

Alan Kilian Spring 2014

Attracting Customers: Design and Construction of an
Inverted Pendulum Mechanical System with a Closed-loop
Control System for use at an industry trade show.

Introduction:

This project is based on past learning as part of my job at the Logic PD Corporation.

The Logic PD Corporation works with other companies to help build products such as home thermostats, portable medical devices and robots. As a Principal Embedded Systems Engineer at the Logic PD Corporation, I work with Logic PD customers to design electrical circuits and software systems to meet the needs of their products.

In order to meet new customers and generate sales, Logic PD attends several industry conferences each year. These conferences include a large area for companies to setup a table and demonstrate their products to potential customers. These conference “Expos” can be very crowded with several hundred companies all attempting to get the attention of conference attendees. Getting the attention of conference attendees can be difficult in this noisy crowded environment. In order to help attract attention to the Logic PD booth, the Vice President of the Sales group asked me if I could gather together some engineers and create a mechanical system that would be visible to conference attendees and would move in such a way to get the attention of these attendees as well as to demonstrate some of the capabilities offered by Logic PD.

After discussing several possibilities with other engineers, we agreed that having an Inverted Pendulum Mechanical System with a Closed-loop Control System demonstration running in our booth would attract their attention. In addition, allowing attendees to download an application to their Android smartphone to control the Inverted Pendulum Mechanical System with a Closed-loop Control System would be a great addition to the Logic PD booth.

My task was to build the Inverted Pendulum Mechanical System with a Closed-loop Control System hardware, software and website. Another developer at Logic PD developed the smartphone application.

The learning I intend to demonstrate is as follows:

- To understand the mechanical principles and processes of an inverted pendulum with a closed-loop control system.
- To calculate theoretical estimates for the electronic components of motor power, motor speed, encoder resolution, encoder rates and processing power required to properly balance an inverted pendulum.
- To select mechanical system components suitable for implementing an Inverted Pendulum Mechanical System with a Closed-loop Control System.
- To select electronic components suitable for implementing an Inverted Pendulum Mechanical System with a Closed-loop Control System.
- To construct an Inverted Pendulum Mechanical System.
- To write software to implement a Closed-Loop Control System.

- To test and tune a working mechanical Inverted Pendulum with a Closed-Loop Control System.

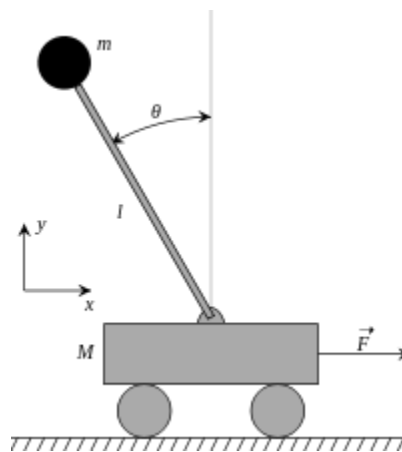
This project is informed by learning in my Depth Criteria and my Extended Studies in Mathematics, Physics and Mechanics. The knowledge gained in the courses of Engineering Fortran, Operating Systems and Data Communications and Distributed Processing allowed me to write the software algorithms required to accomplish the goals of the project. The courses I took in Mechanical Engineering: Systems Dynamics and Control and Analog and Digital Control, as well as my Project #1 Develop a tuning guide for PID control systems allowed me to select, write and test appropriate motion controlling algorithms so that I was able to cause the Inverted Pendulum Mechanical System to move in a way necessary to accomplish the goals of the project. This project is intended as a demonstration of my skills in five specific areas:

Understand the mechanical principles and processes of an inverted pendulum with a closed-loop control system.

An inverted pendulum is a pendulum with its center of mass located above its point of rotation. It differs from a normal pendulum in that it is not statically stable. Any deflection of the pendulum from perfectly vertical causes the pendulum to fall in the direction of the disturbance until it reaches an equilibrium point where the pendulum's center of mass is directly below its pivot point.

Building a closed-loop control system to stabilize an inverted pendulum is a classic problem in both dynamics and control system theory and is often used to test closed loop control systems.

A free body diagram showing the dynamics of an inverted pendulum is as follows:



(Image courtesy of Wikipedia user Krishnavedala)

The dynamics of an inverted pendulum are described in *Modern Control Systems ninth Edition* by Richard Dorf and Robert Bishop pp135-137 and the online resource *Inverted Pendulum Analysis, Design and Implementation* by Khalil Sultan (available at <http://www.engr.usask.ca/classes/EE/480/Inverted%20Pendulum.pdf>)

I reviewed those references for guidance on how to design a closed-loop control system to stabilize both the pendulum angle and the cart position, however these references are mostly theoretical, only analyze the Single Input Single Output (SISO) system where the angle of the pendulum is the only measured value and the force applied to the cart is the only output of the system. My system has four inputs (the angle and rate of change of the angle of the pendulum and the position and the rate of change of the position of the cart) and a single output (The force applied to the cart) making it a more complicated Multi Input Single Output (MISO) dynamic system.

Further, these references and analysis depend on knowing all system parameters such as the transfer function of the motor controller, the transfer function of the motor, masses of all components and estimates of friction of major components. Several of these parameters could be determined through experiment, however, the transfer function of the motor controller and motor would be extremely difficult for me to determine experimentally given the limited laboratory equipment at my disposal.

In addition, implementation of this system using a small embedded microcontroller turns the problem from one of continuous-time into one of discrete time. This introduces additional challenges beyond my knowledge of control systems at this time.

Given the limitations in the knowledge of this system, we decided to implement a Proportional Integral Differential (PID) controller with two measured inputs, two calculated values from those inputs, and a single output.

We will measure the pendulum angle relative to the cart (A) and the cart position along the track (X). We will calculate the rate of change vs. time of each of these inputs ($A\dot{}$ and $X\dot{}$) using the small microcontroller. Two PID control loops will be implemented and their outputs summed to generate a control signal to the motor controller. This output signal will be proportional to the force applied to the cart.

Given the number of successful implementations of this system referenced on the Internet, we believed we could tune the PID coefficients to create a stable control system.

This was a significant risk to the project and could easily have resulted in a system that was not able to perform acceptably. Any “real” project relying on the success of the control system would not have been started without a thorough analysis of the dynamics of the system. For a marketing system given a zero-dollar budget and given volunteer labor, we determined this was the only way we could proceed.

Even though we decided to build and tune the system without a complete theoretical analysis of this system, I will summarize the process that is used to design a closed-loop controller when all system parameters are known.

1. Create a free body diagram showing all the forces on the pendulum and cart.
2. Use the free body diagram to determine the equations of motion of the pendulum and cart.
3. Create linear equations from the equations of motion of the pendulum and cart. Possibly by making assumptions about maximum angle, forces or velocities.
4. Determine the transfer function of the pendulum and cart from the linearized equations of motion. Using the Laplace transform is a common method for this task.
5. The transfer function of the pendulum and cart can be characterized using many stability analysis tools such as a pole-zero plot to gain insight on the necessary features of a controller.
6. Determine the transfer function of the DC motor, pulley and belt drive mechanism using equations of motion and electrical engineering equations.
7. Combine the transfer functions of the drive mechanism and the cart and pendulum to create a transfer function of the complete system.
8. The open-loop (uncontrolled) transfer function can be analyzed using pole-zero, impulse response, step response and root-locus analysis tools to determine a suitable compensation system.
9. A compensation system can be designed using root-locus methods, Bode plots, Nyquist Diagrams or Nichols Charts.
10. The complete closed-loop transfer function can be simulated using tools such as MATLAB to vary the control parameters and verify the control system meets the stability requirements.
11. The closed-loop control system can finally be implemented on the test hardware and additional stability tests made to verify correct performance and requirements are met.

Calculate theoretical estimates for the electronic components required to properly balance an inverted pendulum:

- Motor power
- Motor speed
- Encoder resolution
- Processing speed.

Motor power and Motor speed:

A calculation of the required motor power involves an estimate of the mass of the pendulum+cart+slide+belt combination, an estimate of the acceleration of the pendulum+cart+slide+belt combination required to balance the pendulum, and an

analysis of the motor output angle to cart position mechanical system. We had no estimates for any of these parameters, so we relied on the original plotter designer's expertise in building a functional and successful plotter to provide sufficient motor power to drive the pen and carriage. We will be adding additional mass to the carriage, and are relying on the designers to have provided additional motor power above what they required to drive the pen. This may turn out to be an incorrect assumption, and the project may fail for this reason.

Encoder resolution:

Cart position encoder:

Once again, we will rely on the original plotter designer's cart position encoder design, and assume it is sufficient for our task.

Pendulum position encoder:

Knowing that human can balance an inverted pendulum, and estimating that a human cannot determine the angle of a pendulum within 1 degree, we estimate that any pendulum angle resolution which provides at least a 1 degree angle resolution will be sufficient for this task.

Processing speed:

We estimated the processing power required to run the Inverted Pendulum control system by balancing a similar pendulum by hand and determined that the rate of change of motion of the cart was approximately $\frac{1}{4}$ second. We could easily balance the pendulum by moving the cart by hand and could even balance the pendulum when rapidly blinking our eyes. These experiments demonstrated that using our human body simulated control system we could balance the pendulum by sampling the inputs at less than 10 times-per-second. We then chose to build a control system that could run the control loop at ten times that frequency so that we had sufficient processing power for unanticipated needs. We chose an Atmel ATXMEGA 128 8-bit microprocessor. This processor will be able to easily run two PID control loops at 100Hz.

