CSA Electromagnetic Datasheet CSA_EMCV 1.50

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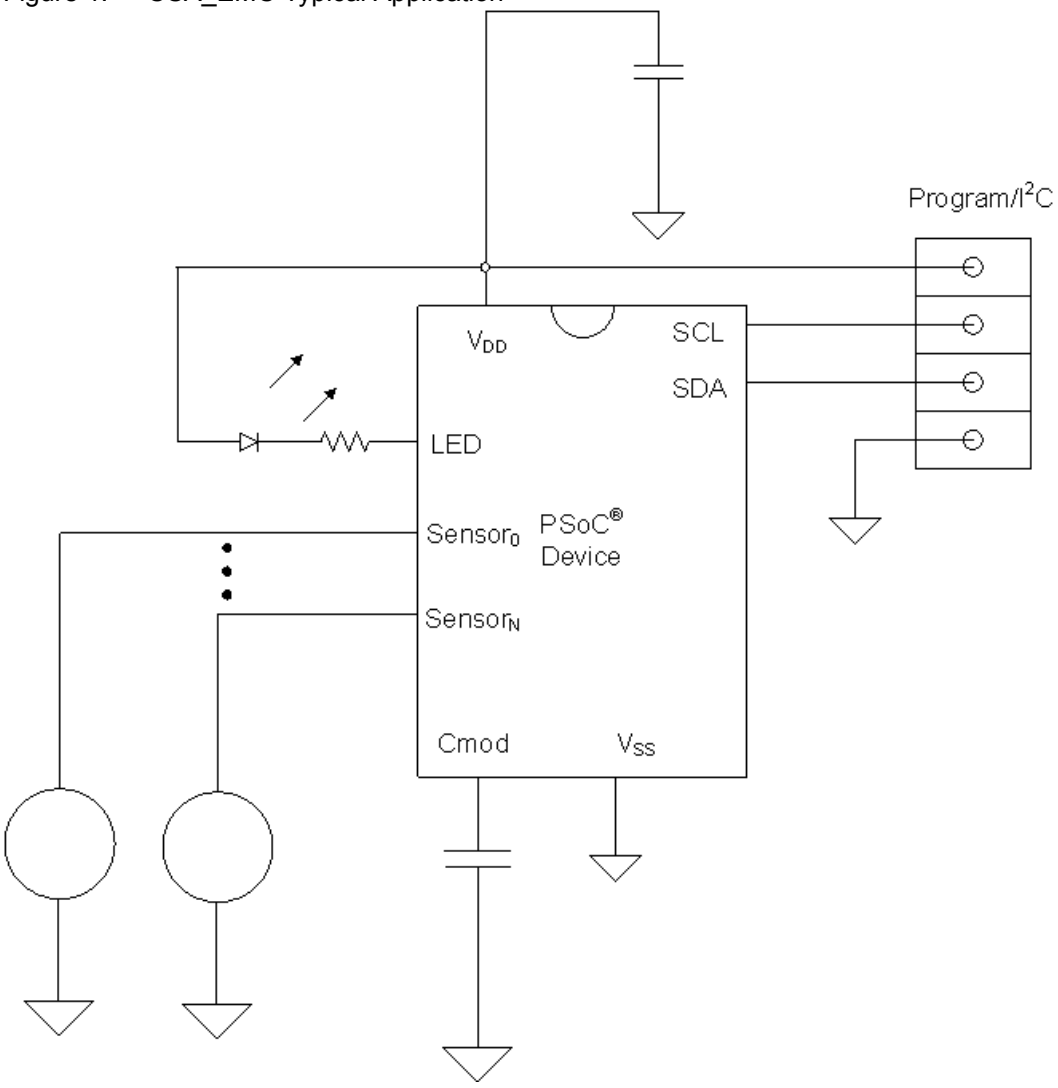
Resources	PSoC® Blocks				API Memory (Bytes) Typical		Pins (per External I/O)
	I²C/SPI	CapSense®	Comparator	Timer	Flash	RAM	
CY8C20x34, CY8C20x24, CY8C20x66, CY8C20x36, CY8C20336AN, CY8C20436AN, CY8C20636AN, CY8C20xx6AS, CY8C20x46, CY8C20x96, CYONSFN2053, CYONSFN2061, CYONSFN2151, CYONSFN2161, CYONSFN2162, CYRF89435, CY8C20065	–	1	1	–	1930	90	1

Features and Overview

- Scan 1 to 28 capacitive sensors
- Scan capacitive sliders with 2 to 28 elements
- Slider physical resolution doubling using diplexing
- Slider interpolated resolution up to 1 part in 65535
- Generate touchpad using multiple slider sensors
- Adjustable sensor sensitivity, detection threshold, and sampling rate
- Guided sensor and pin assignments using the CSA_EMC Wizard
- Integrated baseline update algorithm for handling temperature changes
- Compensate for environmental and physical sensor variations

The CapSense® Successive Approximation Electromagnetic Compatibility (CSA_EMC) User Module implements an array of capacitive touch sensors using switched capacitor circuitry, an analog multiplexer, digital counting functions, and high level software routines to compensate for environmental and physical sensor variations. The sensor array can consist of combinations of independent sensors, sliding sensors, and touchpads implemented as a pair of orthogonal sliding sensors. High level software routines accommodate slider diplexing. Slider diplexing allows a single pin to measure two electrical sensors in two different physical locations. Diplexing provides resolution enhancement of the slider without the cost of an additional I/O.

Figure 1. CSA_EMC Typical Application



Quick Start

1. Select and place user modules that require dedicated pins (such as I^2C or LCD), and assign ports and pins.
2. Select and place the CSA_EMC User Module.
3. Right-click the CSA_EMC User Module to access the CSA_EMC Wizard.
4. Set button sensor count, slider configuration, and pin assignments and associations.
5. Set pins and global user module parameters.
6. Generate the application and switch to Application Editor.
7. Adapt sample code to implement buttons, sliders, or touch pad.

Functional Description

The capacitive sensor consists of physical, electrical, and software components.

Each sensor measured by the CSA_EMC User Module is a capacitor with one side grounded and the other side connected to a PSoC pin. The presence of the conductive object increases the capacitance of the sensor to ground. This capacitance change controls sensor activation.

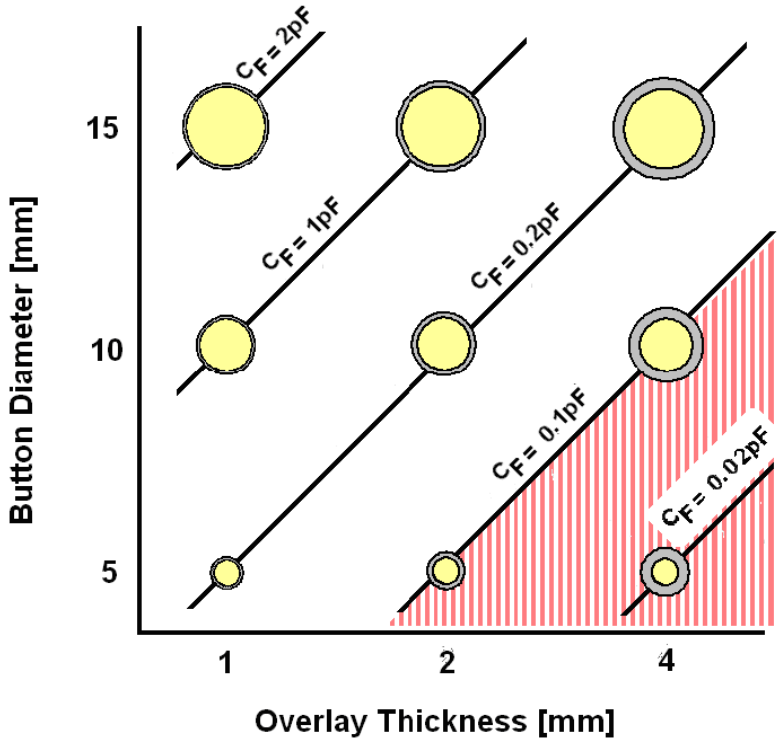
Application Information

This section discusses how to design a capacitive sensing system using the CSA_EMC User Module. It assumes the PSoC device is powered by Vdd = 2.7V to 5.0V, and that the C_{mod} is an X7R-type capacitor.

1. **Button Size**: Use the plot shown in Figure 2 to select a button size that produces the correct level of finger capacitance for a given overlay thickness. The minimum finger capacitance, C_F, is 0.1 pF, but 0.2 pF is recommended for the additional design margin it offers. The clearance between the button and ground fill is equal to the overlay thickness.

   If the board design combined with the overlay does not meet the minimum requirement for Finger Capacitance, use a thinner overlay or increase the size of the sensor.

Figure 2. Button Diameter vs. Overlay Thickness



Example: The plastic overlay is 2 mm thick. The design goal is C_F = 0.2 pF. Figure 2 shows that the button diameter needs to be 10 mm, with 2 mm of clearance between sensor pad and the ground fill.

2. **CP Within 5 to 50 pF**: Check the range of C_P that is monitored by the CSA_EMC User Module. Estimate the capacitive loading on each PSoC pin using the rule of thumb that trace capacitance contributes about 2 pF/inch on a 63 mil-thick 2-layer board with 8mil traces.

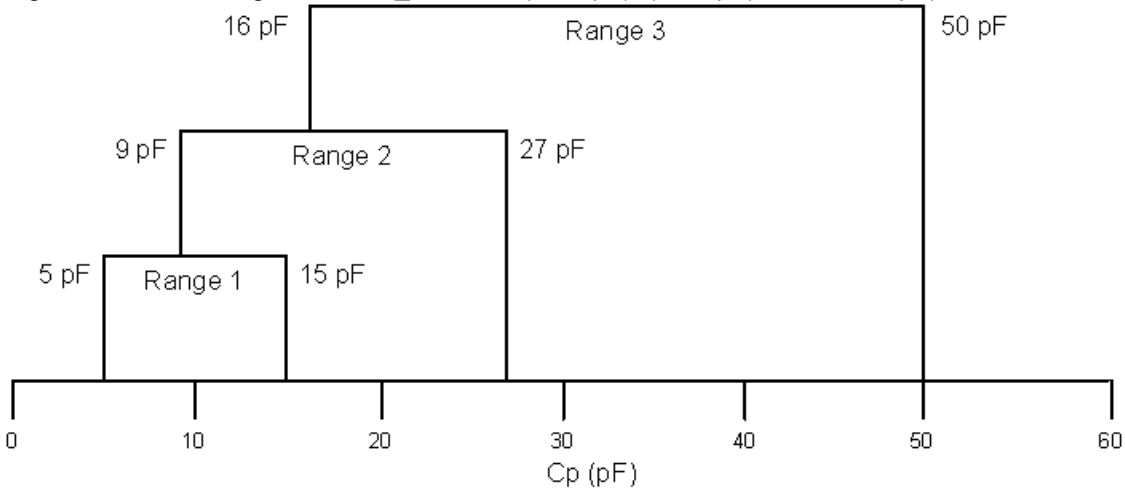
   If every sensor does not fit in the C_P range of 5 pF to 50 pF, move the sensor pad closer to the PSoC device, or consider using another CapSense method, such as CSD. Any trace longer than 24" will exceed the 50 pF limit.

