



Voice Mask MCU

HT83B60

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Features

- Operating voltage: 2.2V~5.5V
- System clock: 4MHz~12MHz
- Three oscillators:
 - ♦ External Crystal-HXT
 - ♦ External RC-ERC
 - ♦ Internal RC-HIRC
- Fully integrated internal HIRC 4MHz, 8MHz and 12MHz oscillators require no external components
- Up to 15 I/O pins
- Serial Interface Module- SIM for SPI or I²C, shared with PB
- Mask ROM: 2Kx16
- Data Memory: 208x8
- Voice ROM: 8M bits
- Two 8-bit programmable timer counter with 8-stage prescaler and one time base counter
- 12-bit high quality voltage type D/A output
- PWM circuit can directly drive speaker
- Watchdog Timer function
- 8-level subroutine nesting
- 2.7V Low voltage detection, tolerance 5%
- 2.2V Low voltage reset, tolerance 5%
- Power-down function and wake-up functions reduce power consumption
- 63 powerful instructions
- 28-pin SOP package

General Description

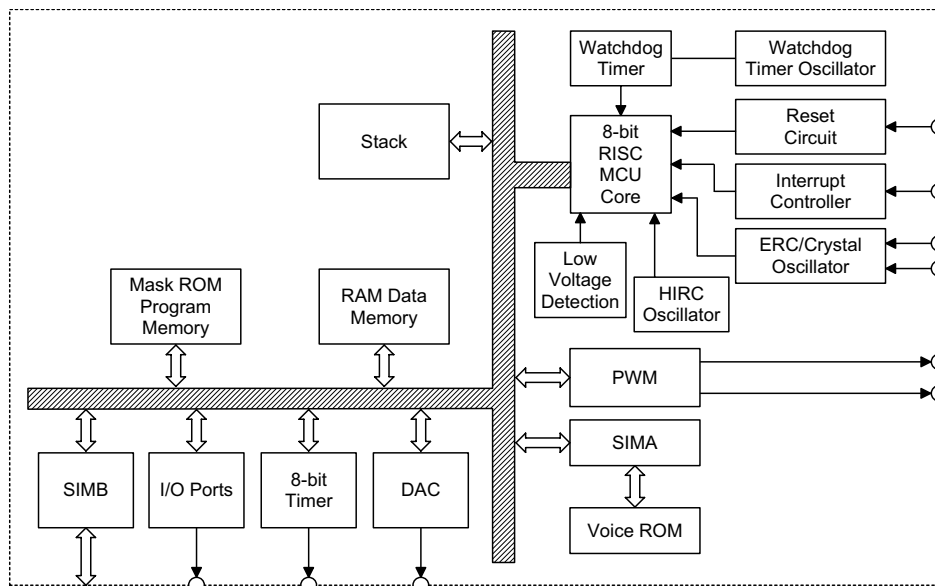
The HT83B60 is the Mask version of the HT83F02 but also includes an integrated 8M bits of Voice ROM, connected to the MCU by an internal SPI Serial Interface. This 8-bit high performance microcontroller includes a wide range of functions and special audio features which include a voice synthesizer and tone generator.

This device is designed for applications which require multiple I/Os and sound effects, such as voice and melody. It also includes an integrated high quality, voltage type DAC as well as a PWM generator.

This device will form an excellent solution for versatile voice and sound effect product applications with their efficient MCU instructions providing the user with programming capability for powerful custom applications. The system frequency can be up to 12MHz at an operating voltage of 5V and includes power-down functions to reduce power consumption. A full choice of oscillator functions are provided including a fully integrated system oscillator which requires no external components for its implementation.

Block Diagram

The following block diagram illustrates the main functional blocks.



Pin Assignment

PA1	□ 1	28	□ PA2
PA0	□ 2	27	□ PA3
PB0/SDOB/SDAB	□ 3	26	□ PA4
PB1/SCKB/SCLB	□ 4	25	□ PA5
PB2/SDIB	□ 5	24	□ PA6
*PB4/SDOA/SDAA	□ 6	23	□ PA7
*PB5/SCKA/SCLA	□ 7	22	□ VSS
*PB6/SDIA	□ 8	21	□ VDD
*PB7/SCSA	□ 9	20	□ VDD_PBIO
PC1/OSC1	□ 10	19	□ PC0/RES
PC2/OSC2	□ 11	18	□ VSSP
VSSA	□ 12	17	□ PWM2
AUD	□ 13	16	□ PWM1
VDDA	□ 14	15	□ VDDP

HT83B60
28 SOP-A

*: Note that the pins, SDOA, SDIA, SCKA and SCSAB, are dedicated for control of the internal voice memory and should not be used for other functions. Care should be taken regarding these pin-shared I/O pin settings and no external connections should be made to these pins.

Pin Description

Pin Name	Function	OPT	I/T	O/T	Description
PA0~PA7	PAn	CO	ST	CMOS	General purpose I/O. Configuration option determined pull-high resistors and wake up function.
PB0/SDOB/SDAB	PB0	CO	ST	CMOS	General purpose I/O. Configuration option determined pull-high resistors.
	SDOB	CO	-	CMOS	SIMB SPI data output pin
	SDAB	CO	ST	CMOS	SIMB I ² C data pin
PB1/SCKB/SCLB	PB1	CO	ST	CMOS	General purpose I/O. Configuration option enabled pull-up. Software instructions determine if the pin is a CMOS output or Schmitt trigger input.
	SCKB	CO	ST	CMOS	SIMB SPI clock pin
	SCLB	CO	ST	CMOS	SIMB I ² C clock pin
PB2/SDIB	PB2	CO	ST	CMOS	General purpose I/O. Configuration option enabled pull-up. Software instructions determine if the pin is a CMOS output or Schmitt trigger input.
	SDIB	CO	ST	-	SIMB SPI data input pin
PB4/SDOA/SDAA	PB4	CO	ST	CMOS	Internal voice memory control pin. PB4 should be selected as input pin by software instructions and disable the internal pull up by configuration option and select as SIMA SPIA data output pin, SDOA. Should be left no external connection.
	SDOA	CO	-	CMOS	
	SDAA	CO	STI	CMOS	
PB5/SCKA/SCLA	PB5	CO	ST	CMOS	Internal voice memory control pin. PB5 should be selected as input pin by software instructions and enable the internal pull up by configuration option and select SIMA SPI clock output pin, SCKA. Should be left no external connection.
	SCKA	CO	ST	CMOS	
	SCLA	CO	ST	CMOS	
PB6/SDIA	PB6	CO	ST	CMOS	Internal voice memory control pin. PB6 should be selected as input pin by software instructions and enable the internal pull up by configuration option and select SIMA SPI data input pin, SDIA. Should be left no external connection.
	SDIA	CO	ST	-	
PB7/SCSAB	PB7	CO	ST	CMOS	Internal voice memory control pin. PB7 should be selected as input pin by software instructions and enable the internal pull up by configuration option and select SIMA SPI Slave select pin, SCSAB. Should be left no external connection.
	SCSAB	CO	ST	-	
PC0/ $\overline{\text{RES}}$	PC0	PCPHC	ST	CMOS	General purpose I/O. Register enabled pull-up.
	$\overline{\text{RES}}$	CO	ST	-	Reset pin
PC1/OSC1	PC1	PCPHC	ST	CMOS	General purpose I/O. Register enabled pull-up
	OSC1	CO	HXT	-	
PC2/OSC2	PC2	PCPHC	ST	CMOS	General purpose I/O. Register enabled pull-up
	OSC2	CO	-	HXT	
AUD	DAC output	-	-	CMOS	DAC output
PWM1,PWM2	PWMn	-	-	CMOS	PWM circuit direct drive speaker
VDD_PBIO	PB power supply	-	PWR	-	PB I/O external positive power supply, determine by option.

Pin Name	Function	OPT	I/T	O/T	Description
VDDA	DAC power supply	-	PWR	-	Positive DAC circuit Power supply
VDDP	PWM power supply	-	PWR	-	PWM positive power supply
VSSA	Ground	-	PWR	-	Negative DAC circuit power supply, ground
VSSP	PWM ground	-	PWR	-	PWM negative power supply, ground

Note: I/T: Input type
O/T: Output type
OPT: Optional by configuration option (CO) or register option
PWR: Power
CO: Configuration option
ST: Schmitt Trigger input
CMOS: CMOS output

Absolute Maximum Ratings

Supply Voltage $V_{SS}-0.3V$ to $V_{SS}+6.0V$ Storage Temperature $-50^{\circ}C$ to $125^{\circ}C$
Input Voltage $V_{SS}-0.3V$ to $V_{DD}+0.3V$ Operating Temperature $-40^{\circ}C$ to $85^{\circ}C$
 I_{OL} Total 100mA I_{OH} Total -100mA
Total Power Dissipation 500mW

Note: These are stress ratings only. Stresses exceeding the range specified under “Absolute Maximum Ratings” may cause substantial damage to the device. Functional operation of this device at other conditions beyond those listed in the specification is not implied and prolonged exposure to extreme conditions may affect device reliability.

D.C. Characteristics

 $T_a=25^{\circ}C$

Symbol	Parameter	Test Conditions		Min.	Typ.	Max.	Unit
		V_{DD}	Conditions				
V_{DD1}	Operating Voltage (Crystal OSC)	—	$f_{SYS}=8MHz$	2.2	—	5.5	V
			$f_{SYS}=10MHz$	2.7	—	5.5	V
			$f_{SYS}=12MHz$	3.3	—	5.5	V
V_{DD2}	Operating Voltage (External RC OSC)	—	$f_{SYS}=6MHz$	2.2	—	5.5	V
			$f_{SYS}=8MHz$	2.7	—	5.5	V
			$f_{SYS}=12MHz$	2.7	—	5.5	V
V_{DD3}	Operating Voltage (High Frequency Internal RC OSC)	—	$f_{SYS}=8MHz$	2.2	—	5.5	V
			$f_{SYS}=12MHz$	2.7	—	5.5	V
I_{DD1}	Operating Current (Crystal OSC, $f_{SYS}=f_H$)	3V	No load, $f_H=8MHz$, WDT enable	—	1.0	2.0	mA
		5V		—	2.7	4.5	mA
		3V	No load, $f_H=10MHz$, WDT enable	—	1.2	2.5	mA
		5V		—	3.3	6.5	mA
		3V	No load, $f_H=12MHz$, WDT enable	—	1.4	3.5	mA
		5V		—	3.9	10.0	mA

Symbol	Parameter	Test Conditions		Min.	Typ.	Max.	Unit
		V _{DD}	Conditions				
I _{DD2}	Operating Current (ERC OSC, f _{sys} =f _H)	3V	No load, f _H =6MHz, WDT enable	—	0.9	2.0	mA
		5V		—	2.2	4.0	mA
		3V	No load, f _H =8MHz, WDT enable	—	1.1	2.5	mA
		5V		—	2.9	6.5	mA
		3V	No load, f _H =12MHz, WDT enable	—	1.5	3.5	mA
		5V		—	4.1	8.0	mA
I _{DD3}	Operating Current (HIRC OSC, f _{sys} =f _H)	3V	No load, f _H =4MHz, WDT enable	—	0.7	2.0	mA
		5V		—	1.6	3.5	mA
		3V	No load, f _H =8MHz, WDT enable	—	1.2	2.5	mA
		5V		—	3.2	7.0	mA
		3V	No load, f _H =12MHz, WDT enable	—	1.8	4.0	mA
		5V		—	4.3	8.5	mA
I _{STB1}	Standby Current (Idle) (Crystal, ERC, HIRC OSC)	3V	No load, system HALT, WDT enable, f _{sys} =12MHz	—	1.2	5.5	μA
		5V		—	4.5	11.0	μA
I _{STB2}	Standby Current (Idle) (Crystal, ERC, HIRC OSC)	3V	No load, system HALT, WDT disable, f _{sys} =12MHz	—	0.2	1.0	μA
		5V		—	0.6	2.0	μA
I _{OL1}	I/O Port Sink Current	3V	V _{OL} =0.1V _{DD}	5.5	10	—	mA
		5V		9.5	20	—	mA
I _{OH1}	I/O Port Source Current	3V	V _{OH} =0.9V _{DD}	-2.5	-5	—	mA
		5V		-10	-15	—	mA
I _{OL2}	PWM1/PWM2 Sink Current	3V	V _{OL} =0.1V _{DD}	60	85	—	mA
		5V		135	195	—	mA
I _{OH2}	PWM1/PWM2 Source Current	3V	V _{OH} =0.9V _{DD}	-38	-55	—	mA
		5V		-80	-115	—	mA
V _{IL1}	Input Low Voltage for I/O Ports	—	—	0	—	0.3V _{DD}	V
V _{IH1}	Input High Voltage for I/O Ports	—	—	0.7V _{DD}	—	V _{DD}	V
V _{IL2}	Input Low Voltage(RES)	—	—	0	—	0.4V _{DD}	V
V _{IH2}	Input High Voltage(RES)	—	—	0.9V _{DD}	—	V _{DD}	V
R _{PH}	Pull-high Resistance	3V	—	30	100	170	kΩ
		5V		10	35	60	kΩ
I _{AUD}	AUD current source	3V	V _{OH} =0.9V _{DD}	—	-4.5	—	mA
		5V	V _{OH} =0.9V _{DD}	—	-10	—	mA
V _{LVR}	Low Voltage Reset Voltage	—	LVR 2.2V option	2.090	2.2	2.310	V
V _{LVD}	Low Voltage Reset Voltage	—	LVD 2.7V option	2.565	2.7	2.835	V