Select mechanical system components suitable for implementing an Inverted Pendulum Mechanical System with a Closed-loop Control System.

The mechanical components required for this project are:

- A pendulum
- A pivot point for a pendulum
- A cart that can support the pendulum pivot and the pendulum
- A method of measuring the angle of the pendulum relative to the cart
- A method of applying a force to move the cart left and right.
- A method of measuring the position of the cart relative to the linear track
 - Additionally, a method for detecting when the cart approaches the end limits of the track

General mechanical system:

We located a used 36 Inch wide Houston Instruments DMP-60 pen plotter which was being thrown into the recycling area at a local technology company and viewed it as a possible basic mechanical system we could use to build the inverted pendulum model. This system is designed with steel rails holding a small sliding mechanism which holds various colored pens and moves in 1 dimension across a sheet of paper. This mechanism contained a DC motor with an incremental rotary position encoder, a toothed pulley and a long toothed belt driving the cart. A video of this kind of plotter in action is available at: <http://www.youtube.com/watch?v=pMKNRkNPZIw> after viewing this video, we were confident that this mechanism could be used for the motor, pulley, belt and cart.

**Pendulum selection:**

The pendulum should have a low mass to reduce the vertical force on the pendulum pivot point thus making the mechanical system of the pivot point simpler to design.

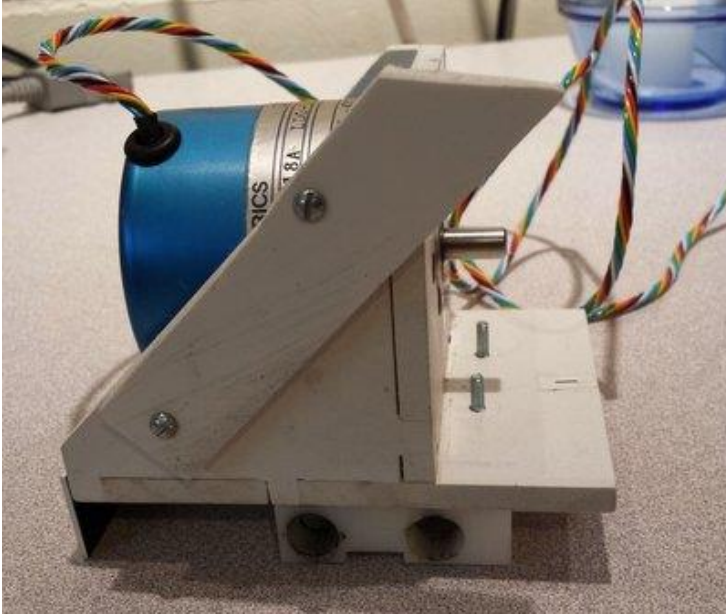
We chose a lightweight $\frac{3}{4}$ Inch square cross section wooden rod for the pendulum. This rod was stiff, light and able to be easily mounted to the pendulum pivot.

Pivot point selection:

We determined that the pendulum could be mounted directly to the shaft of an optical incremental encoder so that the encoder could serve as both the pivot point and the pendulum angle sensor. This encoder has a pair of large bearings supporting the shaft and glass encoder and it was estimated that the mass of the pendulum was very small compared to an estimate of the maximum radial force the encoder could support.

Cart selection:

We designed and built a cart which holds the rotary encoder and mounts to the pen holding sliding mechanism of the plotter. This cart was designed using a 2D CAD software package, was built out of expanded PVC sheet, was cut on a 2D CNC cutter and was assembled using liquid plastic solvent. This produced a lightweight, non-flexible cart for the plotter.



Pendulum angle measurement:

We located an incremental rotary encoder as described in the Pivot point selection above which operated on 5 Volts DC and provided quadrature outputs which are suitable for measuring the angle of the pendulum relative to the cart. The (quadrature) resolution of this encoder is 2000 counts per revolution or 0.18 degrees-per-count. We estimated this would give us enough resolution in pendulum angle to prevent the need for having extremely large proportional gain.



Method for driving the cart:

The plotter contained a DC motor and rotary encoder, toothed pulley and toothed belt for driving the pen holder along the rails, and this mechanism was reused.



Method for determining the position of the cart:

The incremental angle position sensor attached to the DC motor provided quadrature output signals suitable for measuring the position of the cart using the toothed belt ratio of the speed reduction and the tooth-to-tooth distance of the drive belt.

Additional cart position measurement:

The incremental nature of the encoder on the cart positioning motor makes it impossible to determine the absolute position of the cart when the system is powered-on, so two additional sensors were acquired and attached to the plotter. These were short-range infrared proximity detectors. One detector was placed at each extreme end of cart travel and a plate on the cart reflected light back into the sensor when the cart was approximately $\frac{3}{4}$ Inch from the absolute end of travel (the plotter hard stop). These sensors generated a signal to the motion controller software which immediately stopped driving the motor in the direction of travel (to prevent the cart from hitting the hard stop.) This was used both for initializing the cart position when the system was first powered on and well as a safety system in case the cart position was not accurate and the cart was nearly at the end of its travel. This soft-stop is used to stop the motor drive signal and halt the cart motion before it can cause damage to the mechanical system by hitting the end of the rail.

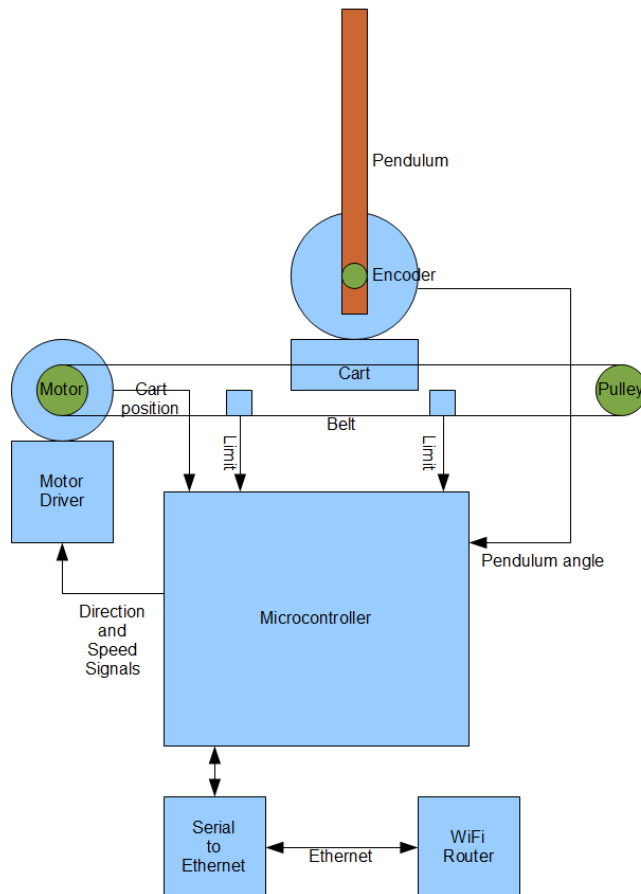


Select electronic components suitable for implementing an Inverted Pendulum Mechanical System with a Closed-loop Control System.

The electrical components required for this project are:

- A method of running control-system software algorithms.
- A method of measuring the angle of the pendulum relative to the cart.
- A method of measuring the position of the cart relative to the linear track.
- A method of applying an electric force to the cart position motor.
- A method of sending cart position and pendulum angle measurements to an Android application.
- A method of receiving control system parameters from an Android application.

General electrical system:



A method of running control-system software algorithms:

We estimated the processing power required to run the Inverted Pendulum control system by balancing a similar pendulum by hand and determined that the rate of change of motion of the cart was approximately $\frac{1}{4}$ second. We could easily balance the pendulum by moving the cart by hand and could even balance the pendulum when rapidly blinking our eyes. These experiments demonstrated that using our human body simulated control system we could balance the pendulum by sampling the inputs at less than 10 times-per-second. We then chose to build a control system that could run the control loop at ten times that frequency so that we had sufficient processing power for unanticipated needs. We chose an Atmel ATXMEGA 128 8-bit microprocessor. This processor will be able to easily run two PID control loops at 100Hz.

A method of measuring the angle of the pendulum relative to the cart:

The pendulum position incremental encoder requires 5 Volts DC and provides a digital quadrature signal on a pair of wires. This interface is compatible with the ATXMEGA 128 8-bit microprocessor's quadrature input peripherals.

A method of measuring the position of the cart relative to the linear track:

The cart position motor's incremental encoder requires 5 Volts DC and provides a digital quadrature signal on a pair of wires. This interface is compatible with the ATXMEGA 128 8-bit microprocessor's quadrature input peripherals.

A method of applying an electric force to the cart position motor:

Using information from the label on the cart positioning motor, we determined the manufacturer was Buehler, the model number was 1.13.048.501, and the motor voltage was 24 VDC. We attempted to retrieve a data sheet on this motor, but it is no longer manufactured, and no data is available. Using the Buehler website, we found a 24 VDC motor with identical length, diameter and a similar part number. We made an assumption that the specifications of this motor would be similar to the motor we had. The only parameter we needed to know was the maximum motor current in a stall. The available motor data sheet stated stall current of 6.5 Amps, so we needed to select a motor driver capable of providing 24 VDC at 6.5 Amps. We chose to use a Pololu brand High-Power Motor Driver Model 24v12 to control the DC cart positioning motor. This controller can provide 24 Volts DC at 12 Amps continuously to brushed DC motor.