   Example: The system has 12 touch sensors. The distance from the sensor pad to the PSoC pin is less than 4" for all sensors. The C_P for these sensors range from 9 pF to 18 pF for the bare PCB. Taking into account the packaging effect of the PSoC device (add 3 pF), the total loading on the PSoC pins range from 12 pF to 21 pF, which easily fits in the C_P limits of 5-50 pF.

3. **CP Range**: Finger Sensitivity and Conversion Time are specified over one of the ranges of C_P shown in Figure 3. The ranges are 5-15 pF, 9-27 pF, and 16-50 pF.

   Find the range which best fits the C_P values found in Step 1.

Figure 3. The Ranges for CSA_EMC are (5-15 pF), (9-27 pF), and 16-50 pF).



   Example: The total loading on the PSoC pins range from 12 pF to 21 pF. The C_P range that best fits these values is Range 2, which is between 9 pF and 27 pF.

4. **Difference Counts and Thresholds**: Estimate the difference counts, and set the Finger and Noise Threshold parameters. Difference counts are the increase in counts caused by a finger touch on the sensor. Difference counts are found using the finger sensitivity, S_{FINGER}, and finger capacitance, C_F, in Equation 1. Finger threshold and noise threshold are found using Equation 2 and Equation 3 (see the CY8C20x34 CapSense Design Guide).

Equation 1

$$DifferenceCounts = S_{Finger} \times C_F$$

Equation 2

$$FingerThreshold = 0.75 \times DifferenceCounts$$

Equation 3

$$NoiseThreshold = 0.5 \times DifferenceCounts$$

Compute these three values and go to Step 5.

Example: The system has the following parameters:

C_P = 10 to 22 pF, C_F = 0.2 pF

IDACSetting = 7

SettlingTime = 245

C_{mod} = 2700 pF, X7R (+/-20%)

CSA_EMC Clock = 6 MHz

IMO = 12 MHz

CPU = 6 MHz

Calculate difference counts, finger threshold, and noise threshold.

Difference counts = 500 counts/pF * 0.2 pF = 100 counts

Finger threshold = .75 * 100 = 75 counts

Noise Threshold = .5 * 100 = 50 counts

5. **Scan Time**: Estimate the scan time, t_{SCAN}, for scanning all the sensors using the conversion time, t_C, in Equation 4. Conversion time is 900 µs per sensor.

Equation 4

$$t_{SCAN} = t_C \times (number of sensors)$$

Compute this value and go to Step 6.

Example: There are 12 sensors in the system defined in Step 4.

tSCAN = 900 µs/sensor * 12 sensors = 10.8 ms

6. **Average Supply Count**: Estimate the average supply current, I_{DDCS}, using the active current, I_{active}, the sleep current, I_{sleep}, and the report rate in Equation 5.

Equation 5

$$I_{DDCS} = [t_{SCAN} \times I_{active} + (ReportRate - t_{SCAN}) \times I_{sleep}] / (ReportRate)$$

Example: Continuing from Step 5, add the following parameters:

ReportRate = 100 ms

I_{active} = 1.13 mA

I_{sleep} = 2.6 µA

Solve for the average supply current, I_{DDCS}.

I_{DDCS} = [10.8 ms * 1.13 mA + 89.2 ms * 2.6 µA] / 100 ms = 124 µA

7. **Series Resistors**: Determine the need for series resistors for RF immunity.
Example: PCB traces are copper and are over 25 mm long. Under these conditions, 560Ω series resistors are recommended for all CapSense inputs.

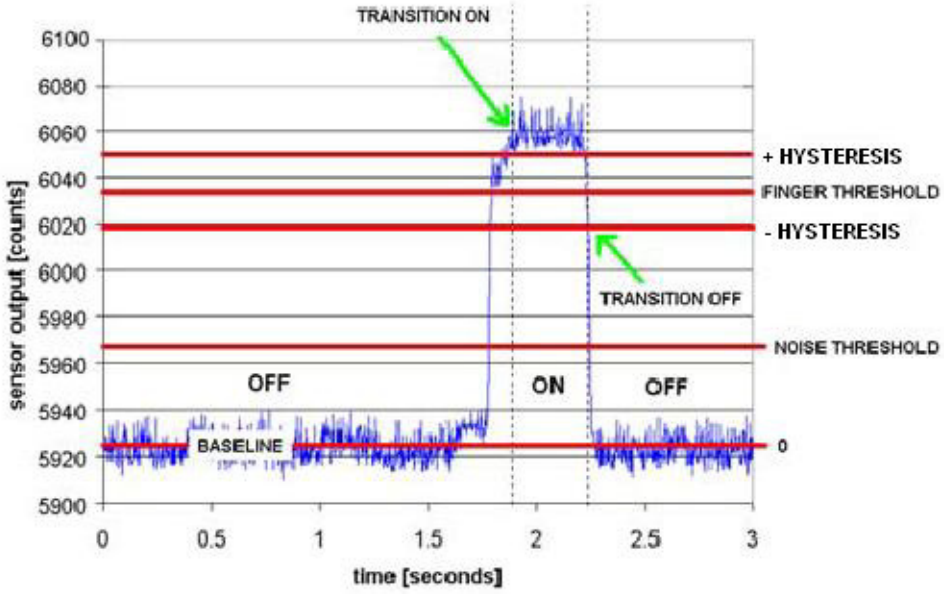
Capacitance Sensing Implementation

Buttons

CapSense buttons are analogous to mechanical push buttons. They are used for discreet controls such as on/off switches, function keys, menu keys, and so on. API functions monitor the capacitance signals (raw counts) from each sensor and compare them to tunable threshold parameters. When a sensor is touched, its capacitance signal increases; if the increase is sufficient as determined by the CSA_EMC decision

logic, that sensor becomes activated. Figure 4 shows a typical signal (blue line) from a sensor as it is being activated. The thresholds (red lines) are all tunable to provide the desired behavior.

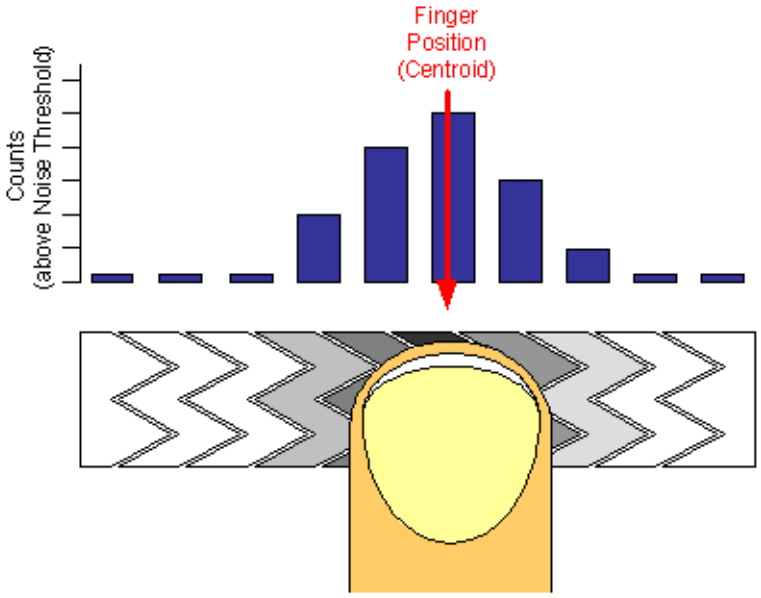
Figure 4. Capacitance Signal from a Sensor as it is Being Activated



Sliders

CapSense sliders are analogous to mechanical potentiometers. Sliders are used for controls requiring a continuum of levels such as lighting dimmers, volume control, graphic equalizers, speed controls, and so on. A CapSense slider is implemented with an array of adjacent sensors. When a slider is actuated by a finger, several adjacent sensors register an increase in capacitance signal as shown in Figure 5. The exact position of the touch is found by computing the centroid location of the set of activated sensors. The practical minimum number of sensors in a slider is five and the maximum is limited only by the number of available I/O pins on the PSoC device.

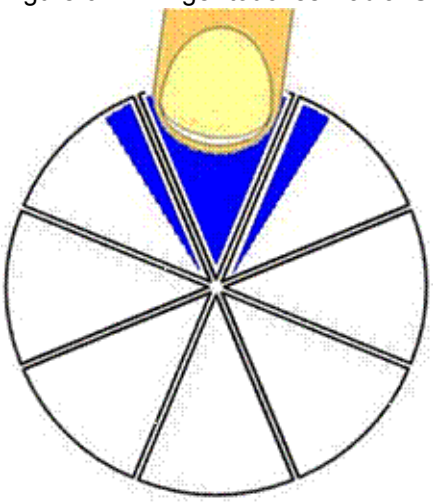
Figure 5. Interpolated Centroid Position of a Finger on a Slider



Radial Sliders

CSA_EMC supports two slider types: linear and radial. Linear sliders have a beginning and an end, whereas radial sliders, shown in Figure 6, do not. In either case, when a touch occurs, the centroid algorithm takes into account signal from sensors adjacent to the sensor with the largest signal to interpolate the exact position of the touch. Radial sliders are not diplexed. The CSA_EMC User Module has two special API functions for radial sliders. The first function CSA_EMC_wGetRadiaPos() returns centroid location and the second CSA_EMC_wGetRadialInc() returns finger shift in resolution units. When the finger moves in a clockwise direction CSA_EMC_wGetRadialInc() returns a positive offset. The reference point(0) is located in the center of the first sensor. The resolution for both linear and radial sliders is limited to (number of pins used for sensors – 1) x 2^8 – 1 or (2 x pins used for sensors – 1) x 2^8 -1 for diplexed sliders.