A.C. Characteristics

Ta=25°C

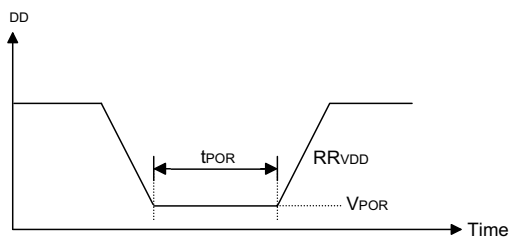
Symbol	Parameter	Test Conditions		Min.	Typ.	Max.	Unit
		V _{DD}	Conditions				
f _{SYS1}	System clock (Crystal OSC)	2.2~5.5V	—	2	—	8	MHz
		2.7~5.5V	—	2	—	10	MHz
		3.3~5.5V	—	2	—	12	MHz
f _{SYS2}	System clock (External RC OSC)	5.0V	Ta=25°C, External R _{ERC} =120kΩ*	-2%×Typ.	8	+2%×Typ.	MHz
f _{SYS3}	System clock (HI RC OSC)	5.0V	Ta=25°C	-2%×Typ.	8	+2%×Typ.	MHz
t _{RES}	External Reset Low Pulse Width	—	—	1	—	—	μs
t _{SST}	System Start-up time Period (Wake-up from HALT)	—	f _{SYS} =XTAL	—	1024	—	t _{SYS}
			f _{SYS} =ERC or HIRC OSC	—	15~16	—	t _{SYS}
			—	1	—	—	t _{SYS}
t _{INT}	Interrupt Pulse Width	—	—	7	—	8	t _{SUB}
t _{LV}	Low Voltage Width to Reset	—	—	350	880	1300	μs
t _{LVD}	LVD Time	—	—	15	—	—	μs

 Note: t_{SYS}=1/f_{SYS}; t_{SUB}=1/f_{SUB}

Power-on Reset Characteristics

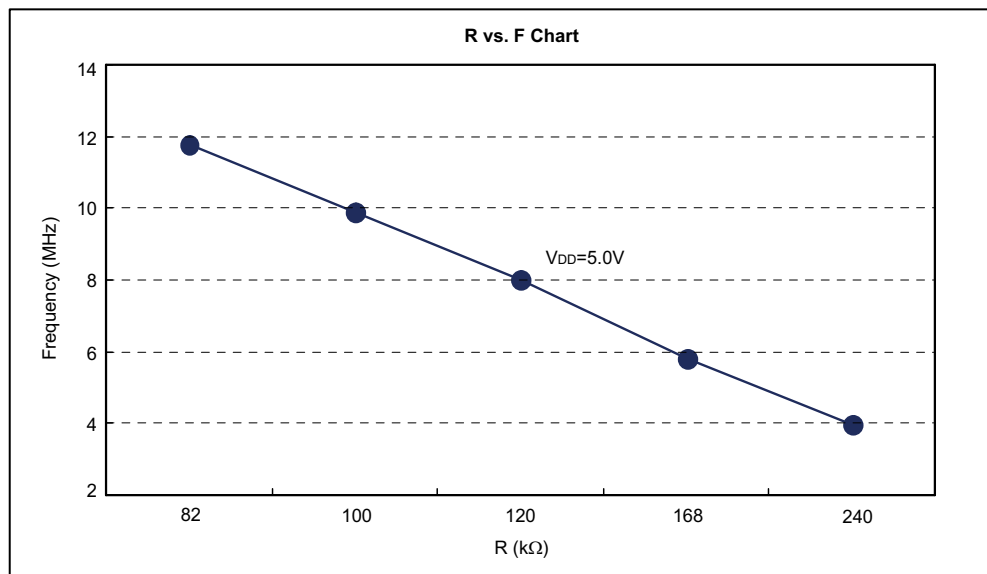
Ta=25°C

Symbol	Parameter	Test Conditions		Min.	Typ.	Max.	Unit
		V _{DD}	Conditions				
V _{POR}	VDD Start Voltage to Ensure Power-on Reset	—	—	—	—	100	mV
RR _{VDD}	VDD Rise Rate to Ensure Power-on Reset	—	—	0.035	—	—	V/ms
t _{POR}	Minimum Time for VDD to Remain at V _{POR} to Ensure Power-on Reset	—	—	1	—	—	ms

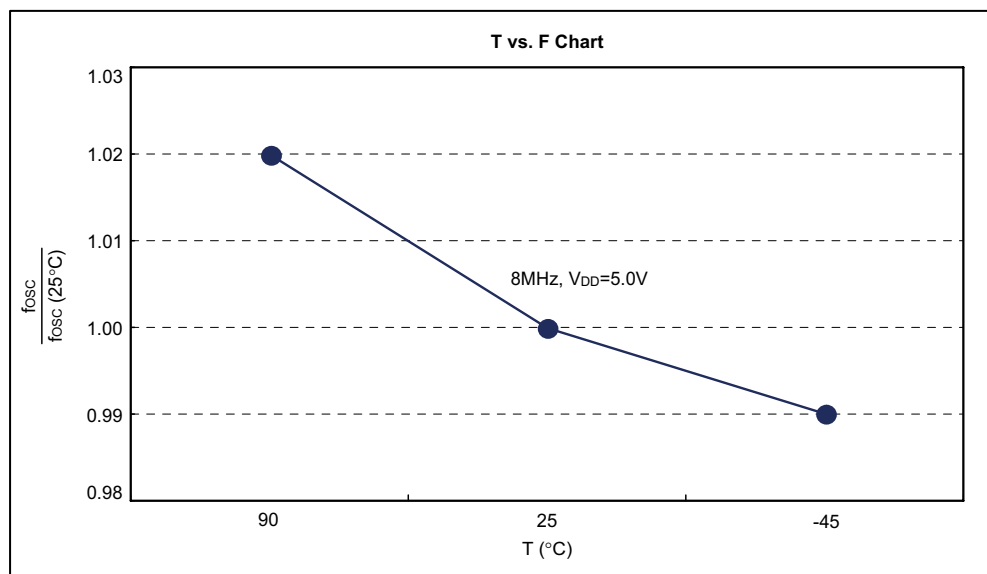


Characteristics Curves

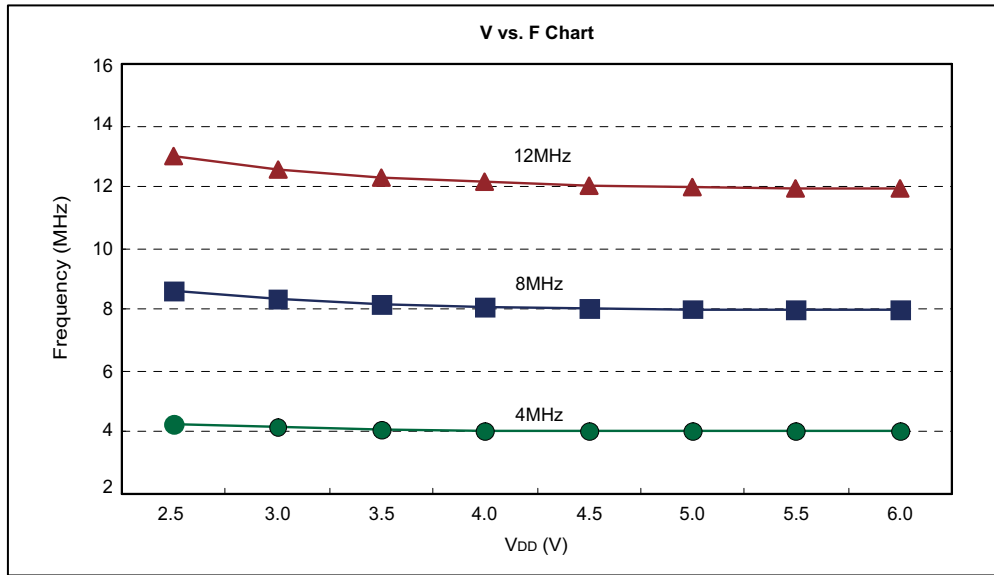
R vs. F (External RC) Chart Characteristics Curve at 25°C



T vs. F (External RC) Chart Characteristics Curve



V vs. F (HIRC) Chart Characteristics Curve at 25°C – Trimmed at 5V



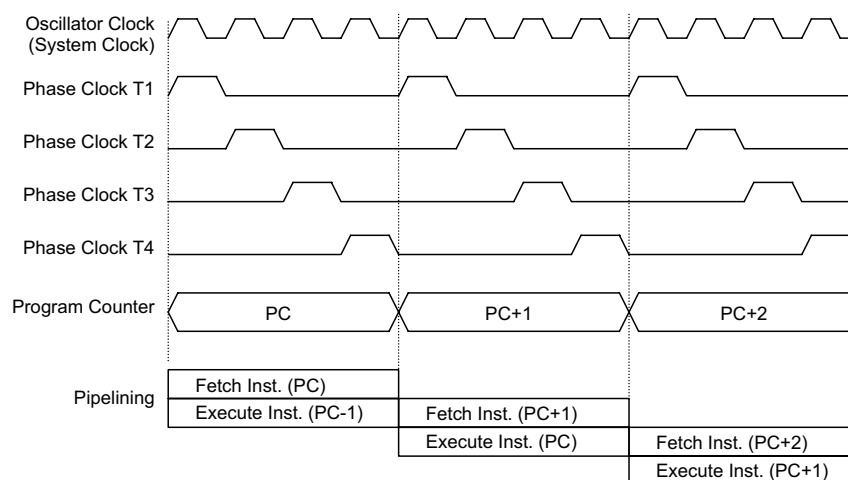
System Architecture

A key factor in the high-performance features of the Holtek range of microcontrollers is attributed to the internal system architecture. The range of devices take advantage of the usual features found within RISC microcontrollers providing increased speed of operation and enhanced performance. The pipelining scheme is implemented in such a way that instruction fetching and instruction execution are overlapped, hence instructions are effectively executed in one cycle, with the exception of branch or call instructions. An 8-bit wide ALU is used in practically all operations of the instruction set. It carries out arithmetic operations, logic operations, rotation, increment, decrement, branch decisions, etc. The internal data path is simplified by moving data through the Accumulator and the ALU. Certain internal registers are implemented in the Data Memory and can be directly or indirectly addressed. The simple addressing methods of these registers along with additional architectural features ensure that a minimum of external components is required to provide a functional I/O control system with maximum reliability and flexibility.