A method of sending cart position and pendulum angle measurements to an Android application and a method of receiving control system parameters from an Android application:

Android software applications can use the Android networking services to connect to other devices over a network. We chose to use an Android tablet and to use the tablet's WiFi interface to connect to the Inverted Pendulum system. This required us to develop a method of creating a WiFi Access point and a network endpoint capable of producing data signals compatible with the simple ATXMEGA 128 8-bit microprocessor processor. The processor has no networking interface, and its limited programming capacity would not allow us to write a complex network interface for the processor. We solved this by

adding a commercial WiFi router for home networking use and a device to translate from an Ethernet network interface to TTL Serial UART signals which are compatible with the ATXMEGA 128 8-bit microprocessor. The WiFi router was a common Netgear 4-port 802.11g router. The Ethernet-to-Serial converter was a Texas Instruments Stellaris development kit RDK-S2E shown below.



The Stellaris RDK-S2E device implements a telnet networking server and a TTL Serial UART interface. We connected the Ethernet interface to the WiFi router and the TTL Serial UART Serial interface to the ATXMEGA 128 8-bit microprocessor. With this configuration, the Android application can open a networking connection and can send and receive data from the ATXMEGA128 8-bit microprocessor's UART connection as if it was a network-connected device.

Construct an Inverted Pendulum Mechanical System.

The construction of the Inverted Pendulum Mechanical system was straightforward since it was based on the already functioning pen plotter. We built an additional structure to hold the Pendulum angle encoder as described above and we mounted all other mechanical components underneath the plotter bed.

Write software to implement a Closed-Loop Control System.

The software is composed of two parts:

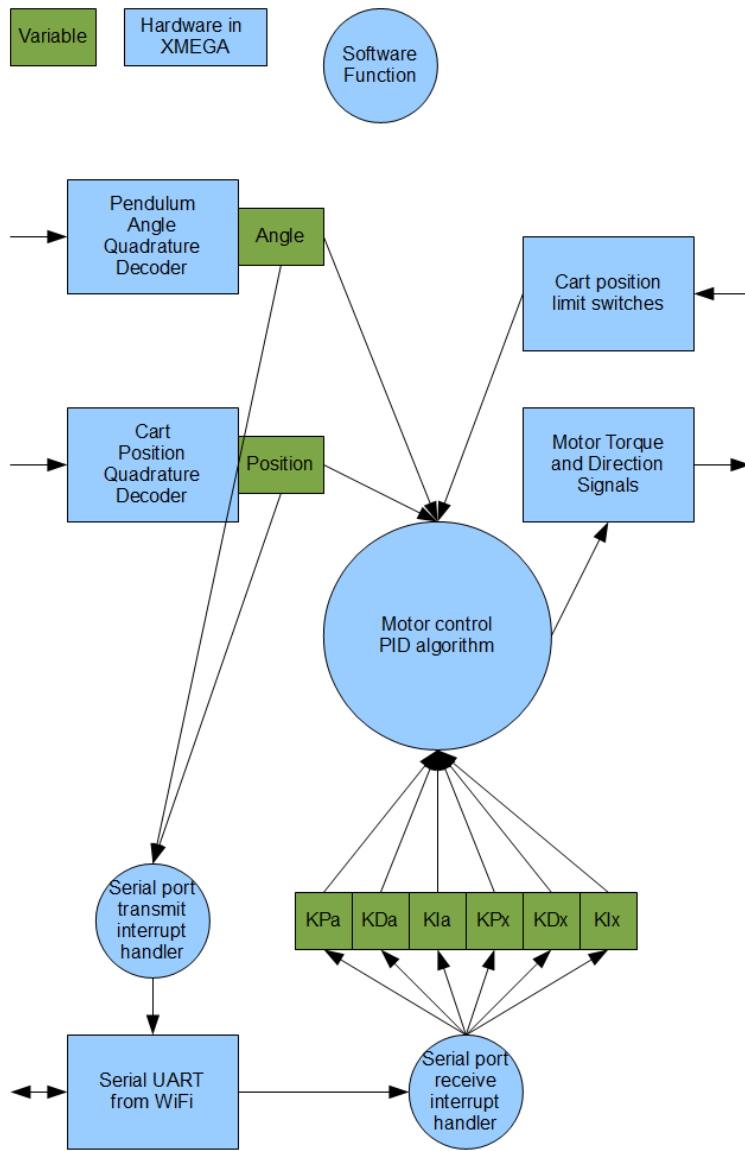
1. Embedded firmware running on the ATXmega 128 which:
 - Reads the information from the Android tablet application.
 - Sends position and angle information to the Android tablet application.
 - Reads information from the angle and position sensors.
 - Reads switch inputs.
 - Runs the control loop.
 - Sends signals to the motor controller.
2. Android Java application running on an Android tables which:
 - Displays graphs showing the pendulum angle and cart position
 - Displays sliders so the user can select motor control coefficients.
 - Displays the state of the control loop as Running, Standing up and halted.

- This application was written by my colleague Tim Anderson at the Logic PD Corporation.

The software running on the XMEGA processor is built on a set of support functions provided by the Atmel Corporation. These functions provide services such as timers, serial input/output, digital input/output, quadrature counting, reset processing and others.

Three additional routines were written for this project:

1. Serial port receive processing. This function reads characters from Android application using the serial port and when a complete command is available, it copies the values for the motor control coefficients into local variables for use by the motor control algorithm.
2. Serial port transmit processing. This function reads local variables containing the state of the motion control algorithm, the pendulum angle and the cart position and sends them to the Android application for display.
3. Motor control algorithm. This is the PID controller used to balance the pendulum.



The motor control algorithm is run 195 times-per-second. This rate is a side-effect of the project upon which this software is based. The previous project had a 19,500 Hz interrupt, and we simply divided the interrupt rate by 100 to get an approximately 200Hz interrupt for the motor controller function. Given the high mass and the low accelerations of the cart, running the control loop 200 times-per-second will make sure the control loop runs faster than the mechanical time constant of the system and will be able to respond to dynamic disturbances.

In normal operation, motor control algorithm reads the quadrature decoder's output for the pendulum angle and the cart position and computes the change in angle and the

change in position as well as the rate of change in angle and rate of change in position. These values are used along with the motor control coefficients to calculate a desired force to be applied to the cart. This value is sent to the Pololu motor controller and on to the cart drive motor which applies the force to the cart through the drive belt.

Normal operation of the Inverted Pendulum can be seen in the video located at: <http://youtu.be/MOb3ZZIolMA>

In this video, the Android tablet can be seen in the lower right of the video displaying the cart position and pendulum angle. The motion control coefficient sliders are not visible in this video.

Several other functions are used intermittently by the controller:

- **Initialization.** Since all the encoders are incremental rather than absolute encoders, when power is applied, they do not represent the actual position of the pendulum and cart. A function detects this power-on condition and drives the cart slowly in an open-loop mode until one of the end-of-travel switches is detected. At this time, the location of the cart is known, and is set to an initial value. The geometry of the pendulum and pendulum stop arms also forces the pendulum against a hard-stop, so its position is also known, and it is initialized to this position.
- **Stand-up.** After initialization, the cart is at one end of travel, and the pendulum is leaning against a hard stop at a large angle from vertical. The pendulum needs to be placed into a vertical position for the control loop to be able to balance the pendulum. To accomplish this, the cart is again moved slowly towards one end of travel, and as it approaches that end of travel, the pendulum rides against a fixed stopper arm and is forced to become more and more vertical. When the pendulum reaches a near vertical position, this is detected and the motion control algorithm is activated and begins balancing the pendulum.
- **Fall detect.** When either the cart or the pendulum exceeds an acceptable position for the motion control algorithm to be able to keep the system stable, the motion control algorithm is halted, and the system is placed into the stand-up mode to position the pendulum upright again.

The operation of fall detection and stand-up can be seen in the video located at: <http://youtu.be/nvfNb7JbDA0>

Test and tune a working mechanical Inverted Pendulum with a Closed-Loop Control System.

I performed a step-by-step experiment changing each control-loop coefficient and recorded the control system performance on a previous instance of the hardware.