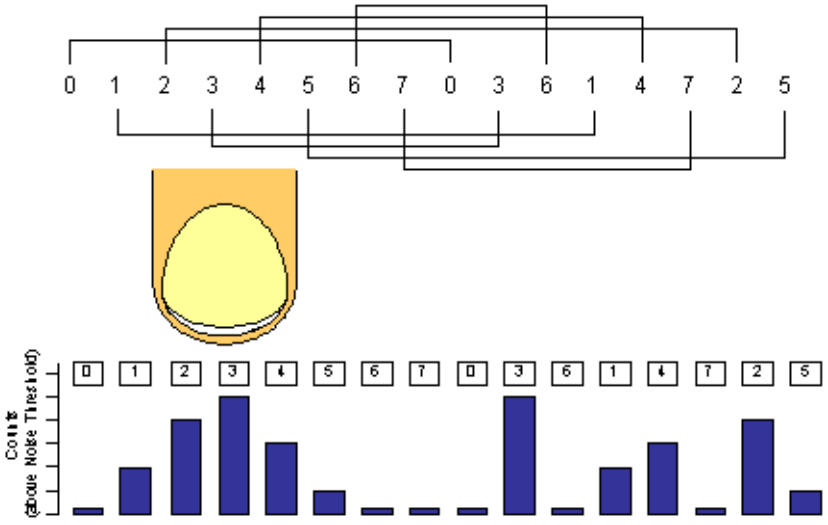
Figure 6. Finger touches Radial Slider



Diplexing

When diplexing is used, each pin on the PSoC designated as a slider element is mapped to two physical locations in the array of slider sensors. The first (or numerically lower) half of the physical locations is mapped according to the port pin assigned in the CSA_EMC wizard. The second (or upper) half of the physical sensor locations is automatically mapped using the pattern shown in Figure 7.

Figure 7. Indexing of Diplexed Slider Array by CSD



The close proximity of strong signals in lower half of the slider results in the same levels aliased into the upper half. However, in the upper half, the results are scattered and non-contiguous. The centroid algorithm searches for strong adjacent sets of signals to declare the resolved slider position. The pattern used for mapped upper half sensors ensures that a valid signal pattern in one half does not result in a valid signal pattern in the other half as shown in Figure 7.

Take care to ensure the mapping of sensors to pins on the PCB matches the Index by 3 sequence used by the diplexing algorithm. The capacitance of sensor pairs in a diplexed slider should also be reasonably well matched (within 10 pF). The diplex sensor index table is automatically generated by the CSA_EMC Wizard when you select diplexing. Table 1 shows the diplexing sequences for up to 56 slider segments diplexed into 28 PSoC I/O pins.

Table 1. Diplexing Sequence for Different Slider Segment Counts

Total Slider Segment Count	Segment Sequence
10	0,1,2,3,4,0,3,1,4,2
12	0,1,2,3,4,5,0,3,1,4,2,5
14	0,1,2,3,4,5,6,0,3,6,1,4,2,5
16	0,1,2,3,4,5,6,7,0,3,6,1,4,7,2,5
18	0,1,2,3,4,5,6,7,8,0,3,6,1,4,7,2,5,8
20	0,1,2,3,4,5,6,7,8,9,0,3,6,9,1,4,7,2,5,8
22	0,1,2,3,4,5,6,7,8,9,10,0,3,6,9,1,4,7,10,2,5,8
24	0,1,2,3,4,5,6,7,8,9,10,11,0,3,6,9,1,4,7,10,2,5,8,11
26	0,1,2,3,4,5,6,7,8,9,10,11,12,0,3,6,9,12,1,4,7,10,2,5,8,11
28	0,1,2,3,4,5,6,7,8,9,10,11,12,13,0,3,6,9,12,1,4,7,10,13,2,5,8,11
30	0,1,2,3,4,5,6,7,8,9,10,11,12,13,14,0,3,6,9,12,1,4,7,10,13,2,5,8,11,14
32	0,1,2,3,4,5,6,7,8,9,10,11,12,13,14,15,0,3,6,9,12,15,1,4,7,10,13,2,5,8,11,14
34	0,1,2,3,4,5,6,7,8,9,10,11,12,13,14,15,16,0,3,6,9,12,15,1,4,7,10,13,16,2,5,8,11,14
36	0,1,2,3,4,5,6,7,8,9,10,11,12,13,14,15,16,17,0,3,6,9,12,15,1,4,7,10,13,16,2,5,8,11,14,17
38	0,1,2,3,4,5,6,7,8,9,10,11,12,13,14,15,16,17,18,0,3,6,9,12,15,18,1,4,7,10,13,16,2,5,8,11,14,17
40	0,1,2,3,4,5,6,7,8,9,10,11,12,13,14,15,16,17,18,19,0,3,6,9,12,15,18,1,4,7,10,13,16,19,2,5,8,11,14,17
42	0,1,2,3,4,5,6,7,8,9,10,11,12,13,14,15,16,17,18,19,20,0,3,6,9,12,15,18,1,4,7,10,13,16,19,2,5,8,11,14,17,20
44	0,1,2,3,4,5,6,7,8,9,10,11,12,13,14,15,16,17,18,19,20,21,0,3,6,9,12,15,18,21,1,4,7,10,13,16,19,2,5,8,11,14,17,20
46	0,1,2,3,4,5,6,7,8,9,10,11,12,13,14,15,16,17,18,19,20,21,22,0,3,6,9,12,15,18,21,1,4,7,10,13,16,19,22,2,5,8,11,14,17,20

Total Slider Segment Count	Segment Sequence
48	0,1,2,3,4,5,6,7,8,9,10,11,12,13,14,15,16,17,18,19,20,21,22,23,0,3,6,9,12,15,18,21,1,4,7,10,13,16,19,22,2,5,8,11,14,17,20,23
50	0,1,2,3,4,5,6,7,8,9,10,11,12,13,14,15,16,17,18,19,20,21,22,23,24,0,3,6,9,12,15,18,21,24,1,4,7,10,13,16,19,22,2,5,8,11,14,17,20,23
52	0,1,2,3,4,5,6,7,8,9,10,11,12,13,14,15,16,17,18,19,20,21,22,23,24,25,0,3,6,9,12,15,18,21,24,1,4,7,10,13,16,19,22,25,2,5,8,11,14,17,20,23
54	0,1,2,3,4,5,6,7,8,9,10,11,12,13,14,15,16,17,18,19,20,21,22,23,24,25,26,0,3,6,9,12,15,18,21,24,1,4,7,10,13,16,19,22,25,2,5,8,11,14,17,20,23,26
56	0,1,2,3,4,5,6,7,8,9,10,11,12,13,14,15,16,17,18,19,20,21,22,23,24,25,26,27,0,3,6,9,12,15,18,21,24,27,1,4,7,10,13,16,19,22,25,2,5,8,11,14,17,20,23,26

DC and AC Electrical Characteristics

Unless specified otherwise, Vdd = 2.7V to 5.0V, and C_{mod} = X7R-type capacitor, ±20% tolerance.

Table 2. Electrical Specifications for the CSA_EMC User Module

Symbol	Description	Conditions	Min	Typ	Max	Unit
C_P	Parasitic Capacitance[a]	see note on C_P ranges[b]	5		50	pF
C_F	Finger Capacitance[c]		0.1			pF
N	Output Counter Resolution		16		16	bit
S_{FINGER}	Finger Sensitivity[d]	C_P = 5 to 15 pF IDAC Setting = 5 Settling Time = 120 C_{mod} = 1200 pF CSA_EMC Clock = 6 MHz IMO = 12 MHz CPU = 6 MHz	500			counts/pF
		C_P = 9 to 27 pF IDAC Setting = 7 Settling Time = 245 C_{mod} = 2700 pF CSA_EMC Clock = 6 MHz, IMO = 12 MHz CPU = 6 MHz	500			counts/pF

Symbol	Description	Conditions	Min	Typ	Max	Unit
		C_P=16 to 50 pF IDAC Setting = 5 Settling Time = 160 C_{mod} = 5600 pF CSA_EMC Clock = 3 MHz IMO=12 MHz CPU=3 MHz	500			counts/pF
t_C	Conversion Time, Single Sensor.[d]	C_P = 5 to 15 pF IDAC Setting = 5 Settling Time = 120 C_{mod} = 1200 pF CSA_EMC Clock = 6MHz IMO = 12 MHz CPU = 6 MHz			700	ms/sensor
		C_P = 9 to 27 pF IDAC Setting = 7 Settling Time = 245 C_{mod} = 2700 pF CSA_EMC Clock = 6 MHz IMO = 12 MHz CPU = 6 MHz			900	ms/sensor
		C_P = 16 to 50 pF IDAC Setting = 5 Settling Time = 160 C_{mod} = 5600 pF CSA_EMC Clock = 3 MHz IMO = 12 MHz CPU = 3 MHz			2500	ms/sensor
I_{DDCS}	Average Supply Current	Vdd = 3.3V C_P=5 to 15 pF 4 button scan 100 ms report rate		35	50	mA
R_S	Series Resistor for RF immunity[e][5]	high conductivity traces (copper or silver ink) longer than 25 mm	300		560	ohms

a. C_P includes package-related capacitance of 2-3 pF.

b. Finger Sensitivity and Conversion Time specified over one of three C_P ranges: (5-15 pF), (9-27 pF), (16-50 pF)

c. Finger Capacitance is the increase in C_P caused by a finger touch on the sensor.