Clocking and Pipelining

The main system clock, derived from either a Crystal, ERC or IRC oscillator, is subdivided into four internally generated non-overlapping clocks, T1~T4. The Program Counter is incremented at the beginning of the T1 clock during which time a new instruction is fetched. The remaining T2~T4 clocks carry out the decoding and execution functions. In this way, one T1~T4 clock cycle forms one instruction cycle. Although the fetching and execution of instructions takes place in consecutive instruction cycles, the pipelining structure of the microcontroller ensures that instructions are effectively executed in one instruction cycle. The exception to this are instructions where the contents of the Program Counter are changed, such as subroutine calls or jumps, in which case the instruction will take one more instruction cycle to execute.

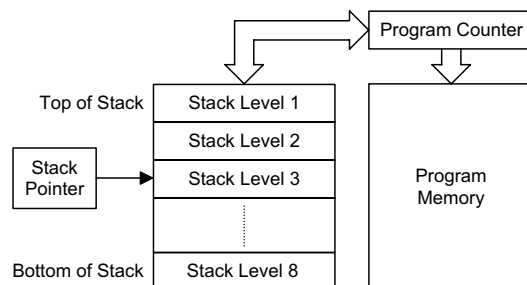
For instructions involving branches, such as jump or call instructions, two machine cycles are required to complete instruction execution. An extra cycle is required as the program takes one cycle to first obtain the actual jump or call address and then another cycle to actually execute the branch. The requirement for this extra cycle should be taken into account by programmers in timing sensitive applications.



System Clocking and Pipelining

Stack

This is a special part of the memory which is used to save the contents of the Program Counter only. The stack has 8 levels and is neither part of the data nor part of the program space, and can neither be read from nor written to. The activated level is indexed by the Stack Pointer, SP, which can also neither be read from nor written to. At a subroutine call or interrupt acknowledge signal, the contents of the Program Counter are pushed onto the stack. At the end of a subroutine or an interrupt routine, signaled by a return instruction, RET or RETI, the Program Counter is restored to its previous value from the stack. After a device reset, the Stack Pointer will point to the top of the stack.



If the stack is full and an enabled interrupt takes place, the interrupt request flag will be recorded but the acknowledge signal will be inhibited. When the Stack Pointer is decremented, by RET or RETI, the interrupt will be serviced. This feature prevents stack overflow allowing the programmer to use the structure more easily. However, when the stack is full, a CALL subroutine instruction can still be executed which will result in a stack overflow. Precautions should be taken to avoid such cases, which might cause unpredictable program branching.

Arithmetic and Logic Unit – ALU

The arithmetic-logic unit or ALU is a critical area of the microcontroller that carries out arithmetic and logic operations of the instruction set. Connected to the main microcontroller data bus, the ALU receives related instruction codes and performs the required arithmetic or logical operations after which the result will be placed in the specified register. As these ALU calculation or operations may result in carry, borrow or other status changes, the status register will be correspondingly updated to reflect these changes. The ALU supports the following functions:

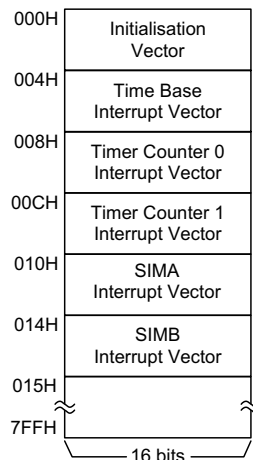
- Arithmetic operations ADD, ADDM, ADC, ADCM, SUB, SUBM, SBC, SBCM, DAA
- Logic operations AND, OR, XOR, ANDM, ORM, XORM, CPL, CPLA
- Rotation RRA, RR, RRCA, RRC, RLA, RL, RLCA, RLC
- Increment and Decrement INCA, INC, DECA, DEC Branch decision JMP, SZ, SZA, SNZ, SIZ, SDZ, SIZA, SDZA, CALL, RET, RETI

Program Memory

The Program Memory is the location where the user code or program is stored. For this device, the Program Memory is Mask type.

Structure

The Program Memory has a capacity of 2K by 16 bits. The Program Memory is addressed by the Program Counter and also contains data, table information and interrupt entries. Table data, which can be setup in any location within the Program Memory, is addressed by separate table pointer registers.



Special Vectors

Within the Program Memory, certain locations are reserved for special usage such as reset and interrupts.

Reset Vector

This vector is reserved for use by the device reset for program initialisation. After a device reset is initiated, the program will jump to this location and begin execution.

External Interrupt Vector

This vector is used by the external interrupt. If the external interrupt pin on the device goes low, the program will jump to this location and begin execution if the external interrupt is enabled and the stack is not full.

Timer Counter 0 Interrupt Vector

This vector is used by the 8-bit Timer 0. If a overflow occurs, the program will jump to this location and begin execution if the timer interrupt is enabled and the stack is not full.

Timer Counter 1 Interrupt Vector

This vector is used by the 8-bit Timer 1. If a overflow occurs, the program will jump to this location and begin execution if the timer interrupt is enabled and the stack is not full.

SIMA Interrupt Vector

This vector is used by the SIMA Bus interrupt service program. If the SIMA Bus interrupt resulting from a slave address is matched or if 8 bits of data have been received or transmitted successfully from the I²C interface, or 8 bits of data have been received or transmitted successful from SPI interface, the program will jump to this location and begin execution if the interrupt is enabled and the stack is not full.

SIMB Interrupt Vector

This vector is used by the SIMB Bus interrupt service program. If the SIMB Bus interrupt resulting from a slave address is matched or if 8 bits of data have been received or transmitted successfully from the I²C interface, or 8 bits of data have been received or transmitted successful from SPI interface, the program will jump to this location and begin execution if the interrupt is enabled and the stack is not full.

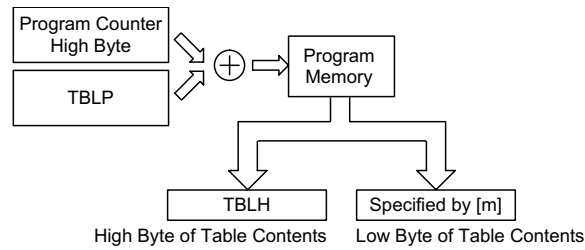
Look-up Table

Any location within the Program Memory can be defined as a look-up table where programmers can store fixed data. To use the look-up table, the table pointers are used to setup the address of the data that is to be accessed from the Program Memory. However, as some devices possess only a low byte table pointer and other devices possess both a high and low byte pointer it should be noted that depending upon which device is used, accessing look-up table data is implemented in slightly different ways.

There are two Table Pointer Registers known as TBLP and TBHP in which the lower order and higher order address of the look-up data to be retrieved must be respectively first written. The additional TBHP register allows the complete address of the look-up table to be defined and consequently allow table data from any address and any page to be directly accessed. For this device, after setting up both the low and high byte table pointers, the table data can then be retrieved from any area of Program Memory using the "TABRDC [m]" instruction or from the last page of the Program Memory using the "TABRDL [m]" instruction. When either of these instructions are executed, the lower order table byte from the Program Memory will be transferred to the user defined Data Memory register [m] as specified in the instruction. The higher order table data byte from the Program Memory will be transferred to the TBLH special register.

Any unused bits in this transferred higher order byte will be read as "0".

The following diagram illustrates the addressing/data flow of the look-up table.



Look-up Table

Table Program Example

The following example shows how the table pointer and table data is defined and retrieved from the devices. This example uses raw table data located in the last page which is stored there using the ORG statement. The value at this ORG statement is "700H" which refers to the start address of the last page within the 2048x16-bit Program Memory of the microcontroller. The table pointer is setup here to have an initial value of "06H" This will ensure that the first data read from the data table will be at the Program Memory address "706H" or 6 locations after the start of the last page.

Note that the value for the table pointer is referenced to the first address of the present page if the "TABRDC[m]" instruction is being used. The high byte of the table data which in this case is equal to zero will be transferred to the TBLH register automatically when the "TABRDL [m]" instruction is executed.

Instruction	Table Location Bits										
	*10	*9	*8	*7	*6	*5	*4	*3	*2	*1	*0
TABRDC [m]	PC10	PC9	PC8	@7	@6	@5	@4	@3	@2	@1	@0
TABRDL [m]	1	1	1	@7	@6	@5	@4	@3	@2	@1	@0

Table Location

- Note: *10~*0: Current Program ROM table
 P10~P8: Write P12~P8 to TBHP pointer register
 @7~@0: Write @7~@0 to TBLP pointer register

Table Read Program Example

```
tempreg1 db ? ; temporary register #1
tempreg2 db ? ; temporary register #2
:
:

mov a,06h ; initialise table pointer - note that this address is referenced

mov tblp,a ; to the last page or present page
:
:

tabrdl tempreg1 ; transfers value in table referenced by table pointer to tempreg1
; data at prog. memory address "706H" transferred to tempreg1 and TBLH

dec tblp ; reduce value of table pointer by one

tabrdl tempreg2 ; transfers value in table referenced by table pointer to tempreg2
; data at prog.memory address "705H" transferred to tempreg2 and TBLH
; in this example the data "1AH" is transferred to
; tempreg1 and data "0FH" to register tempreg2
; the value "00H" will be transferred to the high byte register TBLH
:
:

org 700h ; sets initial address of the last page

dc 00Ah, 00Bh, 00Ch, 00Dh, 00Eh, 00Fh, 01Ah, 01Bh
:
:
```

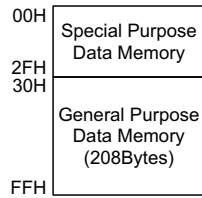
Data Memory

The Data Memory is a volatile area of 8-bit wide RAM internal memory and is the location where temporary information is stored. Divided into two sections, the first of these is an area of RAM where special function registers are located. These registers have fixed locations and are necessary for correct operation of the device. Many of these registers can be read from and written to directly under program control, however, some remain protected from user manipulation. The second area of RAM Data Memory is reserved for general purpose use. All locations within this area are read and write accessible under program control.

Structure

The Data Memory has a bank, known as Bank, which is implemented in 8-bit wide RAM. The RAM Data Memory is located in Bank 0 which is also subdivided into two sections, the Special Purpose Data Memory and the General Purpose Data Memory. The length of these sections is dictated by the type of microcontroller chosen.

The start address of the RAM Data Memory for all devices is the address "00H" and the last Data Memory address is "FFH" Registers which are common to all microcontrollers, such as ACC, PCL, etc., have the same Data Memory address.



RAM Data Memory Structure

Note: Most of the Data Memory bits can be directly manipulated using the “SET [m].i” and “CLR [m].i” with the exception of a few dedicated bits. The Data Memory can also be accessed through the memory pointer registers.

General Purpose Data Memory

All microcontroller programs require an area of read/write memory where temporary data can be stored and retrieved for use later. It is this area of RAM memory that is known as General Purpose Data Memory. This area of Data Memory is fully accessible by the user program for both read and write operations. By using the "SET [m].i" and "CLR [m].i" instructions individual bits can be set or reset under program control giving the user a large range of flexibility for bit manipulation in the Data Memory.

Special Purpose Data Memory

This area of Data Memory, is located in Bank, where registers, necessary for the correct operation of the microcontroller, are stored. Most of the registers are both readable and writable but some are protected and are readable only, the details of which are located under the relevant Special Function Register section. Note that for locations that are unused, any read instruction to these addresses will return the value "00H".

Special Function Registers

To ensure successful operation of the microcontroller, certain internal registers are implemented in the Data Memory area. These registers ensure correct operation of internal functions such as timers, interrupts, etc., as well as external functions such as I/O data control. The location of these registers within the Data Memory begins at the address "00H". Any unused Data Memory locations between these special function registers and the point where the General Purpose Memory begins is reserved and attempting to read data from these locations will return a value of "00H".