These experiments and my analysis are recorded in the following video clips:

- Tuning the angle feedback loop. Pure proportional gain from 10 to 250. Showing more and more oscillatory behavior.
 - $K_a = 10$ $K_{\dot{\theta}} = 0$ http://youtu.be/J_dvs1p19ik
 - $K_a = 50$ $K_{\dot{\theta}} = 0$ <http://youtu.be/KVUZseYmnLw>
 - $K_a = 150$ $K_{\dot{\theta}} = 0$ <http://youtu.be/8bDfa0e-qCA>
 - $K_a = 250$ $K_{\dot{\theta}} = 0$ <http://youtu.be/sXgoIuRVXbo>
- Adding damping to the angle feedback loop. Showing an increase in stability.
 - $K_a = 250$ $K_{\dot{\theta}} = 10$ <http://youtu.be/FAnw8e6-Obw>
 - $K_a = 250$ $K_{\dot{\theta}} = 20$ <http://youtu.be/HT33OHBrd2o>
 - $K_a = 250$ $K_{\dot{\theta}} = 40$ <http://youtu.be/UFaSkNSEgFo>
- Tuning the cart position loop. Pure proportional gain from 10 to 250. Showing more and more oscillatory behavior.
 - $K_x = 3$ $K_{\dot{x}} = 0$ <http://youtu.be/HJDo6fk3Yyc>
 - $K_x = 6$ $K_{\dot{x}} = 0$ http://youtu.be/S_VHxPXBnbM
- Final tuning with this system: (Using negative cart position gain as advised by Dr. Durfee.)
 - $K_a = 250$ $K_{\dot{\theta}} = 40$ $K_x = -4$ $K_{\dot{x}} = 5$
<http://youtu.be/ZAJfMYi3uTA> <http://youtu.be/ZAJfMYi3uTA>

When the second system was created, a tuning analysis was performed similar to the above analysis, and we created a stable Inverted Pendulum system.

Unfortunately, the system was uninteresting as a trade show display. We then experimented with other control loop modifications and ended up with a system we called “Bump”. The “Bump” control system uses the PID control loop as demonstrated above, but with the addition of a “Bump” added to the desired pendulum angle when:

- The pendulum angle error exceeds a set amount.
- The pendulum velocity exceeds a set amount.

This makes the control algorithm less smooth due to the step changes in desired pendulum angle. As the pendulum position or velocity error increases, at some point, it crosses a threshold and the desired angle is changed from zero to some angle slightly off of zero, but still in the correct direction to maintain stability. This causes the carriage to “Bump” out away from the center position. This made for a more interesting display, and (barely) maintained a stable system. We concluded that the stability of a PID controller even with the lack of a complete theoretical stability analysis is sufficient to create a demonstration for a trade show. This feature can be seen by referring to the ABUMP and VBUMP references in the appendix A.

Appendix A:

Source code for the PID controller part of the firmware.

```
// Pin assignments for the 4 channel XMega128A3 board.
//
// cmdUART RX - PC2
// cmdUART TX - PC3
// dbgUART RX - PC6
// dbgUART TX - PC7
//
// PHA4 - PD0
// PHB4 - PD1
// IDX4 - PD2
// ENB4 - PD3
// PHA3 - PD4
// PHB3 - PD5
// IDX3 - PD6
// ENB3 - PD7
//
// PHA2 - PE0
// PHB2 - PE1
// IDX2 - PE2
// ENB2 - PE3
// PHA1 - PE4
// PHB1 - PE5
// IDX1 - PE6
// ENB1 - PE7
//
// PWM1 - PF0
// PWM2 - PF1
// PWM3 - PF2
// PWM4 - PF3
// DIR1 - PF4
// DIR2 - PF5
// DIR3 - PF6
// DIR4 - PF7
//
// PID flag - PA6
// Other flag - PA7
//
// Encoder 1 - Event channel 0, Timer TCC0
// Encoder 2 - Event channel 2, Timer TCDO
// Encoder 3 - Event channel 4, Timer TCEO
// Encoder 4 - Interrupt driven
// All PWM - Timer TCF0
//
// Periodic timer - TCE1

#include <stdio.h>
#include <string.h>

#include "avr_compiler.h"
#include "clksys_driver.h"
#include "TC_driver.h"
#include "qdec_driver.h"
#include "usart_driver.h"
#include "adc_driver.h"
#include "port_driver.h"

/*! \brief Number of lines in the quadrature encoder. */
// Note: I patched the driver to use 65535 as the period so linecount is ignored
uint8_t lineCount = 128; // 30;

volatile uint8_t flag;
volatile bool nlim;
volatile bool plim;
```

```

int plot = 0;

/*! Define that selects the Usart used in example. */
// #define USART USARTC0
#define USART USARTC0
#define DEBUG_USART USARTC1

uint16_t read_encoder(uint16_t channel);
void set_motor_power(long val, uint16_t channel);
void setup_encoder(void);
void setup_pwm(void);
void setup_uart(void);
void setup_debug_uart(void);
void setup_periodic_timer(void);
void setup_limit_switches();
int16_t ADC_Read(ADC_CH_t *CH);
int ADC_Init( void );
void waitForPosition(unsigned int epsilon);
void home();

volatile int32_t position0, position1, potential1 = -1;
volatile double lastposition1 = 0;
volatile uint16_t previous0, previous1;

#define RX_CNT_MAX 32
volatile int rx_pnt = 0;
volatile int rx_pnt_total = 0;
char rx_buf[RX_CNT_MAX];
char rx_buf1[RX_CNT_MAX];
char cmd[RX_CNT_MAX+1];
int command_ready = 0;

void usart_debug_send_byte(uint8_t c) {
    do{
        // Wait until it is possible to put data into TX data register.
        // NOTE: If TXDataRegister never becomes empty this will be a DEADLOCK.
    }while(!USART_IsTXDataRegisterEmpty(&DEBUG_USART));
    USART_PutChar(&DEBUG_USART, c);
}

#if 0
void usart_send_byte(uint8_t c) {
    do{
        // Wait until it is possible to put data into TX data register.
        // NOTE: If TXDataRegister never becomes empty this will be a DEADLOCK.
    }while(!USART_IsTXDataRegisterEmpty(&USART));
    USART_PutChar(&USART, c);
}
#endif

////////// START PRINTF

static int uart_putchar(char c, FILE *stream)
{
    if (c == '\n') uart_putchar('\r', stream);
    usart_debug_send_byte(c);
    return 0;
}

static FILE mystdout = FDEV_SETUP_STREAM(uart_putchar, NULL, _FDEV_SETUP_WRITE);

#if 0
static int uart_putcharE(char c, FILE *stream)
{
    if (c == '\n') uart_putcharE('\r', stream);
    usart_send_byte(c);
    return 0;
}

static FILE mysterr = FDEV_SETUP_STREAM(uart_putcharE, NULL, _FDEV_SETUP_WRITE);
#endif

```

```

//////////////////////////////////// END PRINTF

volatile long time;

#if 0
ISR(USARTC0_RXC_vect)
{
    uint8_t c;
    c = USARTC0.DATA;
}
#endif

ISR(USARTC1_RXC_vect)
{
    uint8_t c;

    c = USARTC1.DATA;
    //fprintf(stderr,"UART_INT [%02x] '%c'\n",c,c);

    if (c == '$') {
        // If '$' then reset pointer and stuff as first character
        rx_pnt = 0;
        // rx_buf[rx_pnt] = '$';
        // rx_pnt++;
    } else {
        // Hyperterminal only puts out carriage return for new line...
        // Ignore line feed
        if (c != 0x0a) {
            rx_buf[rx_pnt] = c;
            // Check for terminator
            if (c == 0x0d) {
                // Overwrite last char with NULL
                rx_buf[rx_pnt]=0x00;
                // Make a working copy
                if(command_ready == 0) strcpy(rx_buf1, rx_buf);
                rx_pnt=0;
                //fprintf(stderr,"Got a CR. %d %s\n",__LINE__,rx_buf1);
                command_ready = 1;
            } else {
                if (rx_pnt < (RX_CNT_MAX-1)) {
                    rx_pnt++;
                    rx_pnt_total++;
                }
            }
        }
    }
}

// servoMode values
#define UNHOMED 0
#define HALTED 1
#define RUNNING 2
#define HOMING 3
#define STANDINGUP 4
volatile int servoMode = UNHOMED;

char * servoModeText() {
    switch(servoMode) {
        case UNHOMED:
            return("Unhomed");
            break;
        case HALTED:
            return("Halted");
            break;
        case RUNNING:
            return("Running");
            break;
        case HOMING:
            return("Homing");
            break;
    }
}

```

```

        case STANDINGUP:
            return("Resetting");
            break;
    }
    return("Unknown servoMode");
}

#define PHOME 205 //230
#define HPOWER 140

unsigned int maxp = 1023;

volatile long desired0, desired1, upright;
volatile double velocity0, velocity1;
volatile double error0, error0dot;
volatile double powerX = 0;
double Xp = 0.0; // -0.4; // -0.25;
double Xd = 0.0;
double Xi = 0.0;
double error0iL = 100; // Integral limit

volatile double Ap = 20.0; //120.0; // 65
volatile double Ad = 0.0; // 20
double Ai = 0.0;
double error1iL = 100; // Integral limit

double Hp = 2.0; // HOMING porportional gain
double Hd = 0.010; // HOMING derivative gain
#define HOMELIMIT 15

double dT = 1.0/195.0; // 195 Hz PID loop time.

int side = 0;

#define ABUMP 18
#define VBUMP 20
#define VBUMP1 40

// Max velocity is around 100 = 10 ips
// To keep momentum low.
#define VMAX 80
#define VMAX1 200
// Max pendulum angle is 4.5 degrees.
#define MAXANGLE 25

#define MAXPENDERROR 200

ISR(TCE1_OVF_vect) // This is our PID controller running at 195Hz
{
    int16_t delta0,delta1;
    static uint16_t current0 = 0;
    static uint16_t current1 = 0;
    static double lastposition0 = 0;
    static double lastVposition0 = 0;

    static double lasterror0 = 0;
    static double lasterror1 = 0;
    double actual0;

    static double error0i = 0;
    long actual1, error1, error1dot;
    static double error1i = 0;
    static int toobigtimes = 0;

    double epsilon0 = 10;
    double epsilon1 = 5;
    static uint32_t running = 0;

    flag = 1;