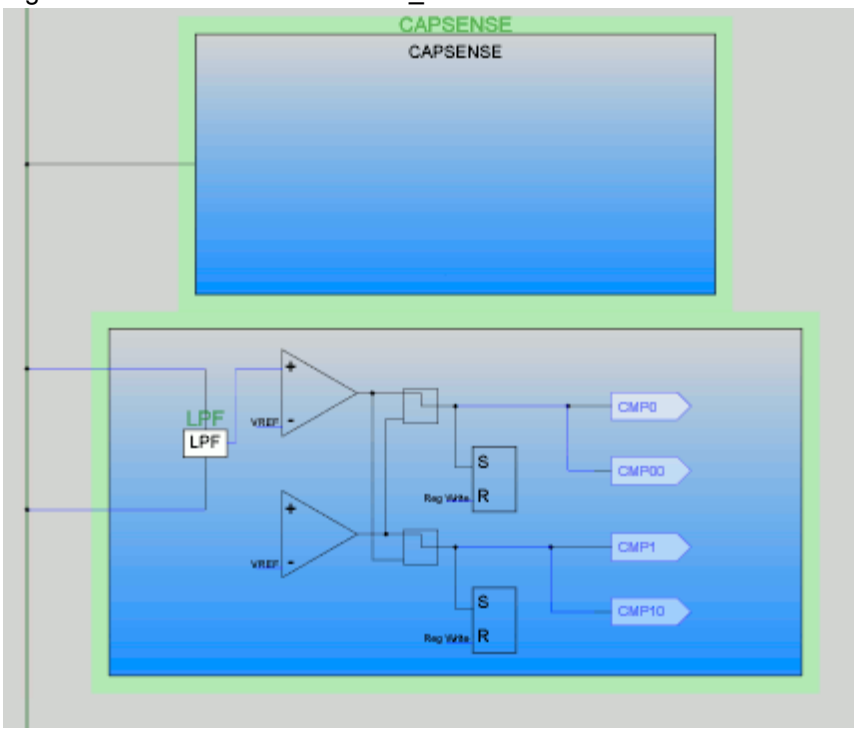
d. IDAC Setting selected so that a finger touch produces a signal of at least 50 counts.

e. R_S not required for low conductivity ITO thin film. Resistors placed within 10 mm of PSoC pin.

Placement

The blocks for the user module are automatically placed when the user module is instantiated, alternate placements are not available. User modules that consume specific pin resources, including the LCD and EZI2Cs, must be placed before establishing port pin connections for the CSA_EMC User Module. These selections are reflected in the wizard when it is opened.

Figure 8. Placement of the CSA_EMC User Module

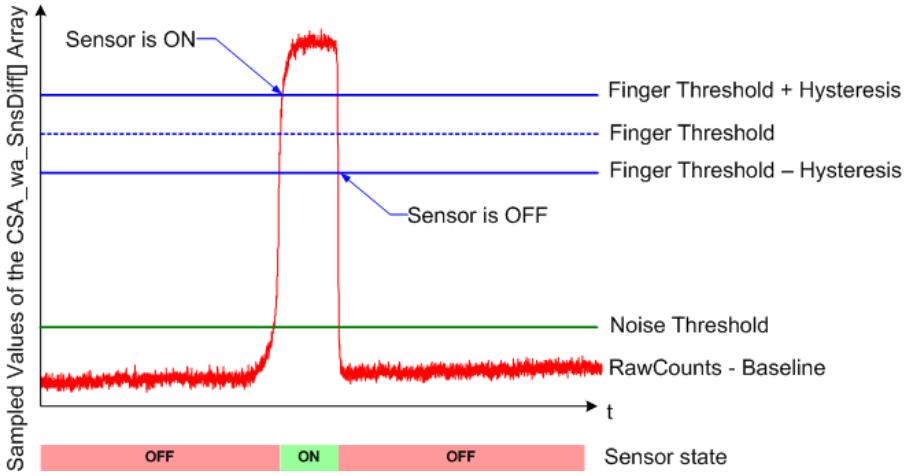


Do not use P1[0] and P1[1] when placing capacitive sensor connections. These pins are used for programming the part and may have excess routing capacitance that degrades sensor performance.

Parameters and Resources

Figure 5 illustrates some of the terms used in the CSA_EMC Parameters:

Figure 9. Terminology for the CSA_EMC Parameters Using a Difference Counts Waveform



Finger Threshold

This threshold is used to determine the state of each button sensor using the difference counts wave form. If the difference count stored in the wa_SnsDiff[] array is at or above the Finger Threshold, the sensor is active.

Possible values range from 3 to 255 (default value: 60).

Noise Threshold

For individual sensors, this parameter sets the count value above which the baseline is not updated.

For slider sensors, it sets the count value below which the results are not counted in the calculation of the centroid.

Possible values are 3 to 255 (default value: 10).

Baseline Update Threshold

When the new raw count value is above the current baseline and the difference is below the noise threshold, the difference between the current baseline and the raw count is accumulated into a “bucket". When the bucket fills, the baseline increments and the bucket is emptied. This parameter sets the threshold that the bucket must reach for the baseline to increment.

Possible values are 0 to 255 (default value: 100).

SettlingTime

The SettlingTime parameter controls the software delay that allows the voltage on the C_{mod} capacitance to stabilize. The loop has 21 CPU cycles per iteration. The total delay is calculated using Equation 6:

Equation 6

$$Delay(\mu s) = \frac{6 + 21 \cdot (Settling\ Time)}{CPU_Speed(MHz)}$$

Select a SettlingTime that is at least 5 × R × C, where R = 1 ÷ (Clock × C_P) and C = C_{mod}.

Possible values are 2 to 255 (default value: 20). The default value is 20, which corresponds to 35.5 µs delay at 12 MHz CPU clock.

ExternalCap

The ExternalCap parameter chooses the PSoC pin to which the C_{mod} capacitor connects. The recommended range of C_{mod} is 1200 pF to 5600 pF. The value of C_{mod} impacts finger sensitivity and conversion time. You usually get better SNR with an external capacitor. See the DC and AC Electrical Characteristics for details.

Possible values are None, P0[1], and P0[3] (default value: None).

Hysteresis

The Hysteresis parameter adds or subtracts from the finger threshold depending on whether the sensor is currently active or inactive. If the sensor is off, the difference count must overcome the finger threshold plus hysteresis. If the sensor is on, the difference count must go below the finger threshold minus hysteresis. It is used to add debouncing and “stickiness" to the finger detection algorithm.

Possible values are 0 to 255 (default value: 10). However, the setting must be lower than the FingerThreshold parameter setting.

Debounce

The Debounce parameter adds a debounce counter to the sensor active transition. For the sensor to transition from inactive to active the difference count value must stay above the finger threshold plus hysteresis for the number of samples specified.

Possible values are 1 to 255 (default value: 3). A setting of 1 gives no debouncing.

NegativeNoiseThreshold

The NegativeNoiseThreshold parameter adds a negative difference count threshold. If the current raw count is below the baseline by more counts than the NegativeNoiseThreshold parameter and the difference between them is greater than this threshold, the baseline is not updated. However, if the current raw count stays in the low state (difference greater than threshold) for the number of samples specified by the LowBaselineReset parameter, the baseline is reset.

Possible values are 0 to 255 (default value: 10).



LowBaselineReset

The LowBaselineReset parameter works together with the NegativeNoiseThreshold parameter. If the sample count values are below the baseline minus the NegativeNoiseThreshold for the specified number of samples, the baseline is set to the new raw count value. It counts the number of abnormally low samples required to reset the baseline. It is used to correct for the finger-on-at-startup condition.

Possible values are 0 to 255 (default value: 50).

Sensors Autoreset

This parameter determines whether the baseline is updated at all times or only when the signal difference is below the Noise Threshold. When set to **Enabled** the baseline is updated constantly. This setting limits the maximum time duration of the sensor (typical values are 5 – 10s), but it prevents the sensors from permanently turning on when the raw count suddenly rises without anything touching the sensor. This sudden rise can be caused by a large power supply voltage fluctuation, a high energy RF noise source, or a very quick temperature change.

When the parameter is set to **Disabled** the baseline is updated only when raw count and baseline difference is below the Noise Threshold parameter.

Possible values are Enabled and Disabled (default value: Disabled).

Freq Num

This parameters allows increasing EMI performance by scanning each sensor three times at different clocks. Freq Num = 1 corresponds to the standard scanning algorithm and Freq Num = 3 turns on advanced algorithm. Enabling the advanced scanning algorithm (Freq Num = 3) increases scanning time and RAM consuming nearly three times.

Possible values are 1 and 3 (default value: 3).

Spread Spectrum

This parameters allows increasing EMI performance by random change of clock value during scanning. Enable this parameter if Freq Num is set at 1.

Possible values are Disable and Enable (default value: Disable).

RawData Median Filter

The median filter looks at the three most recent samples from a sensor and reports the median value. It is used to remove short noise spikes. This filter generates a delay of one sample. This filter is generally not recommended because of the delay and RAM use. Enabling this filter consumes (Number of Sensors × 2 × Freq Num) bytes of RAM and 100 bytes of flash. It is disabled by default.

RawData IIR Filter

This infinite impulse response (IIR) filter reduces noise in the conversion result (raw count). Filtering on the raw counts can be more effective than filtering the XY coordinate but requires more RAM. Enabling this filter consumes an additional 100 bytes of flash. It is disabled by default.

The default IIR coefficient is 0.5.

RawData IIR Filter Coefficient

This is the coefficient for the raw count IIR filter. A “2" means ½ previous + ½ current. A “4" means ¾ previous + ¼ current. Two and four are the only permitted settings (default value: 2).

Clock

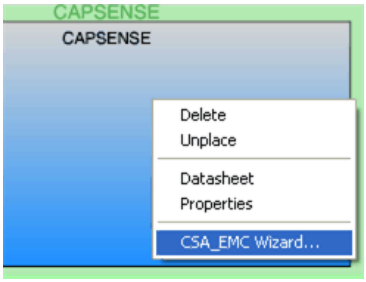
The Clock parameter can be used to increase the amount of effective resistance of the sensor. If the sensor area is large, the effective resistance may be too high for the auto calibration of the switched capacitor circuit. Touchpad rows/columns or large proximity sensors may encounter decreased sensitivity. In this case, the settling voltage is too far beneath the comparator threshold. Setting a larger divider of the IMO increases the effective resistance, compensating for the high capacitance.

Possible values are IMO, IMO/2, IMO/4, and IMO/8 (default value: IMO).