Indirect Addressing Registers – IAR0

The Indirect Addressing Registers, IAR0, although having their locations in normal RAM register space, do not actually physically exist as normal registers. The method of indirect addressing for RAM data manipulation uses these Indirect Addressing Registers and Memory Pointers, in contrast to direct memory addressing, where the actual memory address is specified. Actions on the IAR0 registers will result in no actual read or write operation to these registers but rather to the memory location specified by their corresponding Memory Pointer, MP0. As the Indirect Addressing Registers are not physically implemented, reading the Indirect Addressing Registers indirectly will return a result of "00H" and writing to the registers indirectly will result in no operation.

00H	IAR0
01H	MP0
02H	
03H	
04H	
05H	ACC
06H	PCL
07H	TBLP
08H	TBLH
09H	WDTs
0AH	STATUS
0BH	INTC
0CH	
0DH	TMR0
0EH	TMR0C
0FH	
10H	TMR1
11H	TMR1C
12H	PA
13H	PAC
14H	PB
15H	PBC
16H	PC
17H	PCC
18H	
19H	
1AH	
1BH	
1CH	
1DH	
1EH	INTCH
1FH	
20H	SIMC0B
21H	SIMC1B
22H	SIMDRB
23H	SIMARB/SIMC2B
24H	DAL
25H	DAH
26H	PWMC
27H	PWML
28H	PWMH
29H	VOL
2AH	
2BH	SIMC0A
2CH	SIMC1A
2DH	SIMDRA
2EH	SIMARA/SIMC2A
2FH	PCPHC
30H	User Data RAM
...	
FFH	

■ : Unused, read as "00"

Special Purpose Data Memory Structure

Indirect Addressing Program Example

The following example shows how to clear a section of four Data Memory locations already defined as locations `adres1` to `adres4`.

```
data .section 'data'
adres1 db ?
adres2 db ?
adres3 db ?
adres4 db ?
block db ?
code .section at 0 code
org 00h

start:
    mov a,04h                ; setup size of block
    mov block,a
    mov a,offset adres1     ; Accumulator loaded with first RAM address
    mov mp0,a               ; setup memory pointer with first RAM address

loop:
    clr IAR0                ; clear the data at address defined by MP0
    inc mp0                 ; increment memory pointer
    sdz block               ; check if last memory location has been cleared
    jmp loop

continue:
```

The important point to note here is that in the example shown above, no reference is made to specific Data Memory addresses.

Memory Pointers – MP0

For all devices, two Memory Pointers, known as MP0 is provided. These Memory Pointers are physically implemented in the Data Memory and can be manipulated in the same way as normal registers providing a convenient way with which to address and track data. When any operation to the relevant Indirect Addressing Registers is carried out, the actual address that the microcontroller is directed to, is the address specified by the related Memory Pointer.

Accumulator – ACC

The Accumulator is central to the operation of any microcontroller and is closely related with operations carried out by the ALU. The Accumulator is the place where all intermediate results from the ALU are stored. Without the Accumulator it would be necessary to write the result of each calculation or logical operation such as addition, subtraction, shift, etc., to the Data Memory resulting in higher programming and timing overheads. Data transfer operations usually involve the temporary storage function of the Accumulator; for example, when transferring data between one user defined register and another, it is necessary to do this by passing the data through the Accumulator as no direct transfer between two registers is permitted.

Program Counter Low Register – PCL

To provide additional program control functions, the low byte of the Program Counter is made accessible to programmers by locating it within the Special Purpose area of the Data Memory. By manipulating this register, direct jumps to other program locations are easily implemented. Loading a value directly into this PCL register will cause a jump to the specified Program Memory location, however, as the register is only 8-bit wide, only jumps within the current Program Memory page are permitted. When such operations are used, note that a dummy cycle will be inserted.

Look-up Table Registers - TBLP, TBLH

These two special function registers are used to control operation of the look-up table, which is stored in the Program Memory. TBLP is the table pointer and indicates the location where the table data is located. Its value must be setup before any table read commands are executed. Its value can be changed, for example using the "INC" or "DEC" instructions, allowing for easy table data pointing and reading. TBLH is the location where the high order byte of the table data is stored after a table read data instruction has been executed. Note that the lower order table data byte is transferred to a user defined location.

Watchdog Timer Register - WDTS

The Watchdog feature of the microcontroller provides an automatic reset function giving the microcontroller a means of protection against spurious jumps to incorrect Program Memory addresses. To implement this, a timer is provided within the microcontroller which will issue a reset command when its value overflows. To provide variable Watchdog Timer reset times, the Watchdog Timer clock source can be divided by various division ratios, the value of which is set using the WDTS register. By writing directly to this register, the appropriate division ratio for the Watchdog Timer clock source can be setup. Note that only the lower 3 bits are used to set division ratios between 1 and 128.

Status Register – STATUS

This 8-bit register contains the zero flag (Z), carry flag (C), auxiliary carry flag (AC), overflow flag (OV), power down flag (PDF), and watchdog time-out flag (TO). These arithmetic/logical operation and system management flags are used to record the status and operation of the microcontroller.

With the exception of the TO and PDF flags, bits in the status register can be altered by instructions like most other registers. Any data written into the status register will not change the TO or PDF flag. In addition, operations related to the status register may give different results due to the different instruction operations. The TO flag can be affected only by a system power-up, a WDT time-out or by executing the "CLR WDT" or "HALT" instruction. The PDF flag is affected only by executing the "HALT" or "CLR WDT" instruction or during a system power-up.

The Z, OV, AC and C flags generally reflect the status of the latest operations.

In addition, on entering an interrupt sequence or executing a subroutine call, the status register will not be pushed onto the stack automatically. If the contents of the status registers are important and if the interrupt routine can change the status register, precautions must be taken to correctly save it.

STATUS Register

Bit	7	6	5	4	3	2	1	0
Name	—	—	TO	PDF	OV	Z	AC	C
R/W	—	—	R	R	R/W	R/W	R/W	R/W
POR	—	—	0	0	x	x	x	x

"X" unknown

- Bit 7, 6 Unimplemented, read as "0"
- Bit 5 **TO**: Watchdog Time-Out flag
0: After power up or executing the "CLR WDT" or "HALT" instruction
1: A watchdog time-out occurred.
- Bit 4 **PDF**: Power down flag
0: After power up or executing the "CLR WDT" instruction
1: By executing the "HALT" instruction
- Bit 3 **OV**: Overflow flag
0: no overflow
1: an operation results in a carry into the highest-order bit but not a carry out of the highest-order bit or vice versa.
- Bit 2 **Z**: Zero flag
0: The result of an arithmetic or logical operation is not zero
1: The result of an arithmetic or logical operation is zero
- Bit 1 **AC**: Auxiliary flag
0: no auxiliary carry
1: an operation results in a carry out of the low nibbles in addition, or no borrow from the high nibble into the low nibble in subtraction
- Bit 0 **C**: Carry flag
0: no carry-out
1: an operation results in a carry during an addition operation or if a borrow does not take place during a subtraction operation
C is also affected by a rotate through carry instruction.

Interrupt Control Register - INTC, INTCH

Two 8-bit register, known as the INTC and INTCH registers, controls the operation of both external and internal timer interrupts. By setting various bits within these registers using standard bit manipulation instructions, the enable/disable function of the external and timer interrupts can be independently controlled. A master interrupt bit within this register, the EMI bit, acts like a global enable/disable and is used to set all of the interrupt enable bits on or off. This bit is cleared when an interrupt routine is entered to disable further interrupt and is set by executing the "RETI" instruction.

Note: In situations where other interrupts may require servicing within present interrupt service routines, the EMI bit can be manually set by the program after the present interrupt service routine has been entered.

Timer Registers

All devices contain two 8-bit Timers whose associated registers are known as TMR0 and TMR1 which is the location where the associated timer's 8-bit value is located. Their associated control registers, known as TMR0C and TMR1C, contain the setup information for these timers.

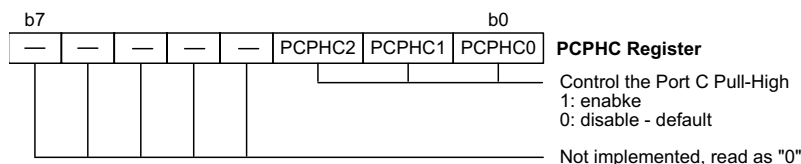
Note that all timer registers can be directly written to in order to preload their contents with fixed data to allow different time intervals to be setup.

Input/Output Ports and Control Registers

Within the area of Special Function Registers, the I/O registers and their associated control registers play a prominent role. All I/O ports have a designated register correspondingly labeled as PA, PB and PC. These labeled I/O registers are mapped to specific addresses within the Data Memory as shown in the Data Memory table, which are used to transfer the appropriate output or input data on that port. With each I/O port there is an associated control register labeled PAC, PBC and PCC, also mapped to specific addresses with the Data Memory. The control register specifies which pins of that port are set as inputs and which are set as outputs. To setup a pin as an input, the corresponding bit of the control register must be set high, for an output it must be set low. During program initialization, it is important to first setup the control registers to specify which pins are outputs and which are inputs before reading data from or writing data to the I/O ports. One flexible feature of these registers is the ability to directly program single bits using the "SET [m].i" and "CLR [m].i" instructions. The ability to change I/O pins from output to input and vice versa by manipulating specific bits of the I/O control registers during normal program operation is a useful feature of these devices.

Port C Pull-high Control Register - PCPHC

Port C pull-high control register, PCPHC, is used to set the Port C pull high function.



Voice Control and Audio output Registers - DAL, DAH, VOL

The devices include a single 12-bit current type DAC function for driving an external 8W speaker through an external NPN transistor or Power Amplifier. The programmer must write the voice data to these DAL/DAH registers. The programmer can control the DAC volume with 8-levels via the VOL register.

Pulse Width Modulator Registers - PWMC, PWML, PWMH

Each device contains a single 12-bit PWM function for driving an external 8W speaker. The programmer must write the voice data to PWML/PWMH register. The programmer can control the PWM volume with 9-levels via the VOL register.

Serial Interface Module (SIM) Registers - SIMC0A/B, SIMC1A/B, SIMC2A/B, SIMARA/B, SIMDRA/B

Each SIM contains SPI and I²C function for communicating with other microcontroller or SPI Flash Memory. All devices contain an integrated I²C and SPI bus which interfaces to the external shared pins SDA, SCL and SCSB, SCK, SDI, SDO with PB on the microcontroller. The I²C correct setup and data transfer operation of this 2-line bidirectional bus utilizes 4 special function registers. The SIMARA/B register sets the slave address of the device while the SIMC0A/B is the control register that enables or disables the device as well as select whether it is in I²C or SPI mode. The SIMC1A/B register is the I²C status register while the SIMDRA/B register is the input/output data register. The SPI correct setup and data transfer operation of this 3-line bidirectional bus utilizes 3 special function registers. The SIMC0A/B is the control register that enables or disables the device as well as select whether it is in I²C or SPI mode. The SIMC2A/B register is the SPI status register while the SIMDRA/B register is the input/output data register.

Input/Output Ports

Holtek microcontrollers offer considerable flexibility on their I/O ports. With the input or output designation of every pin fully under user program control, pull-high options for all ports and wake-up options on certain pins, the user is provided with an I/O structure to meet the needs of a wide range of application possibilities.

Depending upon which device or package is chosen, the microcontroller range provides from 15 bidirectional input/output lines labeled with port names PA, PB, PC etc. These I/O ports are mapped to the Data Memory with specific addresses as shown in the Special Purpose Data Memory table. All of these I/O ports can be used for input and output operations. For input operation, these ports are non-latching, which means the inputs must be ready at the T2 rising edge of instruction "MOV A,[m]" where m denotes the port address. For output operation, all the data is latched and remains unchanged until the output latch is rewritten.

Pull-high Resistors

Many product applications require pull-high resistors for their switch inputs usually requiring the use of an external resistor. To eliminate the need for these external resistors, all I/O pins, when configured as an input have the capability of being connected to an internal pull-high resistor. These pull-high resistors are selectable via configuration or software options and are implemented using a weak PMOS transistor. Note that if the pull-high option is selected, then all I/O pins on that port will be connected to pull-high resistors, individual pins can be selected for pull-high resistor options.