```

```

time++;

// Get the true linear position into position0
actual0 = read_encoder(1); // Linear
current0 = (uint32_t) actual0;
delta0 = current0 - previous0;
position0 += (int32_t) delta0;
previous0 = actual0;

if((time % 5) == 0) { // About 50 ms
    velocity0 = (position0 - lastVposition0)/5.0;
    lastVposition0 = position0;
}
velocity0 = (position0 - lastposition0);
if(servoMode == RUNNING){
    running++;
    if((running % (195 * 5)) == 0) { // About 5 seconds
        if(side > 100) upright--;
        if(side < -100) upright++;
        fprintf(stderr,"-----> side = %d upright = %ld\n",side,upright);
        side = 0;
    }
} else {
    running = 0;
}

error0 = desired0 - position0;
if(error0 > 0) side++;
else side--;
#if(0)
// Limit the maximum error in cart position.
if(error0 > Maxerror0) error0 = Maxerror0;
if(error0 < -Maxerror0) error0 = -Maxerror0;
#endif

error0dot = (error0 - lasterror0) / dT;

// Do the integral
if(abs(error0) > epsilon0) {
    error0i += (error0 * dT);
    if(error0i > error0iL) error0i = error0iL;
    if(error0i < -error0iL) error0i = -error0iL;
}

#if(1) // Bang-Bang controller outside deadband
// Couple error in cart position into desired pendulum angle.
desired1 = upright;
//desired1 = 0;
//if(error0 > 2000) desired1 = -1 * (ABUMP + (int)((error0-2000)/2000));
//if(error0 < -2000) desired1 = ABUMP - (int)((error0+2000)/2000);

// Let's try no proportional at all
if(error0 > 2000) desired1 = (-1 * ABUMP) + upright;
if(error0 < -2000) desired1 = ABUMP + upright;
//if(error0 > 4000) desired1 = (-1 * ABUMP * 1.5) + upright;
//if(error0 < -4000) desired1 = ( ABUMP * 1.5) + upright;
//if(error0 > 6000) desired1 = (-1 * ABUMP * 2.5) + upright;
//if(error0 < -6000) desired1 = ( ABUMP * 2.5) + upright;

//if(abs(error0) > 2000) { // Only do velocity controls outside the deadband
if(velocity0 > VMAX) desired1 = VBUMP;
if(velocity0 < -VMAX) desired1 = -VBUMP;

//if(velocity0 > VMAX1) desired1 = VBUMP1;
//if(velocity0 < -VMAX1) desired1 = -VBUMP1;
//}

#else // Proportional
#define Ke -0.007
desired1 = (int) (error0*Ke);

```

```

    if(velocity0 > VMAX) desired1 = VBUMP;
    if(velocity0 < -VMAX) desired1 = -VBUMP;
#endif

    // Limit the maximum pendulum angle
    if(desired1 > MAXANGLE) desired1 = MAXANGLE;
    if(desired1 < -MAXANGLE) desired1 = -MAXANGLE;

    // Get the true pendulum angle into position1
    actual1 = read_encoder(2); // Angle
    current1 = (uint32_t) actual1;
    delta1 = current1 - previous1;
    position1 += (int32_t) delta1;
    previous1 = actual1;
    velocity1 = position1 - lastposition1;

    error1 = desired1 - position1;
    error1dot = (error1 - lasterror1) / dT;

    if(servoMode == STANDINGUP){
        // Watch to see if the pendulum is upright enough to start the controller
        if(position0 > 0) { // We are on the right-half of the slide
            if((error1 < -10) & (error1 > -20)) servoMode = RUNNING; // Start the
controller.
        } else { // We are on the left-half of the slide
            if((error1 > 10) & (error1 < 20)) servoMode = RUNNING; // Start the
controller.
        }
    } else if(servoMode == HALTED){
        // Watch to see if the pendulum is upright enough to start the controller
        if(abs(error1) < 20) servoMode = RUNNING; // Start the controller.
    }
    if((servoMode == RUNNING) && (abs(error1) > MAXPENDERROR)) {
        fprintf(stderr,"-----toobigtimes = %d\n",toobigtimes);
        if(toobigtimes++ > 3) {
            toobigtimes = 0;
            set_motor_power(0,1); // Stop the motor
            fprintf(stderr,"Error too large. D=%ld p=%ld e=%ld\n",desired1, position1,
desired1 - position1);
            fprintf(stderr,"actual1 = %ld, current1 = %ld, delta1 = %ld\nposition1 = %ld,
previous1 = %ld\n", (long)actual1, (long)current1, (long)delta1, (long)position1,
(long)previous1);
            fprintf(stderr,"error1 = %ld\n", (long)error1);
            desired0 = 0;
            fprintf(stderr,"Delay 5 sec near 378\n");
            _delay_ms(5000); // Wait for things to settle down
            servoMode = STANDINGUP;
        }
    } else {
        toobigtimes = 0;
    }

    if(servoMode == RUNNING) {
        // Do the integral
        if(abs(error1) > epsilon1) {
            error1i += (error1 * dT);
            if(error1i > error1iL) error1i = error1iL;
            if(error1i < -error1iL) error1i = -error1iL;
        }

        powerX = ((double)error1 * Ap) +
                ((double)error1dot * Ad) +
                ((double)error1i * Ai) +

                ((double)error0 * Xp) +
                ((double)error0dot * Xd) +
                ((double)error0i * Xi);

        set_motor_power((long)powerX,1);
    } else if(servoMode == HOMING) {
        if(error0 < 100) servoMode = STANDINGUP;
    }

```

```

        set_motor_power(((double)error0 * Hp)+((double)error0dot * Hd) ,1); // Pure PD on
cart position
    } else if(servoMode == HALTED) {
        set_motor_power(0,1); // Stop the motor.
    } else if(servoMode == STANDINGUP) {
        if(errorr1 > 0) set_motor_power( HPOWER, 1); // Move right if pendulum is leaning
right
        else
            set_motor_power(-HPOWER, 1); // Move left if pendulum is leaning
left
    }

    lastposition0 = position0;
    lastposition1 = position1;
    lasterror0 = error0;
    lasterror1 = error1;
}

bool anylimithit();
bool neglimithit();
bool poslimithit();

#define MPISIZE 195*5
uint16_t mpI = 0;
uint16_t motorPower[MPISIZE];
double motorPowerAverage;

#define DMAX 10 // Maximum pendulum tilt compensation

void waitForPosition(unsigned int epsilon) {
    while(abs(error0) > epsilon) {
        _delay_ms(10);
    }
}

void
motorPowerPrint() {
    int i;
    double average = 0.0;

    for(i=0;i<(MPISIZE);i++) average += motorPower[i];
    printf("%lf\n",average/(MPISIZE));
}

int main( void )
{
    int16_t i;
    char *param_pnt;
    //long prints = 0;
    long lasttime = 0;
    long nexttime = 0;
    int l;

    // Configure PLL with the 2 MHz RC oscillator as source and
    // multiply by 10 to get 20 MHz PLL clock and enable it. Wait
    // for it to be stable.
    CLKSYS_PLL_Config( OSC_PLLSRC_RC2M_gc, 10 ); // 10=20Mhz 16=32Mhz
    CLKSYS_Enable( OSC_PPLEN_bm );
    do {} while ( CLKSYS_IsReady( OSC_PLLRDY_bm ) == 0 );
    CLKSYS_Main_ClockSource_Select( CLK_SCLKSEL_PLL_gc );
    _delay_ms(100);

    PORTF.DIRSET = PIN4_bm; // Motor direction bit
    PORTF.DIRSET = PIN5_bm; // Motor direction bit
    PORTF.DIRSET = PIN6_bm; // Motor direction bit
    PORTF.DIRSET = PIN7_bm; // Motor direction bit

    PORTE.DIRSET = PIN7_bm; // ENB1
    PORTE.DIRSET = PIN3_bm; // ENB2

    //setup_uart(); // stderr
    setup_debug_uart(); // stdout to the Ethernet gadget