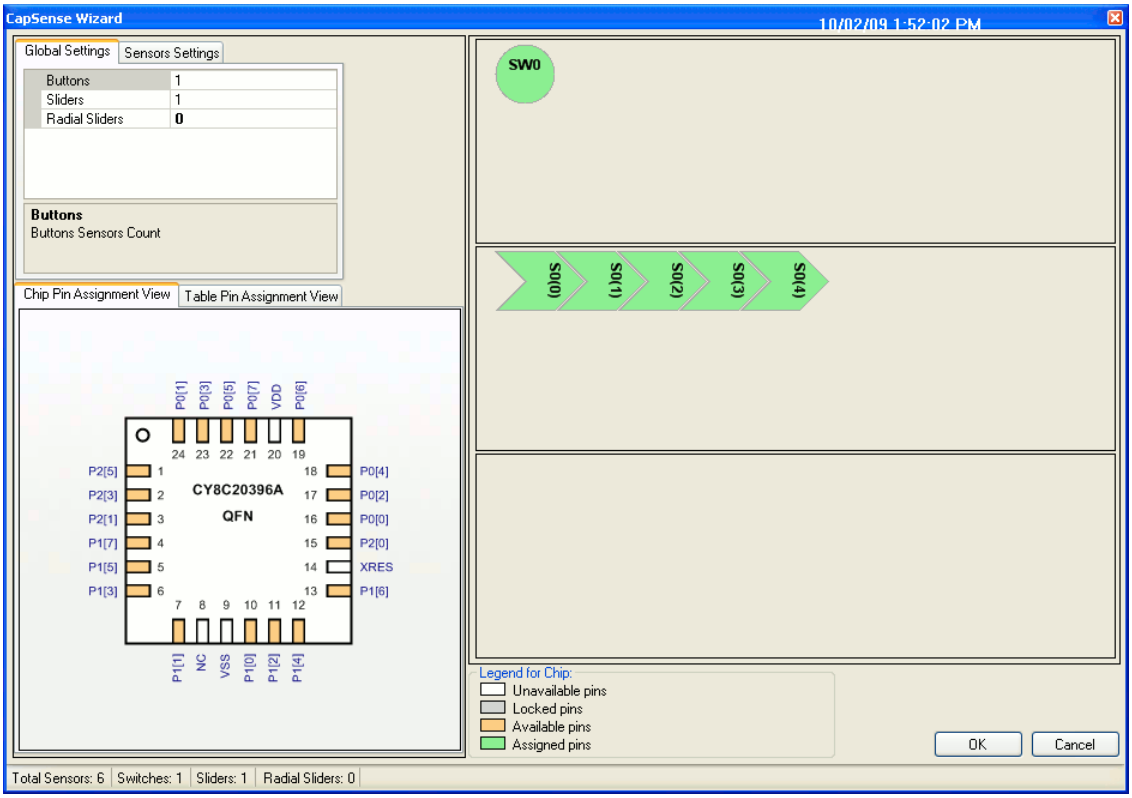
Wizard

The CSA_EMC Wizard is used to set up the pinout for your CapSense buttons, sliders, and proximity sensors. Choose the required configuration and assign the buttons and segments using a drag and drop interface.

1. To access the Wizard, right click any block of the CSA_EMC in the Device Editor Interconnect View, then select the CSA_EMC Wizard with a left-click.



2. The Wizard opens to display the numeric entry boxes for the number of buttons and the number of linear and radial sliders.



Wizard Pin Legend

White – The pin cannot be used as a CapSense input.

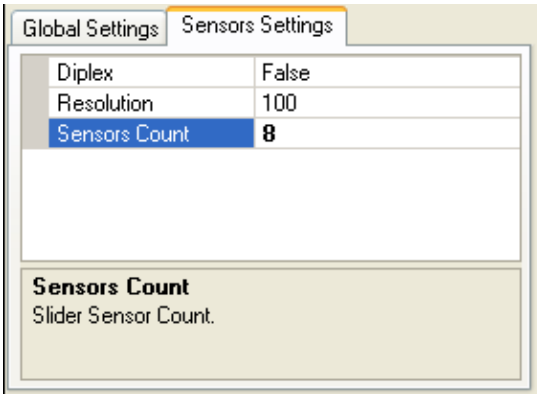
Gray – The pin is locked. There are two possible causes for this. The first possibility is that another user module such as the LCD or I^2C has claimed the pin. The second possibility is that the name of the pin has been changed from its default. To return the pin name to its

default, in the Pinout view expand the pin, from the **Select** menu, select **Default**. The pin is now available for assignment in the wizard.

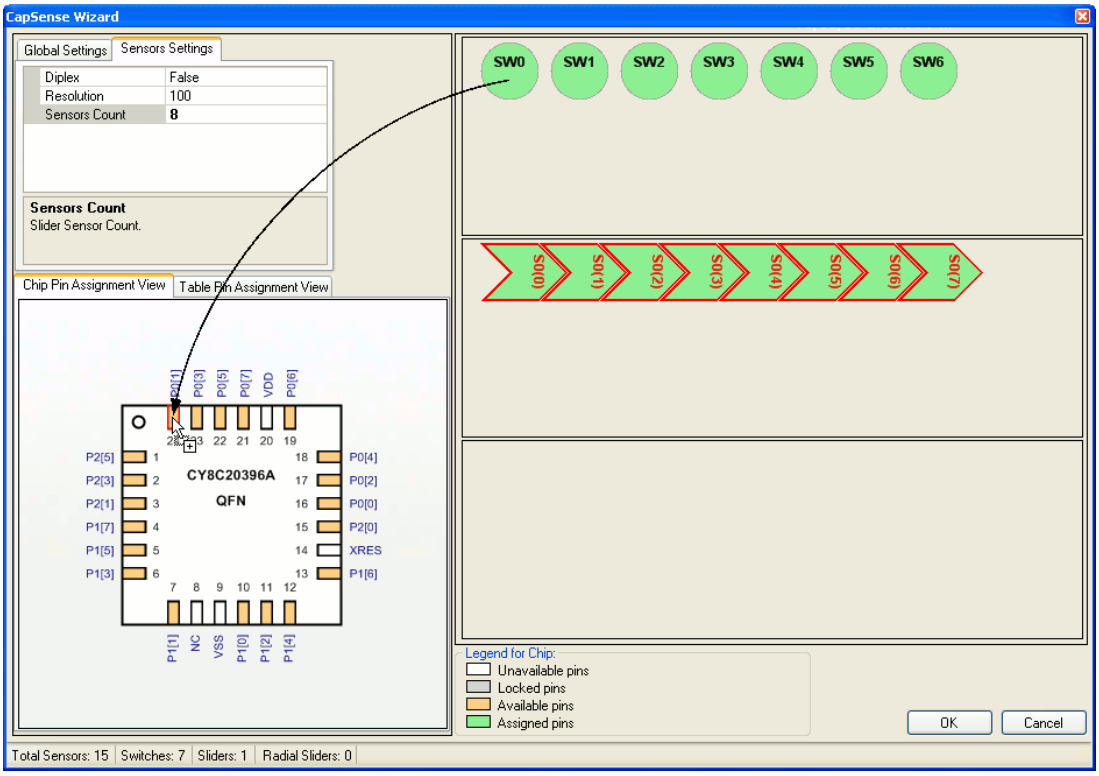
Orange – The pin is available for assignment.

Green – The pin has been assigned as a CapSense input.

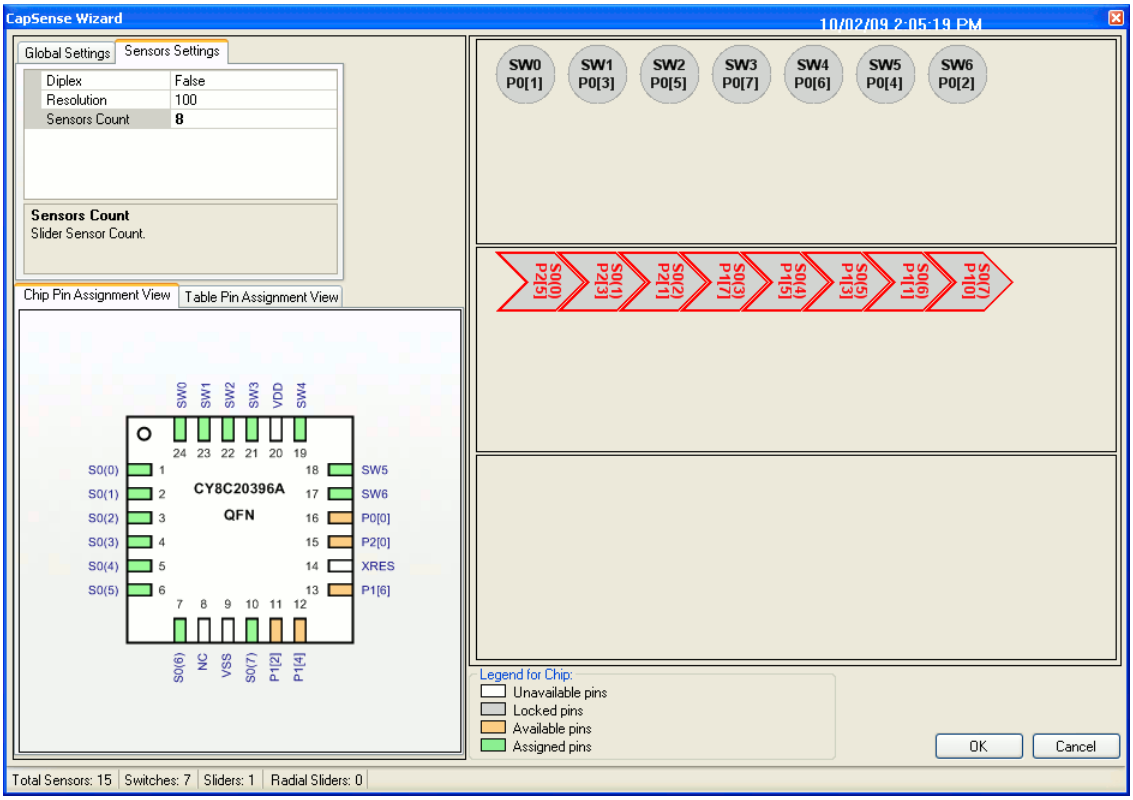
3. Type the number of buttons. The number of sensors is limited to the number of pins available. Press the [Enter] key to enter the new value for the number of sensors.
4. Type the number of linear and radial sliders. X-Y touchpads require two sliders.
5. Click one of your sliders to enable the Sensor Settings for that slider. Type the number of sensor elements in each slider. The practical minimum number of sensors in a slider sensor is five, the maximum is limited by pin count. After entering the data, press the [Enter] key to enter the new value.