Port A Wake-up

Each device has a HALT instruction enabling the microcontroller to enter a Power Down Mode and preserve power, a feature that is important for battery and other low-power applications. Various methods exist to wake-up the microcontroller, one of which is to change the logic condition on one of the Port A pins from high to low. After a "HALT" instruction forces the microcontroller into entering a HALT condition, the processor will remain idle or in a low-power state until the logic condition of the selected wake-up pin on Port A changes from high to low. This function is especially suitable for applications that can be woken up via external switches. Note that each pin on Port A can be selected individually to have this wake-up feature.

I/O Port Control Registers

Each I/O port has its own control register PAC, PBC and PCC, to control the input/output configuration. With this control register, each CMOS output or input with or without pull-high resistor structures can be reconfigured dynamically under software control. Each pin of the I/O ports is directly mapped to a bit in its associated port control register. For the I/O pin to function as an input, the corresponding bit of the control register must be written as a "1". This will then allow the logic state of the input pin to be directly read by instructions. When the corresponding bit of the control register is written as a "0", the I/O pin will be setup as a CMOS output. If the pin is currently setup as an output, instructions can still be used to read the output register. However, it should be noted that the program will in fact only read the status of the output data latch and not the actual logic status of the output pin.

Pin-shared Functions

The flexibility of the microcontroller range is greatly enhanced by the use of pins that have more than one function. Limited numbers of pins can force serious design constraints on designers but by supplying pins with multi-functions, many of these difficulties can be overcome. For some pins, the chosen function of the multi-function I/O pins is set by configuration options while for others the function is set by application program control.

Serial Interface Module

The device pins, PB0~PB3, are pin-shared with pins SDAB, SCLB, \overline{SCSB} , SCKB, SDIB, SDOB. The choice of which function is used is selected using the SIMCOB register.

Serial Interface Module

The device pins, PB4~PB7, are pin-shared with pins SDAA, SCLA, \overline{SCSA} , SCKA, SDIA, SDOA. The choice of which function is used is selected using the SIMCOA register.

This Serial interface module should be selected as SPI function which is used for the internal Voice ROM access control, and should be left no external connection.

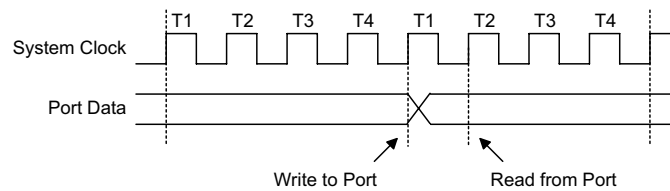
I/O Pin Structures

The following diagrams illustrate the I/O pin internal structures. As the exact logical construction of the I/O pin may differ from these drawings, they are supplied as a guide only to assist with the functional understanding of the I/O pins.

Note also that the specified pins refer to the largest device package, therefore not all pins specified will exist on all devices.

Programming Considerations

Within the user program, one of the first things to consider is port initialization. After a reset, all of the I/O data and port control registers will be set high. This means that all I/O pins will default to an input state, the level of which depends on the other connected circuitry and whether pull-high options have been selected. If the port control registers, PAC, PBC, PCC etc., are then programmed to setup some pins as outputs, these output pins will have an initial high output value unless the associated port data registers, PA, PB, PC etc., are first programmed. Selecting which pins are inputs and which are outputs can be achieved byte-wide by loading the correct values into the appropriate port control register or by programming individual bits in the port control register using the "SET [m].i" and "CLR [m].i" instructions. Note that when using these bit control instructions, a read-modify-write operation takes place. The microcontroller must first read in the data on the entire port, modify it to the required new bit values and then rewrite this data back to the output ports.



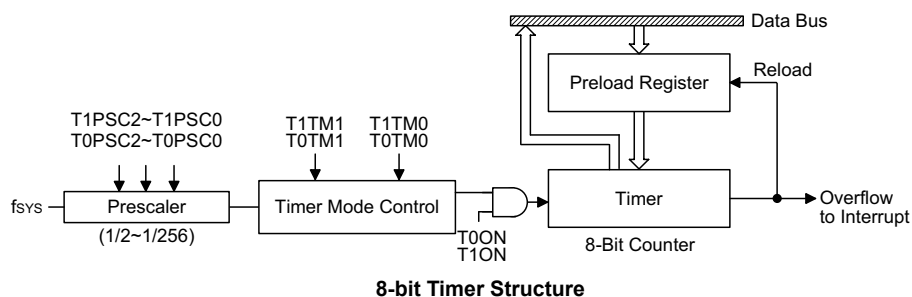
Read/Write Timing

Port A has the additional capability of providing wake-up functions. When the device is in the Power Down Mode, various methods are available to wake the device up. One of these is a high to low transition of any of the Port A pins. Single or multiple pins on Port A can be setup to have this function.

Timers

The provision of timers form an important part of any microcontroller, giving the designer a means of carrying out time related functions. These devices contain two count up timers of 8-bit capacity. The provision of an internal prescaler to the clock circuitry of the timer gives added range to the timer.

There are two types of register related to each Timer. The first is the register that contains the actual value of the timer and into which an initial value can be preloaded. Reading from this register retrieves the contents of the Timer. All devices can have the timer clock configured to come from the internal clock source.



Configuring the Timer Input Clock Source

The clock source for the 8-bit timers is the system clock divided by four. The 8-bit timer clock source is also first divided by a, the division ratio of which is conditioned by the three lower bits of the associated timer control register.

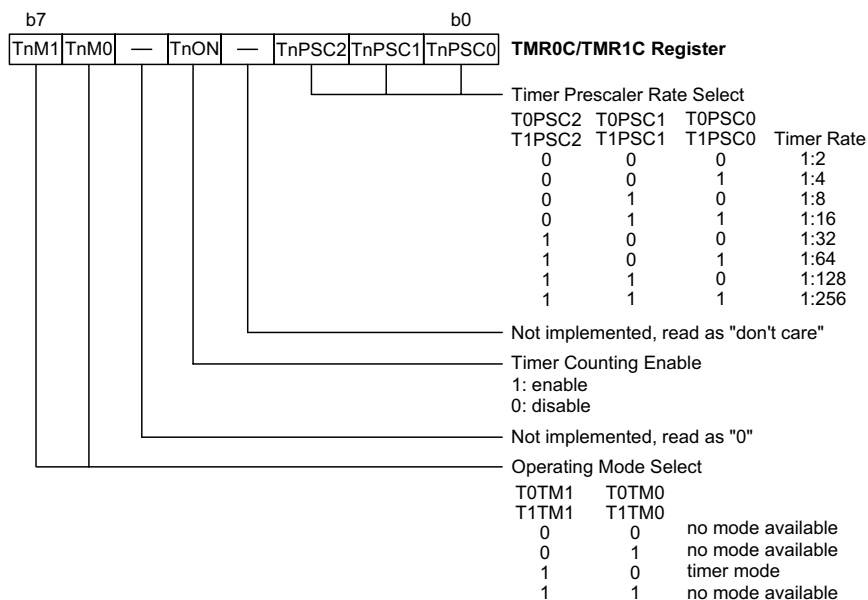
Timer Registers - TMR0, TMR1

The timer registers are special function registers located in the special purpose Data Memory and is the place where the actual timer value is stored. All devices contain two 8-bit timers, whose registers are known as TMR0 and TMR1. The value in the timer registers increases by one each time an internal clock pulse is received. The timer will count from the initial value loaded by the preload register to the full count of FFH for the 8-bit timer at which point the timer overflows and an internal interrupt signal is generated. The timer value will then be reset with the initial preload register value and continue counting.

Note that to achieve a maximum full range count of FFH for the 8-bit timer, the preload registers must first be cleared to all zeros. It should be noted that after power-on, the preload registers will be in an unknown condition. Note that if the Timer Counters are in an OFF condition and data is written to their preload registers, this data will be immediately written into the actual counter. However, if the counter is enabled and counting, any new data written into the preload data register during this period will remain in the preload register and will only be written into the actual counter the next time an overflow occurs. Note also that when the timer registers are read, the timer clock will be blocked to avoid errors, however, as this may result in certain timing errors, programmers must take this into account.

Timer Control Registers - TMR0C, TMR1C

Each timer has its respective timer control register, known as TMR0C and TMR1C. It is the timer control register together with their corresponding timer registers that control the full operation of the timers. Before the timers can be used, it is essential that the appropriate timer control register is fully programmed with the right data to ensure its correct operation, a process that is normally carried out during program initialization. Bits 7 and 6 of the Timer Control Register, must be set to the required logic levels. Bit 6 of the registers must always be written with a "1", and bit 7 must always be written with a "1". The timer-on bit, which is bit 4 of the Timer Control Register and known as T0ON/T1ON, depending upon which timer is used, provides the basic on/off control of the respective timer. setting the bit high allows the timer to run, clearing the bit stops the timer. For the 8-bit timers, which have prescalers, bits 0~2 of the Timer Control Register determines the division ratio of the input clock prescaler.



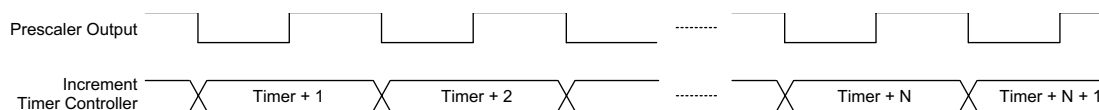
Timer Control Register (n=0 or 1)

Configuring the Timer

The Timer is used to measure fixed time intervals, providing an internal interrupt signal each time the Timer overflows. To do this the Operating Mode Select bit pair in the Timer Control Register must be set to the correct value as shown.

Control Register Operating Mode Select Bits	Bit7	Bit6
	1	0

The internal clock, f_{sys} , is used as the Timer clock. However, this clock source is further divided by a prescaler, the value of which is determined by the Prescaler Rate Select bits, which are bits 0~2 in the Timer Control Register. After the other bits in the Timer Control Register have been setup, the enable bit, which is bit 4 of the Timer Control Register, can be set high to enable the Timer to run. Each time an internal clock cycle occurs, the Timer increments by one. When it is full and overflows, an interrupt signal is generated and the Timer will reload the value already loaded into the preload register and continue counting. The interrupt can be disabled by ensuring that the Timer Interrupt Enable bit in the Interrupt Control Register, INTC, is reset to zero.



Timer Mode Timing Diagram

Prescaler

All of the 8-bit timers possess a prescaler. Bits 0~2 of their associated timer control register, define the pre-scaling stages of the internal clock source of the Timer. The Timer overflow signal can be used to generate signals for the Timer interrupt.

Programming Considerations

The internal system clock is used as the timer clock source and is therefore synchronized with the overall operation of the microcontroller. In this mode, when the appropriate timer register is full, the microcontroller will generate an internal interrupt signal directing the program flow to the respective internal interrupt vector.

When the Timer is read, the clock is blocked to avoid errors, however as this may result in a counting error, this should be taken into account by the programmer. Care must be taken to ensure that the timers are properly initialized before using them for the first time. The associated timer enable bits in the interrupt control register must be properly set otherwise the internal interrupt associated with the timer will remain inactive. The edge select, timer mode and clock source control bits in timer control register must also be correctly set to ensure the timer is properly configured for the required application. It is also important to ensure that an initial value is first loaded into the timer registers before the timer is switched on; this is because after power-on the initial values of the timer registers are unknown. After the timer has been initialized the timer can be turned on and off by controlling the enable bit in the timer control register.