```



```

_delay_ms(10);
flag = 0;

setup_encoder();
setup_pwm();
setup_limit_switches();

setup_periodic_timer();
ADC_Init();
sei();

printf("\nReady! Sleeping for 5 seconds\n");
fprintf(stderr,"\n(stderr) Ready! Sleeping for 5 seconds\n");
_delay_ms(5000);
nlim = 0; plim = 0;
time = 0;
position0 = 0;
//position1 = PHOME; // Sitting on the left (CCW) stop
previous0 = 0;
//previous1 = 0;

PORTE_OUT |= PIN7_bm; // ENB1
PORTE_OUT |= PIN3_bm; // ENB2

TCC0.CNT = 0;
TCDO.CNT = 0;
TCEO.CNT = 0;
position0 = 0;
desired0 = 0;
desired1 = 0;
upright = 0;

maxp = 500; // Limit the maximum motor power while we are homing.

home();
while (1) {
    //fprintf(stderr,"L1 %d\n",__LINE__);
    if (command_ready) {
        //fprintf(stderr,"L2 %d\n", LINE );

        // If buffer is not NULL, split command and parameters
        if ( rx_buf1[0] ) {
            //fprintf(stderr,"L%d\n",__LINE__);
            cmd[0]=0x00;
            rx_buf1[RX_CNT_MAX-1] = 0; // Make sure it's null-terminated.
            l = strlen(rx_buf1);
            //fprintf(stderr,"L%d strlen = %d\n",__LINE__, l);
            if(l > RX_CNT_MAX) l = RX_CNT_MAX-1;
            for (i=0; i<l; i++) {
                if (rx_buf1[i] == ' ') {
                    cmd[i]=0x00;
                    i++;
                    break;
                }
                cmd[i] = rx_buf1[i];
                cmd[i+1] = 0x00;
            }
            //fprintf(stderr,"L%d\n",__LINE__);
            param_pnt = &rx_buf1[i];

            //fprintf(stderr,"[%s] ",cmd);
            //fprintf(stderr,"[%s]\n",param_pnt);

            // Process the command
            // cmd - contains the command field
            // param_pnt - points to parameter start
            //fprintf(stderr,"L%d\n",__LINE__);
            if (strncmp(cmd, "a",1)==0) {
                // put code here
            } else if (strncmp(cmd, "b",1)==0) {
                // put code here
            }
        }
    }
}

```

```

} else if (strncmp(cmd, "h",1)==0) {
    servoMode = UNHOMED;
    home();
} else if (strncmp(cmd, "r",1)==0) {
    fprintf(stderr,"RESET\n");
    Ap = 20;
    Ad = 0;
    servoMode = UNHOMED;
    _delay_ms(100);          // Make sure the control loop gets the state
change notice.
    home();
} else if (strncmp(cmd, "f",1)==0) {
    motorPowerPrint();
} else if (strncmp(cmd, "d",1)==0) {
    printf("D 0,20,50,0,0,0.5\n");          // TODO fill these in.
    fprintf(stderr,"D 0,20,50,0,0,2\n");    // TODO fill these in.
} else if (strncmp(cmd, "m",1)==0) {
    printf("S %s 0,20,50,0,0,0.5\n",servoModeText());
} else if (strncmp(cmd, "p",1)==0) {
    plot = 195*5;
} else if (strncmp(cmd, "Ap",2)==0) {
    double pvalue,dvalue,sum;
    char one[20];
    char two[20];
    char three[20];
    int ret;
    //dvalue = atof(param_pnt);
    ret = sscanf(param_pnt,"%s %s %s",one,two,three);
    if(ret == 3) {
        pvalue = atof(one);
        dvalue = atof(two);
        sum =  atof(three);
        if(sum == (pvalue + dvalue)) {
            //printf("Got an Angle Proportional of %lf\n",dvalue);
            if((pvalue > 0) & (pvalue < 50)) Ap = pvalue;
            if((dvalue >= 0) & (dvalue < 0.5)) Ad = dvalue;
            fprintf(stderr,"----- Ap = %lf Ad = %lf\n",Ap,Ad);
        } else {
            fprintf(stderr,"BAD sum\n");
        }
    }
    } else {
        fprintf(stderr,"--->%s<---\n",param_pnt);
    }
} else if (strncmp(cmd, "Ad",2)==0) {
    double dvalue;
    dvalue = atof(param_pnt);
    //printf("Got an Angle Derivative of %lf\n",dvalue);
    if((dvalue > 0) & (dvalue < 0.5)) Ad = dvalue;
    fprintf(stderr,"----Ad = %lf\n",Ad);
}
command_ready = 0;
//fprintf(stderr,"L%d\n", LINE );
}
//fprintf(stderr,"L%d\n", __LINE__);
}
//fprintf(stderr,"L%d\n", LINE );
if((time-lasttime) > 10) {
    printf("P %ld,%ld,%ld,%ld,%ld\n",
        (long)position0,
        (long)velocity0,
        (long)desired1,
        (long)position1,
        (long)powerX);
#if 0
    fprintf(stderr,"P %ld,%ld,%ld,%ld,%ld\n",
        (long)position0,
        (long)velocity0,
        (long)desired1,
        (long)position1,
        (long)powerX);
#endif
}
#endif

```

```

        lasttime = time;
        nexttime = time + 19;

        //fprintf(stderr,"rx = %d rx_pnt_total = %d\n",rx_pnt,rx_pnt_total);
    }
    _delay_ms(1);
}
}

void home() {
    int p = HPOWER;

    printf("Homing...\n");    // Calibrate the X position

    if(poslimithit()) {      // In positive limit;
        printf("In positive limit. moving negative for a little bit.\n");
        set_motor_power(-p,1); // Move in the positive direction for a little while.
        _delay_ms(100);       // Move motor for 1 second to get out of the limit
    }

    set_motor_power(p,1);    // Move in the positive direction

    while (!poslimithit()); // Wait for negative limit
    printf("At positive limit\n");

    set_motor_power(1,1);
    fprintf(stderr,"Waiting to stop bouncing\n");
    _delay_ms(5000);        // Wait for the pendulum to stop bouncing off the hard-
stop
    fprintf(stderr,"Zeroing angle\n");
    position0 = 30350;      // Home against the negative limit.
    position1 = PHOME;      // Sitting on the left (CCW) stop set encoder counter to
a value of PHOME
    previous1 = PHOME;
    TCDO.CNT = PHOME;
    _delay_ms(100);        // Wait for the control loop to set previous0

    printf("Homed.\n");
    servoMode = STANDINGUP;
}

bool anylimithit() {
    // Returns 1 if either limit switch is hit
    return((PORTD.IN&0x30) != 0x30);
}

bool neglimithit() {
    // Returns 1 if negative limit switch is hit
    return((PORTD.IN&0x20) != 0x20);
}

bool poslimithit() {
    // Returns 1 if positive limit switch is hit
    return((PORTD.IN&0x10) != 0x10);
}

uint16_t read_encoder(uint16_t channel) {
    uint16_t ret_val;

    switch (channel) {
        case 1:
            ret_val = TCC0.CNT;
            break;
        case 2:
            ret_val = TCDO.CNT;
            break;
        case 3:
            ret_val = TCE0.CNT;
            break;
        default:

```

```

        ret_val = 0;
    }
    return ret_val;
}

void set_motor_power(long val, uint16_t channel)
{
    uint16_t new_val;

    new_val = abs(val);
    motorPower[mpi++] = new_val;
    if(mpi >= MPISIZE) {
        //printf("Reset mpi\n");
        mpi = 0;
    }
    if (abs(val) > maxp) new_val = maxp; // Limit to less than 10 bits since I have a 33
    Volt supply and a 24 Volt motor
    //if(new_val != 0) printf("set_motor_power %d\n",new_val);
    switch (channel) {
        case 1:
            if (val < 0) {
                PORTF_OUT &= ~PIN4_bm;
                if((PORTD.IN&0x20) != 0x20) new_val = 0; // In negative limit don't
move -
            } else {
                PORTF_OUT |= PIN4_bm;
                if((PORTD.IN&0x10) != 0x10) new_val = 0; // In positive limit don't
move +
            }
            // Output new compare value.
            TC_SetCompareA( &TCF0, new_val);
            break;
        case 2:
            if (val < 0) {
                PORTF_OUT &= ~PIN5_bm;
            } else {
                PORTF_OUT |= PIN5_bm;
            }
            TC_SetCompareB( &TCF0, new_val);
            break;
        case 3:
            if (val < 0) {
                PORTF_OUT &= ~PIN6_bm;
            } else {
                PORTF_OUT |= PIN6_bm;
            }
            TC_SetCompareC( &TCF0, new_val);
            break;
        case 4:
            if (val < 0) {
                PORTF_OUT &= ~PIN7_bm;
            } else {
                PORTF_OUT |= PIN7_bm;
            }
            TC_SetCompareD( &TCF0, new_val);
            break;
        default:
            break;
    }
}

void setup_limit_switches() {
    PORT_ConfigurePins( &PORTD,
        0x30, // negative and positive limit switches ACTIVE LOW.
        false, //
        false, //
        PORT_OPC_TOTEM_gc, //
        PORT_ISC_FALLING_gc //
    );
    PORT_SetPinsAsInput ( &PORTD, 0x30 );
}