6. Type the output resolution. The minimum value is five. The maximum value is (number of pins used for sensors – 1) x 2^8 – 1 or (2 x pins used for sensors – 1) x 2^8 – 1 for diplexed sliders.
7. Select Diplex, if required. This maps the number of pins selected for sensors to twice as many sensor locations on the board. Only the first half of the diplex sensors is shown. See the Getting Started with CapSense Design Guide to find Diplexing tables for pin connections.
8. Assign switches or sensors to pins by dragging the switch or sensor onto the pin in the Pin Assignment View. You can choose to drag switches or sensors onto pins in the Chip Pin Assignment View or the Table Pin Assignment View. The port pin is green after selection and is no longer available. Change sensor assignments by dragging the sensor off of the port pin. If you right-click on the “Chip Pin Assignment View" and "Table Pin Assignment View", you get the "Clear All Pins" option. This option unassigns all chip pins.



9. Repeat for the remainder of independent sensors.



Mapping of individual slider sensors onto physical port pins is the same as for individual sensors. Click **OK** to accept data and return to PSoC Designer.

Sensor placement is now complete. Right-click in the Device Editor window and select **Refresh** to update the pin connections.

Set the user module parameters and generate the application. You can adapt a sample project now, if required.

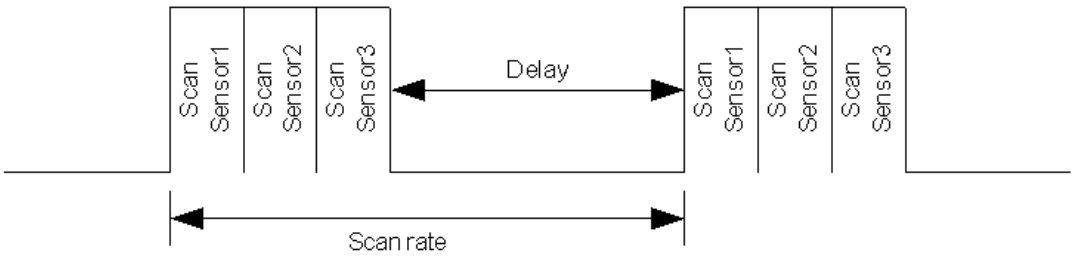
If you want to change the pin assignment, place your cursor on the assigned pin, click the pin, and drag and drop it outside the switches box. The pin is now unassigned and you can reassign it.

After completing the Wizard, click Generate Application. Based on your entries for sensor count, pin assignment, diplexing, and resolution, a set of tables is generated. The tables are located in CSA_EMCTABLE.asm.

Sensor Scan Rate Selection Guidelines

Scan rate is the rate at which sensors are scanned. An example of a 3-button design is shown in the following figure. All sensors in the design are scanned sequentially and there is a delay before the next sensor scan is initiated

Figure 10. Typical Sensor Scan



To ensure proper working of the baseline, it is recommended to maintain a scan rate of 15 ms or more in a design. This indicates that a design with less number of sensors must add a delay to make the sensor scan rate equal to or greater than 15 ms. A design with more number of sensors may not need any delay as scanning all sensors itself may consume 15 ms. A good design may put the CapSense controller in sleep mode, instead of the firmware delay routine, to create a low power design.

Application Programming Interface

The Application Programming Interface (API) routines are given as part of the user module to allow your code to interact with the user module without dependence on its implementation details. This section specifies each function of the interface together with related constants provided by the include files.

Only one instance of this user module can be placed in the project and this also applies to loadable configurations.

Note

**In this, as in all user module APIs, the values of the A and X register are altered by calling an API function. It is the responsibility of the calling function to preserve the values of A and X before the call if

those values are required after the call. This registers are volatile policy was selected for efficiency reasons and in force since version 1.0 of PSoC Designer. The C compiler automatically takes care of this requirement. Assembly language programmers need to make certain that their code observes the policy. Though some user module API functions may leave A and X unchanged, there is no guarantee they may do so in the future.

For Large Memory Model devices, it is also the caller's responsibility to preserve any value in the CUR_PP, IDX_PP, MVR_PP, and MVW_PP registers. Even though some of these registers may not be modified now, there is no guarantee that will remain the case in future releases.

Entry Points are supplied to initialize, start, and stop the CSA_EMC User Module. In all cases the instance name of the module replaces the CSA_EMC prefix shown in the following entry points. Failure to use the correct instance name is a common cause of syntax errors.

Software Control Parameters

Control parameters passed to the APIs include:

bSnsGroup

Reference to a specific group of sensors used as a slider. Used by CSA_bGetCentroidPos to select which group of sensors to update.

Buttons are contained in group 0. Sliders are contained in group 1 and higher.

bSensor

The sensor number is used by CSA_wGetPortPin to determine port and bit mask (bPort and bMask) for the selected active sensor. CSA_wGetPortPin returns bMask and bPort. These two are used by CSA_EnableSensor and CSA_DisableSensor to determine specific sensor selection. They are also used by CSA_wReadSensor to set which sensor's counts are returned.

CSA_EMC Data Arrays

API functions use several global arrays. You must not alter these arrays manually. You can inspect these values for debugging purposes.

CSA_waSnsResult

This array holds the 16-bit raw count values for each sensor. It has dimensions [Freq Num][Number of Sensors].

CSA_waIIR

This array holds the 16-bit filtered raw count values for each sensor if IIR filter is enabled. It has dimensions [Freq Num][Number of Sensors].

CSA_waSnsBaseline

This array holds the 16-bit baseline values for each sensor.It has dimensions [Freq Num][Number of Sensors].

CSA_waSnsDiff

This array holds the 16-bit difference count values for each sensor (raw count - baseline).

CSA_baSnsOnMask

This 8-bit array holds the sensor on or off data (for buttons or sliders). Each element in the array holds the sensor state for up to 8 sensors. CSA_baSnsOnMask[0] contains the masked bits for sensors zero through seven (sensor zero is bit 0, sensor one is bit 1). CSA_baSnsOnMask[1] contains the

masked bits for sensors 8 through 15 (if they are needed), and so on. This byte array contains as many elements as are necessary to contain all the placed sensors. The value of the bit is 1 if the sensor is on and 0 if the sensor is off.

CSA_baDACCodeBaseline

This array holds the 8-bit calibration setting for each sensor that is determined automatically in CSA_Start. The values in this array give a relative measure of the parasitic capacitance loading each CapSense input.

Basic APIs

Basic APIs are used to start and stop the user module:

CSA_Start()

Description:

Calibrates the CSA_EMC User Module for each sensor and the common for all sensors slope IDAC value. Disconnects all sensor pins from the Analog Mux Bus. All sensor pins are shunted to ground. Connects the C_{mod} capacitor to the system.

C Prototype:

```
void  CSA_Start
```

Assembly:

```
lcall  CSA_Start
```

Parameters:

None

Return Value:

None

Side Effects:

**

CSA_Stop

Description:

Disables the CapSense block. Calls CSA_ClearSensors to disconnect all sensor pins from the Analog Mux Bus and shunt them to ground.

C Prototype:

```
void  CSA_Stop()
```

Assembly:

```
lcall  CSA_Stop
```

Parameters:

None

Return Value:

None

Side Effects:

**

CSA_Resume

Description:

Resumes the user module operation after CSA_Stop call.

C Prototype:

```
void  CSA_Resume()
```

Assembly:

```
lcall  CSA_Resume
```

Parameters:

None

Return Value:

None

Side Effects:

**

CSA_Calibrate (Legacy)

Description:

Calibrates the common for all sensors slope IDAC value. This function runs when CSA_Start() is called. This function can be called at anytime to recalibrate the sensors. The function adjusts the iDAC current to obtain a raw count as close as possible to wLevel.

C Prototype:

```
void  CSA_Calibrate(WORD wLevel)
```

Assembly:

```
mov  A, <wLevel
mov X, >wLevel
lcall  CSA_Calibrate
```

Parameters:

wLevel - The desired raw count value

Return Value:

None

Side Effects:

**

CSA_CalibrateSingleSensor

Description:

Performs successive approximation for the selected sensor to find the DAC setting that gives a result closest to the CalibratedRawCountLevel value.

C Prototype:

```
void CSA_CalibrateSingleSensor(BYTE bSensor, WORD CalibratedRawCountLevel)
```

Assembly:

```
mov A, >CalibratedRawCountLevel
push A ; wLevel (MSB) -> Stack
mov A, <CalibratedRawCountLevel
push A ; wLevel (LSB) -> Stack
mov A, bSensor

lcall CSA_CalibrateSingleSensor
```

Parameters:

[X - 3] => bSensor

[X - 4] => CalibratedRawCountLevelLSB

[X - 5] => CalibratedRawCountLevelMSB

Return Value:

None

Side Effects:

**

CSA_CalibrateAllSensors

Description:

Performs successive approximation for all sensors to find the DAC setting that gives a result closest to the CalibratedRawCountLevel value.

C Prototype:

```
void CSA_CalibrateAllSensors(WORD CalibratedRawCountLevel)
```

Assembly:

```
mov A, <CalibratedRawCountLevel
mov X, >CalibratedRawCountLevel
lcall CSA_CalibrateSingleSensor
```

Parameters:

A => CalibratedRawCountLevelLSB

X => CalibratedRawCountLevelMSB

Return Value:

None

Side Effects:

**

Data Tables

Based upon your entries for sensor count, pin assignment, diplexing, and resolution, the wizard generates a set of data tables. The sensor table is located in CSA_EMCTABLE.asm. The group and diplex tables are located in CSA_EMCHL.asm.

CSA_Sensor_Table

The sensor table consists of a 2 byte entry for each sensor. The first byte is the port number and the second byte is the bit mask for the bit (not the bit number). The table includes all independent sensors, then each slider sensor in order. An example for a table with six sensors is:

```
CSA_Sensor_Table:
_CSA_Sensor_Table:
      dw    0x0140  //  Port 1 Bit 6
      dw    0x0301  //  Port 3 Bit 0
      dw    0x0304  //  Port 3 Bit 2
      dw    0x0308  //  Port 3 Bit 3
      dw    0x0302  //  Port 3 Bit 1
      dw    0x0108  //  Port 1 Bit 3
```

CSA_Group_Table

The group table defines each of the groups of sensors or slider sensors. The first entry in each line of the table is the starting sensor number for the group. The second entry is the number of sensors in the group. The third entry is 0 if not diplexed. The fourth, fifth, and sixth entries are combined to form the fixed point multiplier value for the centroid calculation. An example with seven sensors is shown here:

```
CSA_Group_Table:
CSA_Group_Table:
// Group Table
//        Origin Count  Diplex?  SliceMultiplier
      db    0,    0x7,    0x0,    0x00     // Buttons
```

In projects with independent sensors and slider sensors, the set of independent sensors and each slider sensor has a separate entry in the group table, as shown here:

```
CSA_Group_Table:
CSA_Group_Table:
; Group Table
;         Origin Count  Diplex?  DivBtwSns(wholeMSB, wholeLSB, fractByte)
      db    0,    0x7,    0x0,    0x00,    0x00,    0x00 ; Buttons
      db    0x6,  0xA,    0x4,    0x0,     0x7,     0xE5 ; Slider 1
```

CSA_Diplex_Table

The diplex table defines the mapping of the full range of sensors for each slider sensor. The table consists of two parts: sensor mapping for each slider, and a reference for each separate slider to its table. A typical example for a ten sensor slider is shown here:

```
DiplexTable_0:
; This group is not a diplexed slider

DiplexTable_1:
    db    0,1,2,3,4,5,6,7,8.9,0,3,6,9,1,4,7,2,5,8   // 10 switch slider

CSA_Diplex_Table:
_CSA_Diplex_Table:
    db >DiplexTable_0, <DiplexTable_0
    db >DiplexTable_1, <DiplexTable_1
```

Low-Level APIs

Low level APIs are used to acquire sensor data.