Timer Program Example

The following example program section is based on the device, which contain two 8-bit timers. Programming the timer for other devices is conducted in a very similar way. The program shows how the timer registers are setup along with how the interrupts are enabled and managed. Points to note in the example are how, for the 8-bit timer. Note how the timer is turned on by setting bit 4 of the respective timer control register. The timer can be turned off in a similar way by clearing the same bit. This example program sets the timer to be in the timer mode which uses the internal f_{SYS} as their clock source, and produce a timer 0 interrupt per 1ms.

```

#include HT83B60.inc
    jmp begin
    :
org 04h                ; time base vector
    reti
org 08h                ; timer 0 interrupt vector
    jmp tmr0int        ; jump here when timer 0 overflows every 1ms
org 0Ch
    reti
org 10h
    reti
org 14h
    reti
    :
                                ; internal timer 0 interrupt routine
Tmr0int:
    :
                                ; timer 0 main program placed here
    :
    reti
    :
begin:
                                ; setup timer 0 registers
    mov  a,06h           ; setup timer 0 low byte
    mov  tmr0,a          ; low byte must be setup before high byte
    mov  a,094           ; setup timer 0 control register
    mov  tmr0c,a        ; setup timer mode and clock source is fsys/32 prescaler
                                ; setup interrupt register
    mov  a,05h           ; enable global interrupt
    mov  intc,a         ; enable timer 0 interrupt

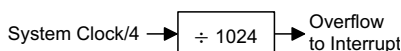
```

Time Base

The Time Base function will generate a regular interrupt signal synchronised to the system clock which can be used by the application as a time base signal.

Time Base Operation

The Time Base operation is a very simple function for the generation of a regular time signal. This is implemented by generating a regular interrupt signal whose enable/disabled and request flags are in the INTC register. The clock source for the time base is the internal $f_{SYS}/4$ clock source, which is then divided internally by a value of 1024. It is this divided signal that generates the internal interrupt. The Time Base Interrupt is enabled by the ETBI bit in the INTC register and interrupt request flag is the TBF flag in the same register. A time base of 1ms will therefore be generated from a system clock of 4MHz and a time base of 0.5ms will be generated from a system clock source of 8MHz.



Time Base Example

The following example program section is based on the device. The program shows how the Time Base registers are setup along with how the interrupts are enabled and managed. The points to note in the example are how the Time Base is turned on by setting bit 4 of the INTC register. The Time Base can be turned off in a similar way by clearing the same bit. This example program sets the Time Base which uses the internal system clock as their clock source, and produces a time base interrupt every 0.5ms from a system source clock of 8MHz.

```

#include HT83B60.inc
    jmp    begin
    :
org 04h                ; time base vector
    jmp    time_base_int ; jump here when time base overflows per 0.5ms
org 08h
    reti
org 0Ch
    reti
org 10h
    reti
org 14h
    reti
    :
                                ; time base interrupt routine
time_base_int:
    :
                                ; time base main program placed here
    :
    reti
    :
begin:
                                ; setup interrupt register
    mov    a,03h                ; enable global and time base interrupt
    mov    intc,a                ; enable time base
  
```

Serial Interface

The device contains both SPI and I²C serial interface functions, which allows two methods of easy communication with external peripheral hardware. As the SPI and I²C function share the same external pins and internal registers their function must first be chosen by selecting the correct configuration option.

SPI Interface

The SPI interface is often used to communicate with external peripheral devices such as sensors, Flash or EEPROM memory devices etc. Originally developed by Motorola, the four line SPI interface is a synchronous serial data interface that has a relatively simple communication protocol simplifying the programming requirements when communicating with external hardware devices.

SPI Interface Operation

The SPI interface is a full duplex synchronous serial data link. Communication between devices connected to the SPI interface is carried out in a slave/master mode with all data transfer initiations being implemented by the master. Multiple slave devices can be connected to the SPI serial bus with each device controlled using its slave select line. The SPI is a four line interface with pin names SDI, SDO, SCK and $\overline{\text{SCS}}$. Pins SDI and SDO are the Serial Data Input and Serial Data Output lines, SCK is the Serial Clock line and $\overline{\text{SCS}}$ is the Slave Select line. As the SPI interface pins are pin-shared with segment pins and with the I²C function pins, the SPI interface must first be enabled by selecting the correct configuration option. After the SPI configuration option has been selected it can then also be selected using the SIMEN bit in the SIMC0 register.

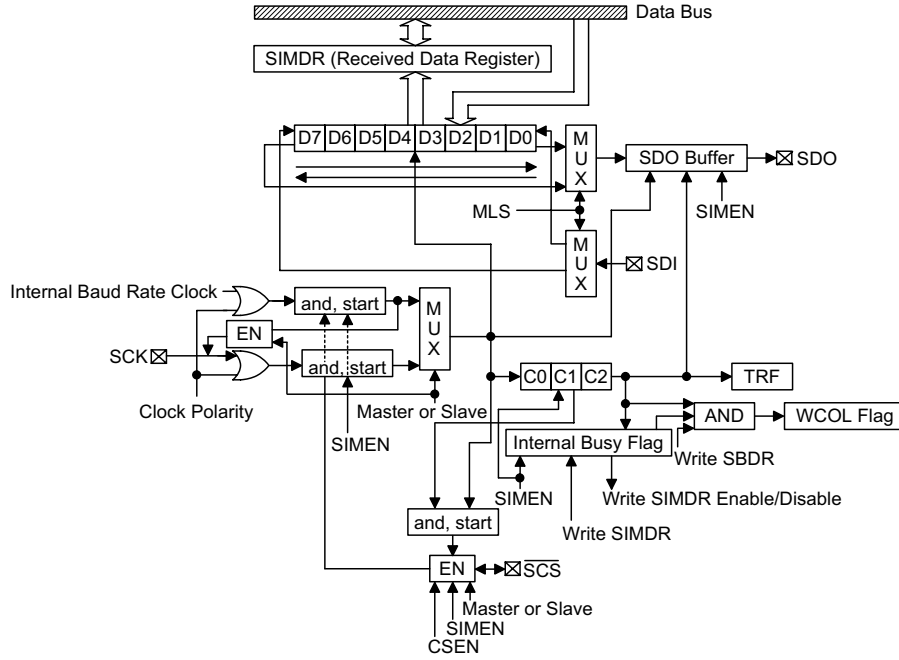
The SPI function in this device offers the following features:

- Full duplex synchronous data transfer
- Both Master and Slave modes
- LSB first or MSB first data transmission modes
- Transmission complete flag

Several other configuration options also exist to setup various SPI interface options as follows:

- SPI pin enabled
- WCOL bit enabled or disabled
- CSEN bit enabled or disabled

The status of the SPI interface pins is determined by a number of factors, whether the device is in master or slave mode and upon the condition of certain control bits such as CSEN and SIMEN.



Block Diagram

	Master/Slave (SIMEN=0)	Master (=1)		Slave (=1)		
		CSEN=1	CSEN=0	CSEN=0	SCS line=0 (CSEN=1)	SCS line=1 (CSEN=1)
SCS	Z	L	Z	Z	I, Z	I, Z
SDO	Z	O	O	O	O	Z
SDI	Z	I, Z	I, Z	I, Z	I, Z	Z
SCK	Z	L(CPOL=1) H(CPOL=0)	L(CPOL=1) H(CPOL=0)	I, Z	I, Z	Z

"Z" floating, "H" output high, "L" output low, "I" input, "O" output level,
 "I,Z" input floating (no pull-high)

SPI Interface Pin Status

SPI Registers

The SIMDR A/B register is used to store the data being transmitted and received. There are two control registers associated with the SPI interface, SIMC0 A/B and SIMC2 A/B and one data register known as SIMDRA/B. The SIMC1 A/B register is not used by the SPI function. Register SIMC0 A/B is used to control the enable/disable function, the power down control and to set the data transmission clock frequency. Register SIMC2 A/B is used for other control functions such as LSB/MSB selection, write collision flag etc.

The following gives further explanation of each bit:

- SIMEN A/B

The A/B bit is the overall on/off control for the SPI interface. When the A/B bit is cleared to zero to disable the SPI interface, the SDI, SDO A/B, SCK A/B and $\overline{\text{SCS}}$ A/B lines will be in a floating condition and the SPI operating current will be reduced to <0.1mA at 5V. When the bit is high the SPI interface is enabled. Note that when the SIMEN A/B bit changes from low to high the contents of the SPI control registers will be in an unknown condition and should therefore be initialised by the application program.

- SIM0 A/B~SIM2 A/B

These three bits control the Master/Slave selection and also setup the SPI interface clock speed when in the Master Mode. The SPI clock is a function of the system clock whether it be RC type or Crystal type. If the Slave Mode is selected then the clock will be supplied by the external Master device.

The following gives further explanation of each bit:

- TRF A/B

The TRF A/B bit is the Transmit/Receive Complete flag and is cleared by the application program and can be used to generate an interrupt. When the bit is high the data has been transmitted or received. If the bit is low the data is being transmitted or has not yet been received.

- WCOL A/B

The WCOL A/B bit is used to detect if a data collision has occurred. If this bit is high it means that data has been attempted to be written to the SIMDR A/B register during a data transfer operation. This writing operation will be ignored if data is being transferred. The bit can be cleared by the application program. Note that using the CSEN A/B bit can be disabled or enabled via configuration option.

- CSEN A/B

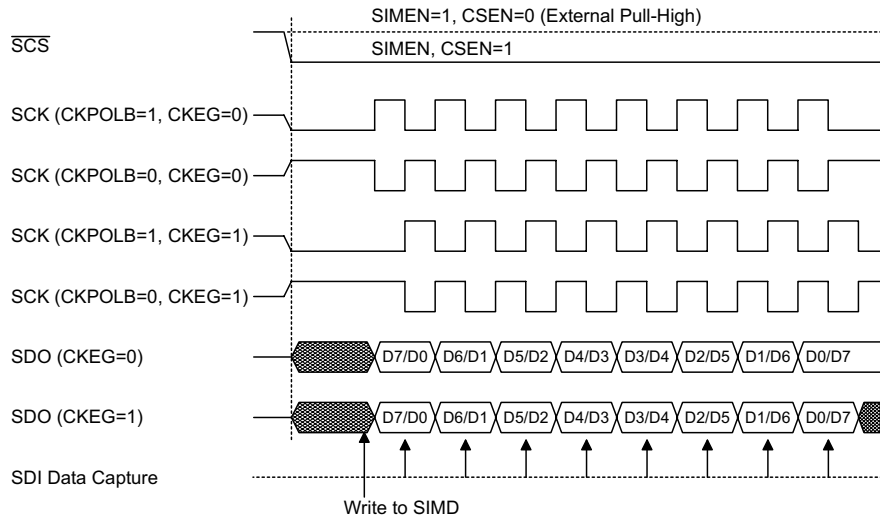
The CSEN A/B bit is used as an on/off control for the $\overline{\text{SCS}}$ A/B pin. If this bit is low then the $\overline{\text{SCS}}$ A/B pin will be disabled and placed into a floating condition. If the bit is high the $\overline{\text{SCS}}$ A/B pin will be enabled and used as a select pin.

- MLS A/B

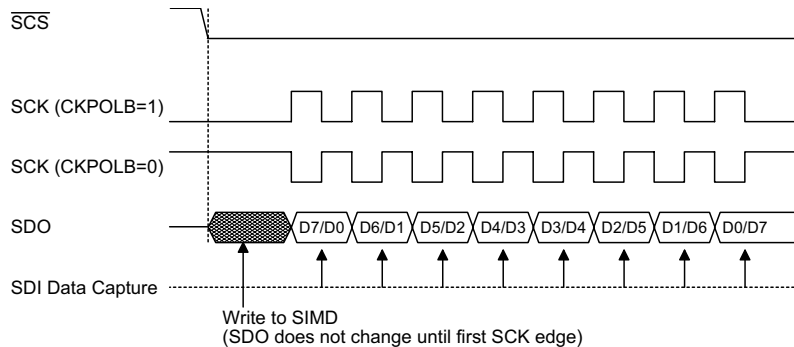
The MLS A/B is used to select how the data is transferred, either MSB or LSB first. Setting the bit high will select MSB first and low for LSB first. Note that the SIMC2 A/B register is the same as the SIMAR A/B register used by the I²C interface.