```

```

PORT_ConfigureInterrupt0 ( &PORTD, PORT_INT0LVL_MED_gc, 0x30 );

PORT_ConfigurePins( &PORTD,
    0x10, // negative and positive limit switches ACTIVE LOW.
    false, //
    false, //
    PORT_OPC_TOTEM_gc, //
    PORT_ISC_FALLING_gc //
);
PORT_SetPinsAsInput ( &PORTD, 0x10 );
PORT_ConfigureInterrupt1 ( &PORTD, PORT_INT0LVL_MED_gc, 0x10 );
PMIC_CTRL |= PMIC_MEDLVLEN_bm;
}

ISR(PORTD_INT0_vect) {
    if(PORTD.IN & 0x10) {
        if(!(PORTF_OUT & PIN4_bm)) set_motor_power(0,1);
        nlim = 1; plim = 0;
        //printf("Neg interrupt\n");
    }
    if(PORTD.IN & 0x20) {
        if(PORTF_OUT & PIN4_bm) set_motor_power(0,1);
        plim = 1; nlim = 0;
        //printf("Pos interrupt\n");
    }
}

ISR(PORTD_INT1_vect) {
    printf("Positive limit\n");
}

void setup_encoder(void) {
    // Setup PORT? with pin ? as input for QDPH0, dont invert IO pins.
    //
    // Setup event channel ?, pin ? on PORT? as input, don't enable index.
    // if index used then state 00 is set as the index reset state.
/*
* \param qPort      The port to use.
* \param qPin       The first input pin (QDPH0) to use (0 - 5/6).
* \param invIO      True if IO pins should be inverted.
*
* \param qEvMux     Which event channel to use. Only 0, 2 and 4 is available.
* \param qPinInput  The pin input of QDPH0 to the EVSYS.CHMUX .
* \param useIndex   True if an optional Index pin is used.
* \param qIndexState In which state the index signal will trigger.
*
* \param qTimer     The timer to use for QDEC.
* \param qEventChannel The event channel to listen to.
* \param lineCount  The number of lines in the quadrature encoder.
*/

    // Setup TCC0 with PORTE-Pin4 as input to Event channel 0
    QDEC_Total_Setup(&PORTE, // PORT_t * qPort
        4, // uint8_t qPin
        false, // bool invIO
        0, // uint8_t qEvMux
        EVSYS_CHMUX_PORTE_PIN4_gc, // EVSYS_CHMUX_t qPinInput
        false, // bool useIndex
        EVSYS_QDIRM_00_gc, // EVSYS_QDIRM_t qIndexState
        &TCC0, // TC0_t * qTimer
        TC_EVSEL_CH0_gc, // TC_EVSEL_t qEventChannel
        0); // uint8_t lineCount

    // Setup TCD0 with PORTE-Pin0 as input to Event channel 2
    QDEC_Total_Setup(&PORTE, // PORT_t * qPort
        0, // uint8_t qPin
        false, // bool invIO
        2, // uint8_t qEvMux
        EVSYS_CHMUX_PORTE_PIN0_gc, // EVSYS_CHMUX_t qPinInput
        false, // bool useIndex
        EVSYS_QDIRM_00_gc, // EVSYS_QDIRM_t qIndexState

```

```

        &TC0,                // TC0_t * qTimer
        TC_EVSEL_CH2_gc,    // TC_EVSEL_t qEventChannel
        0);                // uint8_t lineCount
#endif
// Setup TCE0 with PORTD-Pin4 as input to Event channel 4
QDEC_Total_Setup(&PORTD, // PORT_t * qPort
                4,        // uint8_t qPin
                false,    // bool invIO
                4,        // uint8_t qEvMux
                EVSYS_CHMUX_PORTD_PIN4_gc, // EVSYS_CHMUX_t qPinInput
                false,    // bool useIndex
                EVSYS_QDIRM_00_gc,        // EVSYS_QDIRM_t qIndexState
                &TCE0,                // TC0_t * qTimer
                TC_EVSEL_CH4_gc,        // TC_EVSEL_t qEventChannel
                0);                // uint8_t lineCount
}

void setup_pwm(void)
{
    // Enable output on PC0.
    PORTF.DIR |= 0x0f;
    // Use 10 bits for the TC period
    TC_SetPeriod( &TCF0, 0x03FF );
    // Configure the TC for single slope mode.
    TC0_ConfigWGM( &TCF0, TC_WGMODE_SS_gc );
    // Enable Compare channel A,B,C,D.
    TC0_EnableCCChannels( &TCF0, TC0_CCAEN_bm | TC0_CCBEN_bm | TC0_CCCEN_bm |
TC0_CC DEN_bm );
    // Start timer by selecting a clock source.
    TC0_ConfigClockSource( &TCF0, TC_CLKSEL_DIV1_gc ); // 19.5312 KHz
    // TC0_ConfigClockSource( &TCF0, TC_CLKSEL_DIV2_gc ); // 9.7656 KHz
    // TC0_ConfigClockSource( &TCF0, TC_CLKSEL_DIV4_gc ); // 4.8828 KHz
}

void setup_periodic_timer(void)
{
    /* Set period/TOP value. */
    TC_SetPeriod( &TCE1, 100 ); // 10=1953 100 = 195.3 1000=19.5 Hz
    /* Select clock source. */
    TC1_ConfigClockSource( &TCE1, TC_CLKSEL_DIV1024_gc );
    /* Enable Overflow interrupt. */
    TCE1.INTCTRLA = (uint8_t) TC_OVFINTLVL_HI_gc;
    PMIC.CTRL |= PMIC_HILVLEN_bm;
}

#if 0
void setup_uart(void)
{
    // PIN3 (TXD0) as output.
    PORTC.DIRSET = PIN3_bm;
    // PF2 (RXD0) as input.
    PORTC.DIRCLR = PIN2_bm;
    // USARTF0, 8 Data bits, No Parity, 1 Stop bit.
    USARTC0.CTRLA = (uint8_t) (USART_CHSIZE_8BIT_gc | USART_PMODE_DISABLED_gc);
    // See: http://www.avrfreaks.net/index.php?name=PNphpBB2&file=printview&t=66741&start=0
    // Baud Rate variables
    // (2067, -4) = 9600 (at 20Mhz fper)
    // (1026, -4) = 19200
    // (1261, -7) = 115200
    uint16_t bsel = 1261;
    int bscale = -7;
    // Set Baud Rate
    USARTC0.BAUDCTRLB = ((unsigned char)(bscale & 0x0F) << 4) | ((unsigned char)(bsel >>
8) & 0x0F);
    USARTC0.BAUDCTRLA = (unsigned char)(bsel & 0xFF);
    _delay_ms(10);
    // Enable both RX and TX.
    USARTC0.CTRLB = (uint8_t) (USART_RXEN_bm | USART_TXEN_bm);
}

```

```

    // Enable RXC interrupt.
    USARTC0.CTRLA = (uint8_t)USART_RXCINTLVL_LO_gc;
    PMIC.CTRL |= PMIC_LOLVLEN_bm;
    stderr = &mysterr; //printf
}
#endif

void setup_debug_uart(void)
{
    // (TXD0) as output.
    PORTC.DIRSET = PIN7_bm;
    // (RXD0) as input.
    PORTC.DIRCLR = PIN6_bm;
    // 8 Data bits, No Parity, 1 Stop bit.
    USARTC1.CTRLA = (uint8_t)(USART_CHSIZE_8BIT_gc | USART_PMODE_DISABLED_gc);
    // See: http://www.avrfreaks.net/index.php?name=PNphpBB2&file=printview&t=66741&start=0
    // Baud Rate variables
    // (2067, -4) = 9600 (at 20Mhz fper)
    // (1026, -4) = 19200
    // (1261, -7) = 115200
    int bsel = 1261;
    int bscale = -7;
    // Set Baud Rate
    USARTC1.BAUDCTRLB = ((unsigned char)(bscale & 0x0F) << 4) | ((unsigned char)(bsel >>
8) & 0x0F);
    USARTC1.BAUDCTRLA = (unsigned char)(bsel & 0xFF);
    _delay_ms(10);
    // Enable both RX and TX.
    USARTC1.CTRLB = (uint8_t)(USART_RXEN_bm | USART_TXEN_bm);
    // Enable RXC interrupt.
    USARTC1.CTRLA = (uint8_t)USART_RXCINTLVL_LO_gc;
    PMIC.CTRL |= PMIC_LOLVLEN_bm;
    stdout = &mystdout; //printf
}

```

Appendix B:

Source code for the Android Graphical interface.

```
package com.logicpd.android.invertedpendulum;

import java.util.Observable;
import java.util.Observer;
import com.androidplot.xy.XYPlot;
import com.logicpd.android.invertedpendulum.Common.GainType;
import android.app.Activity;
import android.content.BroadcastReceiver;
import android.content.Context;
import android.content.Intent;
import android.content.IntentFilter;
import android.graphics.Color;
import android.os.Bundle;
import android.os.SystemClock;
import android.util.Log;
import android.view.View;
import android.view.View.OnClickListener;
import android.widget.Button;
import android.widget.LinearLayout;
import android.widget.SeekBar;
import android.widget.TextView;
import android.widget.SeekBar.OnSeekBarChangeListener;

public class InvertedPendulumActivity extends Activity
{
    // Network Service
    NetworkService networkService = null;

    // UI Elements
    private TextView proportionalGainTextView;
    private TextView derivativeGainTextView;

    private TextView proportionalGainValueTextView;
    private TextView derivativeGainValueTextView;

    private SeekBar proportionalGainSeekBar;
    private SeekBar derivativeGainSeekBar;

    private SeekBar linearPositionSeekBar;

    private TextView statusValueTextView;

    private Button resetButton;

    // Graph Elements
    Graph graph;

    private float Fps;
    private int AverageTime;

    private TextView fpsTextView;
    private TextView averageTimeTextView;

    private class GraphUpdater implements Observer
    {
        Graph graph;
        XYPlot xyPlot;
        int FrameNumber;
        long StartTime;

        public GraphUpdater(Graph pendulumGraph)
        {
            graph = pendulumGraph;
            xyPlot = (XYPlot)graph.graphView;
            Reset();
        }
    }
}
```



```

    }
    public void Reset(){
        FrameNumber = 0;
        StartTime = 0L;
        Fps = 0.0f;
        AverageTime = 0;
    }

    @Override
    public void update(Observable o, Object arg)
    {
        if (Common.SHOW_FRAMERATE)
        {
            if (StartTime == 0)
            {
                StartTime = SystemClock.elapsedRealtime();
            }
            else
            {
                long NowTime = SystemClock.elapsedRealtime();
                FrameNumber++;
                long TotalTime = (NowTime - StartTime);
                Fps = ((float) FrameNumber * 1000) / ((float) TotalTime);
                AverageTime = (int) (TotalTime / FrameNumber);

                if ((FrameNumber & 7) == 0)
                {
                    runOnUiThread(FPSUpdaterRunnable);
                }
            }
        }
    }
}

private GraphUpdater graphUpdater;

public Runnable FPSUpdaterRunnable = new Runnable()
{
    public void run()
    {
        fpsTextView.setText(String.format(getString(R.string.fps) + " %3.1f", Fps));
        averageTimeTextView.setText(getString(R.string.avgTime) + " " +
Integer.toString(AverageTime));
    }
};

// Receiver for incoming network packet notification to update the GUI slider value
private BroadcastReceiver receiver = new BroadcastReceiver()
{
    @Override
    public void onReceive(Context context, Intent intent)
    {
        String action = intent.getAction();
        if (action.equalsIgnoreCase(Common.ACTION_LINEAR_POSITION_RECEIVED))
        {
            int linearPosition = intent.getIntExtra(Common.EXTRA_LINEAR_POSITION, -
1);
linearPositionSeekBar.setProgress(Common.ScaleCartPosition(linearPosition));
        }
        else if (action.equalsIgnoreCase(Common.ACTION_STATUS_RECEIVED))
        {
            String status = intent.getStringExtra(Common.EXTRA_STATUS_VALUE);
            if ((status != null) && (status.length() > 0))
            {
                statusValueTextView.setText(status);

                if (status.equalsIgnoreCase("Running"))
                {
                    statusValueTextView.setTextColor(Color.GREEN);
                }
            }
        }
    }
};