CSA_ScanSensor

Description:

Scans a single sensor to determine the raw count value representing its capacitance. This routine assumes that the CSA_Start function was called before its execution. The routine is a blocking call that waits for the CapSense block interrupt CSA_ISR to complete. It then transfers the data from the 16-bit counter to the CSA_wADCResult global variable.

C Prototype:

```
void  CSA_ScanSensor(BYTE bSensor)
```

Assembly:

```
mov  A,  bSensor
lcall CSA_ScanSensor
```

Parameters:

bSensor: Range is 0 to n-1, where n is the total of the number of sensors set in the CSA_EMC Wizard plus the number of sensors included in the slider sensors.

Return Value:

None

Side Effects:

**

CSA_ScanAllSensors

Description:

Scans all of the configured sensors by calling CSA_ScanSensor for each sensor index. Then it applies all enabled filters to the raw data and updated all baselines.

C Prototype:

```
void  CSA_ScanAllSensors()
```

Assembly:

```
lcall  CSA_ScanAllSensors
```

Parameters:

None

Return Value:

None

Side Effects:

**

CSA_ClearSensors

Description:

CSA_DisableSensor for each of the sensors. The sensors pins are disconnected from the Analog Mux Bus and shunted to ground.

C Prototype:

```
void  CSA_ClearSensors()
```

Assembly:

```
lcall  CSA_ClearSensors
```

Parameters:

None

Return Value:

None

Side Effects:

**

CSA_wGetPortPin

Description:

Returns the port number and pin mask for a given sensor. The passed parameter indexes and selects the data from the CSA_Sensor_Table.

C Prototype:

```
WORD  CSA_wGetPortPin(BYTE bSensor)
```

Assembly:

```
mov  A,  bSensor
lcall     CSA_wGetPortPin
```

Parameters:

bSensor: Range is 0 to n-1, where n is the total of the number of sensors set in the CSA_EMC Wizard plus the number of sensors included in slider sensors.

Return Value:

bPort and bMask: The port number and the bit mask that are used to determine a specific sensor selection.

Side Effects:

**

CSA_EnableSensor

Description:

Configures the selected sensor for scanning during the next measurement cycle. The port and pin of the sensor are selected using the CSA_wGetPortPin routine, with the port number and sensor bit mask loaded into X and A, respectively. Drive modes are modified to place the selected port and pin into Analog High Z mode and to enable the correct Analog Mux Bus input.

C Prototype:

```
void  CSA_EnableSensor(BYTE bMask, BYTE bPort)
```

Assembly:

```
mov  X,  bPort
mov  A,  bMask
lcall  CSA_EnableSensor
```

Parameters:

bPort and bMask: The port number and the bit mask that are used to determine a specific sensor selection.

Return Value:

None

Side Effects:

**

CSA_DisableSensor

Description:

Disconnects a sensor so that it is no longer an input. Typically, this call is used in combination with the CSA_wGetPortPin. The connection from the port pin to the AnalogMuxBus is turned off. The drive mode is changed to Strong (01). This grounds the sensor.

C Prototype:

```
void  CSA_DisableSensor(BYTE bMask, BYTE bPort)
```

Assembly:

```
mov  X,  bPort
mov  A,  bMask
lcall  CSA_DisableSensor
```

Parameters:

bPort and bMask: The port number and the bit mask that are used to determine a specific sensor selection.

Return Value:

None

Side Effects:

**

High-Level APIs

High level APIs are used to process sensor data acquired by the low level APIs.

CSA_bIsSensorActive

Description:

Checks the difference count array for the given sensor compared to its finger threshold. Hysteresis is taken into account. The Hysteresis value is added or subtracted from the finger threshold based the

state of the sensor. If it is active, the threshold is lowered. If it is inactive, the threshold is raised. This function also updates the sensor's bit in the CSA_baSnsOnMask array.

C Prototype:

```
BYTE  CSA_bIsSensorActive(BYTE bSensor)
```

Assembly:

```
mov  A,  bSensor
lcall CSA_bIsSensorActive
```

Parameters:

bSensor: Range is 0 to n-1, where n is the total of the number of sensors set in the CSA_EMC Wizard plus the number of sensors included in slider sensors.

Return Value:

Return value of 1 if active, 0 if not active

Side Effects:

**

CSA_bIsAnySensorActive

Description:

Checks the difference count array for all sensors compared to their finger threshold. Calls CSA_bIsSensorActive for each sensor so that the CSA_baSnsOnMask array is up to date after calling this function.

C Prototype:

```
BYTE  CSA_bIsAnySensorActive()
```

Assembly:

```
lcall CSA_bIsAnySensorActive
```

Parameters:

None

Return Value:

Return value of 1 if active, 0 if not active

Side Effects:

**

CSA_SetDefaultFingerThresholds

Description:

Loads the CSA_baBtnFThreshold array with the FingerThreshold parameter value. This function must be called before scanning if the CSA_baBtnFThreshold array is not manually loaded with custom values.

C Prototype:

```
void  CSA_SetDefaultFingerThresholds()
```

Assembly:

```
lcall CSA_SetDefaultFingerThresholds
```

Parameters:

None

Return Value:

None

Side Effects:

**

CSA_InitializeBaselines

Description:

Loads the CSA_waSnsBaseline array with initial values by scanning each sensor.

C Prototype:

```
void  CSA_InitializeBaselines()
```

Assembly:

```
lcall CSA_InitializeBaselines
```

Parameters:

None

Return Value:

None

Side Effects:

**

CSA_InitializeSensorBaseline

Description:

Loads the CSA_waSnsBaseline array with an initial value for a particular sensor. Used to reset the baseline for a particular sensor.

C Prototype:

```
void  CSA_InitializeSensorBaseline(BYTE bSensor)
```

Assembly:

```
lcall CSA_InitializeSensorBaseline
```

Parameters:

bSensor: Range is 0 to n-1, where n is the total of the number of sensors set in the CSA_EMC Wizard plus the number of sensors included in slider sensors.

Return Value:

None

Side Effects:

**

CSA_wGetCentroidPos

Description:

Checks a difference array for a centroid. If one exists, the offset and length are stored in temporary variables and the centroid position is calculated to the resolution specified in the CSA_EMC Wizard.

C Prototype:

```
WORD  CSA_wGetCentroidPos(BYTE bSnsGroup)
```

Assembly:

```
mov  A,  bSnsGroup
lcall CSA_wGetCentroidPos
```

Parameters:

bSnsGroup: Reference to a specific group of sensors used as a slider.

Return Value:

Position value of the slider, LSB in A and MSB in X.

Side Effects:

This routine modifies the difference counts by subtracting the noise threshold value. The routine should be called only once after each scan to avoid getting negative difference values. If your application monitors difference count signals, call this routine after difference count data transmission.

Note If noise counts on the slider segments are greater than the noise threshold, this subroutine may generate a false centroid result. The noise threshold should be set carefully (high enough above the noise level) so that noise does not generate a false centroid.

CSA_wGetRadialPos

Description:

Checks a difference array for a centroid. If one exists, the centroid position is calculated to the resolution specified in the CSA Wizard. This function is available only for radial slider that is defined by the CSA Wizard.

C Prototype:

```
WORD  CSA_wGetRadialPos(BYTE bSnsGroup)
```

Assembly:

```
mov  A,  bSnsGroup
lcall CSA_wGetRadialPos
```

Parameters:

bSnsGroup: This parameter is the number of the radial slider that you are working with. This number is shown by the CSA_EMC User Module wizard on the left side of radial slider representation (for example: for s2, the radial slider number is 2).

Return Value:

Position value of the radial slider, LSB in A and MSB in X.

Side Effects:

The routine should be called only once after each scan to avoid getting negative difference values and baseline update. If your application monitors difference count signals, call this routine after difference count data transmission.

If any slider sensor is active, the function returns values from zero to the Resolution value set in the CSA Wizard. If no sensors are active, the function returns -1 (FFFFh).

Note If noise counts on the slider segments are greater than the noise threshold, this subroutine may generate a false centroid result. The noise threshold should be set carefully (high enough above the noise level) so that noise does not generate a false centroid.

CSA_wGetRadialInc

Description:

Returns actual finger shift, the difference between current and previous finger positions. This function works with the CSA_wGetRadialPos() and takes data generated by the latter (data is saved in internal variables).

C Prototype:

```
WORD  CSA_wGetRadialInc(BYTE bSnsGroup)
```

Assembly:

```
mov  A,  bSnsGroup
lcall CSA_wGetRadialInc
```

Parameters:

bSnsGroup: This parameter is the number of the radial slider that you are working with. This number is shown by the CSA_EMC User Module wizard on the left side of radial slider representation (for example: for s2, the radial slider number is 2).

Return Value:

Finger shift value, positive if clockwise and negative if anti-clockwise, LSB in A and MSB in X.

Finger shift value is the difference between the current and previous finger positions. If there was no touch during the previous scan (the last but one time CSA_wGetRadialPos() returned -1 (FFFFh)) or there is no touch at the moment (this time CSA_wGetRadialPos() returned -1 (FFFFh)).

Side Effects:

The routine should be called only after the CSA_wGetRadialPos() API. This is because internal data CSA_waSliderPrevPos and CSA_waSliderCurrPos that are set by the CSA_wGetRadialPos() is used.