- SPI Communication

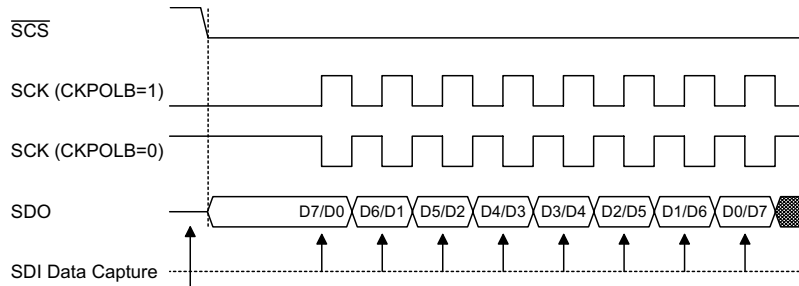
After the SPI interface is enabled by setting the SIMEN A/B bit high, then in the Master Mode, when data is written to the SIMDR A/B register, transmission/reception will begin simultaneously. When the data transfer is complete, the TRF A/B flag will be set automatically. In the Slave Mode, when the clock signal from the master has been received, any data in the SIMDR register will be transmitted and any data on the SDI A/B pin will be shifted into the SIMDR A/B register. The master should output an \overline{SCS} A/B signal before a clock signal is provided and slave data transfers should be enabled/disabled before/after an \overline{SCS} A/B signal is received.



SPI Master Mode Timing



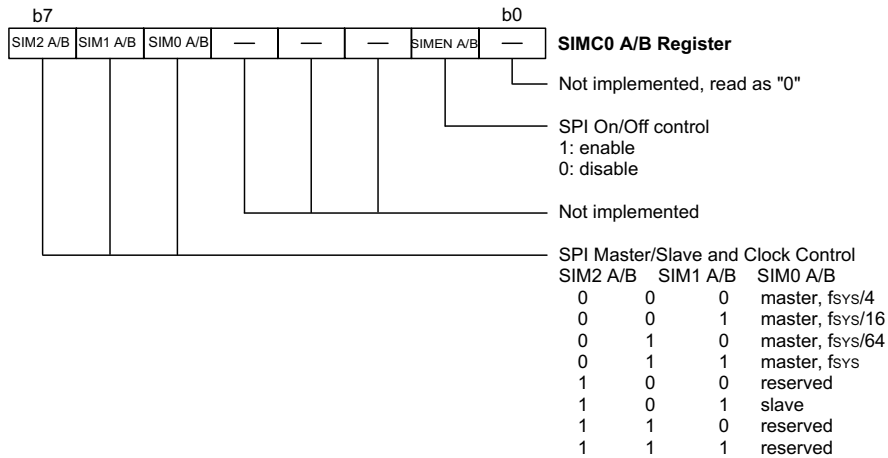
SPI Slave Mode Timing - CKEG=0



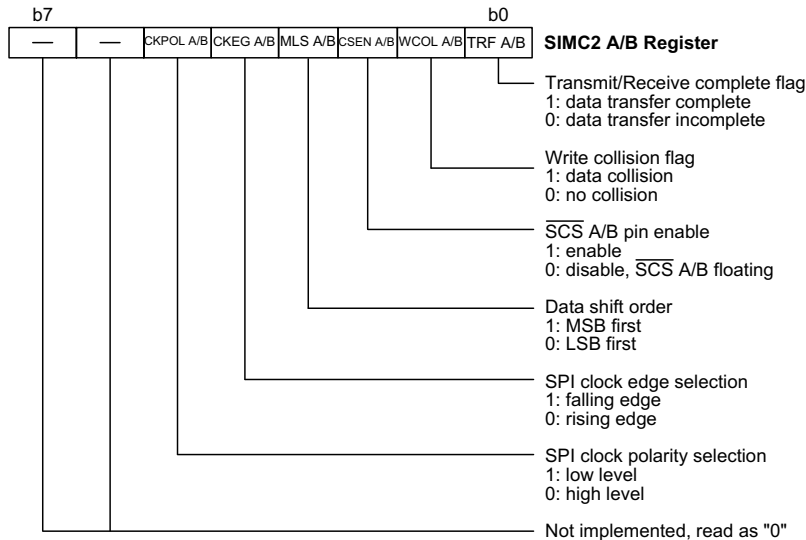
Write to SIMD
(SDO changes as soon as writing occurs; SDO is floating if $\overline{SCS}=1$)

Note: For SPI slave mode, if SIMEN=1 and CSEN=0, SPI is always enabled and ignores the SCS level.

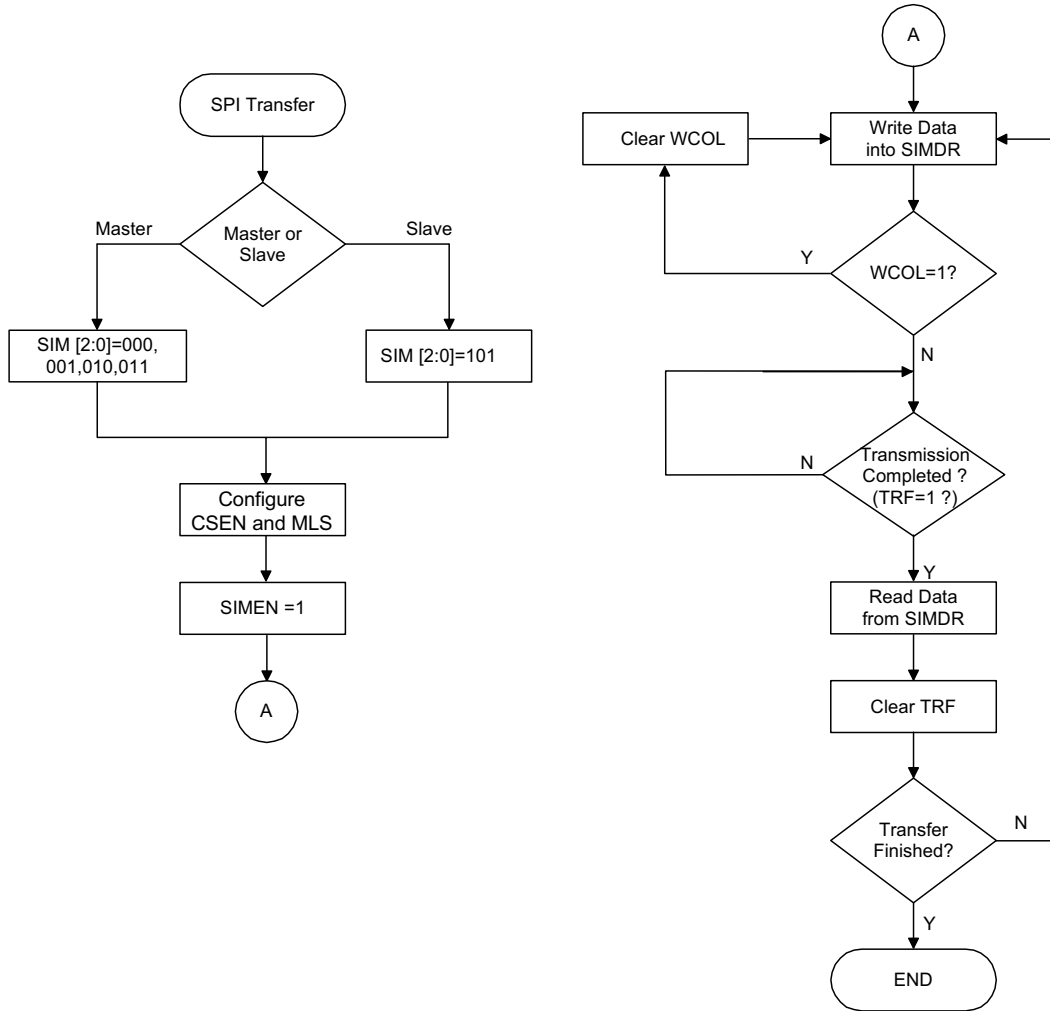
SPI Slave Mode Timing - CKEG=1



SPI Control Register - SIMC0A/B



SPI Control Register - SIMC2A/B



SPI Transfer Control Flowchart

I²C Interface

The I²C bus is a bidirectional 2-line communication interface originally developed by Philips. The possibility of transmitting and receiving data on only 2 lines offers many new application possibilities for microcontroller based applications.

I²C Interface Operation

As the I²C interface pins are pin-shared with segment pins and with the SPI function pins, the I²C interface must first be enabled by selecting the correct configuration option.

There are two lines associated with the I²C bus, the first is known as SDA and is the Serial Data line, the second is known as SCL line and is the Serial Clock line. As many devices may be connected together on the same bus, their outputs are both open drain types. For this reason it is necessary that external pull-high resistors are connected to these outputs. Note that no chip select line exists, as each device on the I²C bus is identified by a unique address which will be transmitted and received on the I²C bus.

When two devices communicate with each other on the bidirectional I²C bus, one is known as the master device and one as the slave device. Both master and slave can transmit and receive data, however, it is the master device that has overall control of the bus. For this device, which only operates in slave mode, there are two methods of transferring data on the I²C bus, the slave transmit mode and the slave receive mode.

I²C Registers

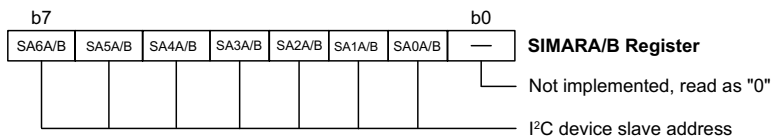
There are three control registers associated with the I²C bus, SIMC0A/B, SIMC1A/B and SIMARA/B and one data register, SIMDRA/B.

The SIMDRA/B register is used to store the data being transmitted and received on the I²C bus. Before the microcontroller writes data to the I²C bus, the actual data to be transmitted must be placed in the SIMDRA/B register. After the data is received from the I²C bus, the microcontroller can read it from the SIMDRA/B register. Any transmission of data to the I²C bus or reception of data from the I²C bus must be made via the SIMDRA/B register.

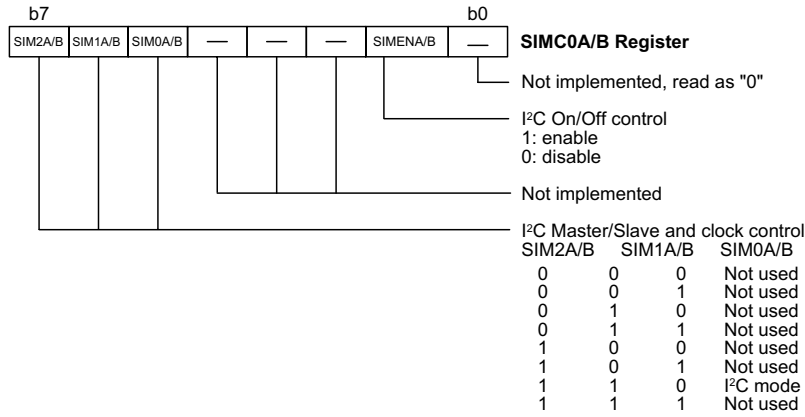
The SIMARA/B register is the location where the slave address of the microcontroller is stored. Bits 1~7 of the SIMARA/B register define the microcontroller slave address. Bit 0 is not defined. When a master device, which is connected to the I²C bus, sends out an address, which matches the slave address in the SIMARA/B register, the microcontroller slave device will be selected.

Note that the SIMARA/B register is the same register as SIMC2A/B which is used by the SPI interface.