```

```

        else if
(status.equalsIgnoreCase(getString(R.string.disconnectedStatusValue)))
        {
            statusValueTextView.setTextColor(Color.RED);
        }
        else
        {
            statusValueTextView.setTextColor(Color.YELLOW);
        }
    }
}
else if (action.equalsIgnoreCase(Common.ACTION_DEFAULT_DATA_RECEIVED))
{
    ResetGainSeekBarsToDefaults();
}
}
};

@Override
public void onCreate(Bundle savedInstanceState)
{
    super.onCreate(savedInstanceState);

    setContentView(R.layout.main);

    Common.ActivityContext = this;

    proportionalGainTextView = (TextView)findViewById(R.id.proportionalGainTextView);
    derivativeGainTextView = (TextView)findViewById(R.id.derivativeGainTextView);

    proportionalGainValueTextView =
(TextView)findViewById(R.id.proportionalGainValueTextView);
    derivativeGainValueTextView =
(TextView)findViewById(R.id.derivativeGainValueTextView);

    proportionalGainSeekBar = (SeekBar)findViewById(R.id.proportionalGainSeekBar);
    derivativeGainSeekBar = (SeekBar)findViewById(R.id.derivativeGainSeekBar);

    proportionalGainSeekBar.setMax(100);
    derivativeGainSeekBar.setMax(100);

    linearPositionSeekBar = (SeekBar)findViewById(R.id.linearPositionSeekBar);

    statusValueTextView = (TextView)findViewById(R.id.statusValueTextView);
    statusValueTextView.setTextColor(Color.RED);

    resetButton = (Button)findViewById(R.id.resetButton);

    resetButton.setOnClickListener(new OnClickListener()
    {
        public void onClick(View v)
        {
            Intent resetIntent = new Intent();
            resetIntent.setAction(Common.ACTION_SEND_RESET);
            sendBroadcast(resetIntent);

            ResetGainSeekBarsToDefaults();
        }
    });

    OnSeekBarChangeListener seekBarListener = new OnSeekBarChangeListener()
    {
        @Override
        public void onProgressChanged(SeekBar seekBar, int progress, boolean
fromUser)
        {
            if (seekBar == proportionalGainSeekBar)
            {
                // Scale the value
                double gain = ConvertSeekBarToGain(GainType.PROPORTIONAL_GAIN,
progress);

```

```

        Common.ProportionalGainActual = gain;
        proportionalGainValueTextView.setText(String.format("%.2f", gain));
    }
    else if (seekBar == derivativeGainSeekBar)
    {
        double gain = ConvertSeekBarToGain(GainType.DERIVATIVE_GAIN,
progress);
        Common.DerivativeGainActual = gain;
        derivativeGainValueTextView.setText(String.format("%.2f", gain));
    }
}

@Override
public void onStartTrackingTouch(SeekBar seekBar)
{
}

@Override
public void onStopTrackingTouch(SeekBar seekBar)
{
}
};

// Setup change listeners for seek bars
proportionalGainSeekBar.setOnSeekBarChangeListener(seekBarListener);
derivativeGainSeekBar.setOnSeekBarChangeListener(seekBarListener);

ResetGainSeekBarsToDefaults();

linearPositionSeekBar.setProgress(50);

LinearLayout rootlayout = (LinearLayout) findViewById(R.id.rootLinearLayout);

// Setup the Graph
graph = new Graph();

if (graph.graphView != null)
{
    try
    {
        rootlayout.addView(graph.graphView);
    }
    catch (Exception e)
    {
        Log.e("InvertedPendulumActivity", "Unable to create graph", e);
    }
}

fpsTextView = (TextView) findViewById(R.id.fpsTextView);
averageTimeTextView = (TextView) findViewById(R.id.averageTimeTextView);
graphUpdater = new GraphUpdater(graph);

if (!Common.SHOW_FRAMERATE)
{
    fpsTextView.setText("");
    averageTimeTextView.setText("");
}
}

private void ResetGainSeekBarsToDefaults()
{
    // Set to default values. Try setting to min and max so it is guaranteed to
    // update the label at least once when we set
    // it to the default. Otherwise if the value doesn't change, the callback won't
    // happen and the label won't be correct.

    proportionalGainSeekBar.setProgress(ConvertGainToProgressBar(GainType.PROPORTIONAL_GAIN,
Common.ProportionalGainMin));

```

```

derivativeGainSeekBar.setProgress(ConvertGainToProgressBar(GainType.DERIVATIVE_GAIN,
Common.DerivativeGainMin));

proportionalGainSeekBar.setProgress(ConvertGainToProgressBar(GainType.PROPORTIONAL_GAIN,
Common.ProportionalGainMax));

derivativeGainSeekBar.setProgress(ConvertGainToProgressBar(GainType.DERIVATIVE_GAIN,
Common.DerivativeGainMax));

proportionalGainSeekBar.setProgress(ConvertGainToProgressBar(GainType.PROPORTIONAL_GAIN,
Common.ProportionalGainDefault));

derivativeGainSeekBar.setProgress(ConvertGainToProgressBar(GainType.DERIVATIVE_GAIN,
Common.DerivativeGainDefault));
}

private int ConvertGainToProgressBar(GainType gainType, double gain)
{
    int progress = 0;

    if (gainType == GainType.PROPORTIONAL_GAIN)
    {
        progress = (int)((gain - Common.ProportionalGainMin) /
(Common.ProportionalGainMax - Common.ProportionalGainMin) * 100);
    }
    else if (gainType == GainType.DERIVATIVE_GAIN)
    {
        progress = (int)((gain - Common.DerivativeGainMin) /
(Common.DerivativeGainMax - Common.DerivativeGainMin) * 100);
    }

    return progress;
}

private double ConvertSeekBarToGain(GainType gainType, int progress)
{
    double gain = 0;

    if (gainType == GainType.PROPORTIONAL_GAIN)
    {
        gain = (((double)progress / 100) * (double)(Common.ProportionalGainMax -
Common.ProportionalGainMin)) + Common.ProportionalGainMin;
    }
    else if (gainType == GainType.DERIVATIVE_GAIN)
    {
        gain = (((double)progress / 100) * (double)(Common.DerivativeGainMax -
Common.DerivativeGainMin)) + Common.DerivativeGainMin;
    }

    return gain;
}

// Register for notification of incoming network packets when active
@Override
protected void onResume()
{
    // Register the Activity for events it cares about
    IntentFilter filter = new IntentFilter();
    filter.addAction(Common.ACTION_LINEAR_POSITION_RECEIVED);
    filter.addAction(Common.ACTION_STATUS_RECEIVED);
    filter.addAction(Common.ACTION_DEFAULT_DATA_RECEIVED);
    registerReceiver(receiver, filter);

    // Register the graph for updates from the network service
    IntentFilter graphfilter = new IntentFilter();
    graphfilter.addAction(Common.ACTION_GRAPH_DATA_RECEIVED);
    registerReceiver(graph.GraphBroadcastReceiver, graphfilter);

    networkService = new NetworkService();
    networkService.AddObserver(graphUpdater);
}

```

```
graphUpdater.Reset();
    super.onResume();
}

// Unregister for notification of incoming network packets when inactive
@Override
protected void onPause()
{
    unregisterReceiver(receiver);
    unregisterReceiver(graph.GraphBroadcastReceiver);

    networkService.Stop();

    networkService.RemoveObserver(graphUpdater);

    super.onPause();
}
}
```