CSA_CalibrateSingleSensor

Description:

Performs successive approximation for the selected sensor to find the DAC setting that results in a result closest to the CalibratedRawCountLevel value.

C Prototype:

```
void CSA_CalibrateSingleSensor(BYTE bSensor, WORD CalibratedRawCountLevel)
```

Assembly:

```
mov A, >CalibratedRawCountLevel
```

```
push A ; wLevel (MSB) -> Stack
mov A, <CalibratedRawCountLevel
push A ; wLevel (LSB) -> Stack
mov A, bSensor
push A ; bSensor -> Stack
lcall CSA_CalibrateSingleSensor
```

Parameters:

[X - 3] => bSensor

[X - 4] => CalibratedRawCountLevelLSB

[X - 5] => CalibratedRawCountLevelMSB

Return Value:

None

Side Effects:

**

CSA_CalibrateAllSensors

Description:

Performs successive approximation for all sensors to find the DAC setting that results in a result closest to the CalibratedRawCountLevel value.

C Prototype:

```
void CSA_CalibrateAllSensors(WORD CalibratedRawCountLevel)
```

Assembly:

```
mov A, <CalibratedRawCountLevel
mov X, >CalibratedRawCountLevel
lcall CSA_CalibrateSingleSensor
```

Parameters:

A => CalibratedRawCountLevelLSB

X => CalibratedRawCountLevelMSB

Return Value:

None

Side Effects:

**

Sample Firmware Source Code

Scanning Buttons and Turning LEDs On and Off

This code is written for the CSA_EMC UCC board (CY3280-20x34) and Linear Slider Module board (CY3280-SLM):

```
//------ Sample code for CSA_EMC buttons that LEDs On and Off   ----------
//------     pin assignments for Linear Slider Module plugged   ---------
//-------     into CSA_EMC UCC board, CY3280-20x43+SLM            --------
```

```
#include <m8c.h>        //part specific constants and macros
#include "PSoCAPI.h"    //PSoC API definitions for all User Modules

void main(void)
{
//initialize LED states
  PRT0DR |= 0b00100010;  //turn-off LED on P0[5],P0[1]
PRT1DR |= 0b00000100;  //turn-off LED on P1[2]
PRT2DR |= 0b10100000;  //turn-off LED on P2[7],P2[5]

//Set port drive modes for LEDs
  PRT0DM0 |= 0b00100010;  //strong on P0[5],P0[1]
  PRT0DM1 &=~0b00100010;

  PRT1DM0 |= 0b10100100;  //strong on P1[2]
  PRT1DM1 &=~0b10100100;

PRT2DM0 |= 0b10100000;  //strong on P2[5],P2[7]
  PRT2DM1 &=~0b10100000;

M8C_EnableGInt;  //enable global interrupts for use with CSA_EMC

CSA_Start();     //initialize the CSA_EMC User Module
  CSA_SetDefaultFingerThresholds();   //Load finger thresholds
  CSA_InitializeBaselines();  //Set baselines to current count

  while(1)  //infinite loop scanning buttons
  {
    CSA_ScanAllSensors();    //sample all buttons and compute baselines

// control the LEDs using the sensor states.
// LED ON if active, OFF if not active.
// Check buttons in sequence.
    if (CSA_bIsSensorActive(0))
    {
      PRT1DR &= ~0b00000100;   //turn-on LED on P1[2]
    }
    else
    {
      PRT1DR |= 0b00000100;  //turn-off LED on P1[2]
    }
    if (CSA_bIsSensorActive(1))
    {
      PRT0DR &= ~0b00100000;  //turn-on LED on P0[5]
    }
    else
    {
      PRT0DR |= 0b00100000;  //turn-off LED on P0[5]
    }
    if (CSA_bIsSensorActive(2))
    {
      PRT0DR &= ~0b00000010;  //turn-on LED on P0[1]
    }
    else
```

```
    {
      PRT0DR |= 0b00000010;  //turn-off LED on P0[1]
    }
    if (CSA_bIsSensorActive(3))
    {
      PRT2DR &= ~0b10000000;  //turn-on LED on P2[7]
    }
    else
    {
      PRT2DR |= 0b10000000;  //turn-off LED on P2[7]
    }
    if (CSA_bIsSensorActive(4))
    {
      PRT2DR &= ~0b00100000;  //turn-on LED on P2[5]
    }
    else
    {
      PRT2DR |= 0b00100000;  //turn-off LED on P2[5]
    }
  }
}
```

Controlling LED Intensity Using a Linear Slider

This code is written for the CSA_EMC UCC board (CY3280-20x34) and Linear Slider Module board (CY3280-SLM).

```
//------ Sample code for CSA_EMC slider controlling LED intensity -------
//------   pin assignments for Linear Slider Module plugged   ----------
//-------  into CSA_EMC UCC board, CY3280-20x43+SLM               -------

#include <m8c.h>        // part specific constants and macros
#include "PSoCAPI.h"    // PSoC API definitions for all User Modules

int wCentroid = 0;  //estimated finger position; 0xffff for no finger
int wPos = 0;  //estimated finger position
int wLED_PWM; //controls LED intensity

void main(void)
{
//initialize LED states
  PRT0DR |= 0b00100010;  //turn-off LED on P0[5],P0[1]
PRT1DR |= 0b00000100;  //turn-off LED on P1[2]
PRT2DR |= 0b10100000;  //turn-off LED on P2[7],P2[5]

//Set port drive modes for LEDs
  PRT0DM0 |= 0b00100010;  //strong on P0[5],P0[1]
  PRT0DM1 &=~0b00100010;

  PRT1DM0 |= 0b10100100;  //strong on P1[2]
  PRT1DM1 &=~0b10100100;

PRT2DM0 |= 0b10100000;  //strong on P2[5],P2[7]
  PRT2DM1 &=~0b10100000;
```

```
M8C_EnableGInt;  //enable global interrupts for use with CSA_EMC

CSA_Start();     //initialize the CSA_EMC User Module
  CSA_SetDefaultFingerThresholds();   //Load finger thresholds
  CSA_InitializeBaselines();  //Set baselines to current count

  while(1)  //infinite loop scanning slider
  {
    CSA_ScanAllSensors(); //sample all sensorsand and compute baselines

    wCentroid = CSA_wGetCentroidPos(1); //estimated position
    if (wCentroid != 0xffff)  //0xffff means finger off slider
    {
      wPos = wCentroid;  //get position, range is 0 to 100
    }

if (wPos > 0)  //if position>0, then pulse all LEDs ON
    {
      PRT1DR &= ~0b00000100;  //turn-on LED on P1[2]
      PRT0DR &= ~0b00100000;  //turn-on LED on P0[5]
      PRT0DR &= ~0b00000010;  //turn-on LED on P0[1]
      PRT2DR &= ~0b10000000;  //turn-on LED on P2[7]
      PRT2DR &= ~0b00100000;  //turn-on LED on P2[5]

      for (wLED_PWM = 0; wLED_PWM < wPos*wPos/100; wLED_PWM++)
      {   //control LED pulse width by position^2
      }  //this control function looks nice

}
    // LED pulse ON is over for this period, turn all off
    PRT1DR |= 0b00000100;  //turn-off LED on P1[2]
    PRT0DR |= 0b00100000;  //turn-off LED on P0[5]
    PRT0DR |= 0b00000010;  //turn-off LED on P0[1]
    PRT2DR |= 0b10000000;  //turn-off LED on P2[7]
    PRT2DR |= 0b00100000;  //turn-off LED on P2[5]


}  //do next scan (while loop)
}
```

Further Reading

The following design guides are recommended after reading the CSD User Module datasheet. These documents are available on the Cypress Semiconductor website at www.cypress.com:

- Getting Started with CapSense
- CY8C20xx6A/H CapSense Design Guide
- CY8C21x34/B CapSense Design Guide
- CY8C20x34 CapSense Design Guide
- CY8CMBR2044 CapSense Design Guide

Version History

Version	Originator	Description
1.00	DHA	Initial version
1.10	DHA	1. Changed CSA_UpdateSensorBaseline API call in CSA_ProcessData with "lcall" instruction. 2. Updated minimum value of sensor count.

Version	Originator	Description
1.20	DHA	1. Transferred the DiplexTable from "AREA UserModules" to "AREA lit" to fix code compression issues. 2. Set the default "DiplexTable" parameter value to 0x0112 to fix build errors when the wizard was not run. 3. Added the "DiplexUsed" parameter to fix code compression issues. 4. Updated the CSA_EMC_Start() API to address Cmod connections. 5. Updated the CSA_EMC_ScanSingleSensor API to improve noise level. 6. Updated the CSA_EMC_ScanSingleSensor API to address stack overflow. 7. Updated IMO_SETTING on CY8C20x24 devices. 8. Updated the CSA_EMC_ScanSingleSensor() API address incorrect scanning results in case of CapSense counter Overflow. 9. Updated the prototype of the API function from "BYTE CSA_SetDefaultFingerThresholds()" to "void CSA_SetDefaultFingerThresholds()" in the API section.
1.30	DHA	1. Updated area declarations to support Imagecraft optimization. 2. Updated this user module datasheet to correct the IDDCS calculation. 3. Changed the sensor table name from "CSA_EMC_table.asm" to "CSA_EMCTABLE.asm" 4. Updated the InitializeSensorBaseline API to initialize the IIR Filter variable if the IIR Filter is not enabled with the Median Filter. 5. Updated the UpdateBaseline API for the right sensor offset. 6. Added missing default parameters values in this user module datasheet. 7. Updated the user module wizard help. Added a description of the slider resolution parameter min/max values. 8. Updated the resolution range calculation for Slider and Radial Slider in the user module wizard.
1.40	DHA	1. Added `@INSTANCE_NAME`_IMMUNITY_LEVEL constant. 2. Moved `@INSTANCE_NAME`_waSnsDiff and `@INSTANCE_NAME`_baLowBaselineReset to newly added RAM4 area. 3. Added CYRF89435 device support. 4. Added baSnsDebounce initialization to Start API. 5. Explained limitations of dynamic reconfiguration in user module datasheet.

Version	Originator	Description
1.50	MYKZ	1. Added Resume(), CalibrateSingleSensor(), and CalibrateAllSensors() functions to User Module API. 2. Fixed problem with saving information for sliders. 3. Added a build error message when the user attempts to build a project without first calling the user module wizard.

Note PSoC Designer 5.1 introduces a Version History in all user module datasheets. This section documents high level descriptions of the differences between the current and previous user module versions.

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