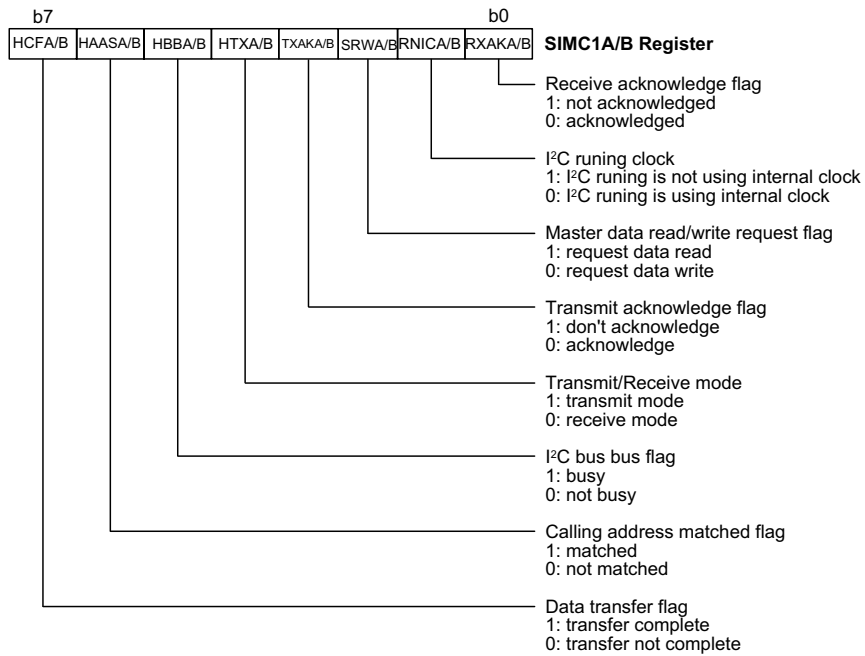
The SIMC0A/B register is used for the I²C overall on/off control.



Slave Address Register - SIMARA/B



I²C Control Register - SIMC0A/B



I²C Control Register - SIMC1A/B

I²C Configuration Option

There are several configuration options associated with the I²C interface. One of these is to enable the RNICA/B bit function which selects the RNICA/B bit in SIMC1A/B register. Another configuration option determines the debounce time of the I²C interface. This adds a debounce delay time to the external clock to reduce the possibility of glitches on the clock line causing erroneous operation. The debounce time if selected can be chosen to be either 1 or 2 system clocks.

The following gives further explanation of each bit:

- SIMENA/B

The SIMENA/B bit determines if the I²C bus is enabled or disabled. If data is to be transferred or received on the I²C bus then this bit must be set high.

The following gives further explanation of each bit:

- HCFA/B

The HCFA/B flag is the data transfer flag. This flag will be zero when data is being transferred. Upon completion of an 8-bit data transfer the flag will go high and an interrupt will be generated.

- HASSA/B

The HASSA/B flag is the address match flag. This flag is used to determine if the slave device address is the same as the master transmit address. If the addresses match then this bit will be high, if there is no match then the flag will be low.

- HBBA/B

The HBBA/B flag is the I²C busy flag. This flag will be high when the I²C bus is busy which will occur when a START signal is detected. The flag will be reset to zero when the bus is free which will occur when a STOP signal is detected.

- HTXA/B

The HTXA/B flag is the transmit/receive mode bit. This flag should be set high to set the transmit mode and low for the receive mode.

- TXAKA/B

The TXAKA/B flag is the transmit acknowledge flag. After the receipt of 8-bits of data, this bit will be transmitted to the bus on the 9th clock. To continue receiving more data, this bit has to be reset to zero before further data is received.

- SRWA/B

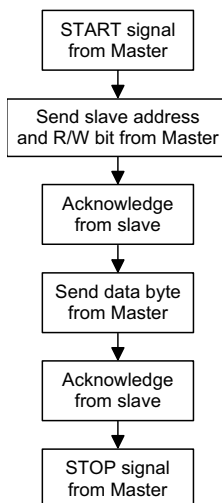
The SRWA/B bit is the Slave Read/Write bit. This bit determines whether the master device wishes to transmit or receive data from the I²C bus. When the transmitted address and slave address match, that is when the HAASA/B bit is set high, the device will check the SRWA/B bit to determine whether it should be in transmit mode or receive mode. If the SRWA/B bit is high, the master is requesting to read data from the bus, so the device should be in transmit mode. When the SRWA/B bit is zero, the master will write data to the bus, therefore the device should be in receive mode to read this data.

- RNICA/B

The RNICA/B bit is used as I²C running clock from Internal or external clock. If this bit is low then I²C running using internal clock and it will not wake-up when I²C interrupts in the Power Down Mode. If the bit is high I²C running using external clock and it will wake-up when I²C interrupts in the Power Down Mode.

- RXAKA/B

The RXAKA/B flag is the receive acknowledge flag. When the RXAKA/B bit has been reset to zero it means that a correct acknowledge signal has been received at the 9th clock, after 8 bits of data have been transmitted. When in the transmit mode, the transmitter checks the RXAKA/B bit to determine if the receiver wishes to receive the next byte. The transmitter will therefore continue sending out data until the RXAKA/B bit is set to "1". When this occurs, the transmitter will release the SDAA/B line to allow the master to send a STOP signal to release the bus.



I²C Bus Communication

Communication on the I²C bus requires four separate steps, a START signal, a slave device address transmission, a data transmission and finally a STOP signal. When a START signal is placed on the I²C bus, all devices on the bus will receive this signal and be notified of the imminent arrival of data on the bus. The first seven bits of the data will be the slave address with the first bit being the MSB. If the address of the microcontroller matches that of the transmitted address, the HAAS bit in the SIMC1 register will be set and an I²C interrupt will be generated. After entering the interrupt service routine, the microcontroller slave device must first check the condition of the HAAS bit to determine whether the interrupt source originates from an address match or from the completion of an 8-bit data transfer. During a data transfer, note that after the 7-bit slave address has been transmitted, the following bit, which is the 8th bit, is the read/write bit whose value will be placed in the SRW bit. This bit will be checked by the microcontroller to determine whether to go into transmit or receive mode. Before any transfer of data to or from the I²C bus, the microcontroller must initialise the bus, the following are steps to achieve this:

Step 1

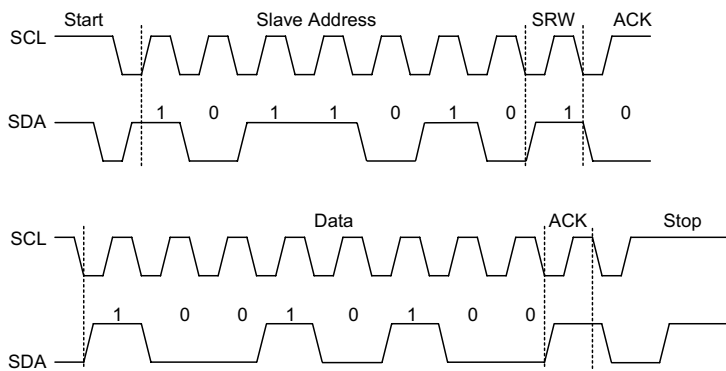
Write the slave address of the microcontroller to the I²C bus address register SIMAR.

Step 2

Set the SIMEN bit in the SIMC0 register to "1" to enable the I²C bus.

Step 3

Set the EHI bit of the interrupt control register to enable the I²C bus interrupt.



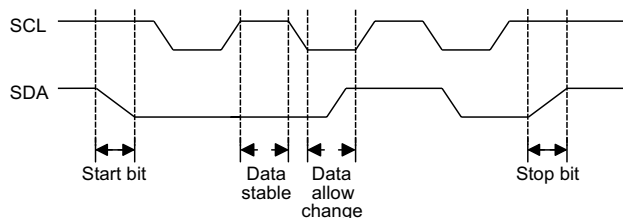
S=Start (1 bit)
 SA=Slave Address (7 bits)
 SR=SRW bit (1 bit)
 M=Slave device send acknowledge bit (1 bit)
 D=Data (8 bits)
 A=ACK (RXAK bit for transmitter, TXAK bit for receiver 1 bit)
 P=Stop (1 bit)

S	SA	SR	M	D	A	D	A	S	SA	SR	M	D	A	D	A	P
---	----	----	---	---	---	---	---	-------	---	----	----	---	---	---	---	---	-------	---

I²C Communication Timing Diagram

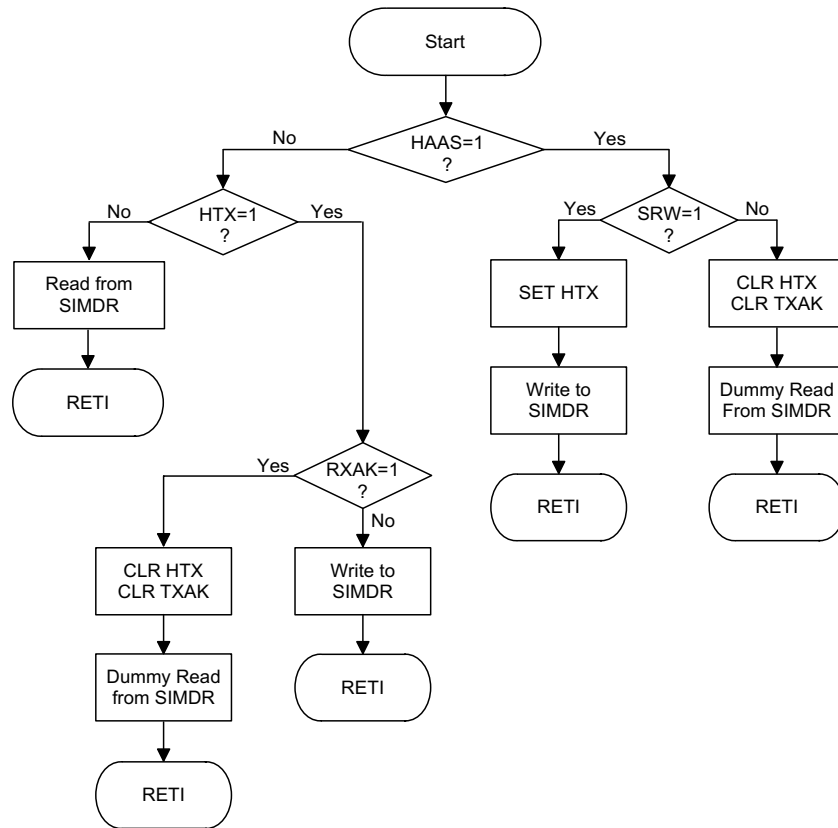
- Start Signal**
 The START signal can only be generated by the master device connected to the I²C bus and not by the microcontroller, which is only a slave device. This START signal will be detected by all devices connected to the I²C bus. When detected, this indicates that the I²C bus is busy and therefore the HBB bit will be set. A START condition occurs when a high to low transition on the SDA line takes place when the SCL line remains high.
- Slave Address**
 The transmission of a START signal by the master will be detected by all devices on the I²C bus. To determine which slave device the master wishes to communicate with, the address of the slave device will be sent out immediately following the START signal. All slave devices, after receiving this 7-bit address data, will compare it with their own 7-bit slave address. If the address sent out by the master matches the internal address of the microcontroller slave device, then an internal I²C bus interrupt signal will be generated. The next bit following the address, which is the 8th bit, defines the read/write status and will be saved to the SRW bit of the SIMC1 register. The device will then transmit an acknowledge bit, which is a low level, as the 9th bit. The microcontroller slave device will also set the status flag HAAS when the addresses match.
 As an I²C bus interrupt can come from two sources, when the program enters the interrupt subroutine, the HAAS bit should be examined to see whether the interrupt source has come from a matching slave address or from the completion of a data byte transfer. When a slave address is matched, the device must be placed in either the transmit mode and then write data to the SIMDR register, or in the receive mode where it must implement a dummy read from the SIMDR register to release the SCL line.

- **SRW Bit**
 The SRW bit in the SIMC1 register defines whether the microcontroller slave device wishes to read data from the I²C bus or write data to the I²C bus. The microcontroller should examine this bit to determine if it is to be a transmitter or a receiver. If the SRW bit is set to "1" then this indicates that the master wishes to read data from the I²C bus, therefore the microcontroller slave device must be setup to send data to the I²C bus as a transmitter. If the SRW bit is "0" then this indicates that the master wishes to send data to the I²C bus, therefore the microcontroller slave device must be setup to read data from the I²C bus as a receiver.
- **Acknowledge Bit**
 After the master has transmitted a calling address, any slave device on the I²C bus, whose own internal address matches the calling address, must generate an acknowledge signal. This acknowledge signal will inform the master that a slave device has accepted its calling address. If no acknowledge signal is received by the master then a STOP signal must be transmitted by the master to end the communication. When the HAAS bit is high, the addresses have matched and the microcontroller slave device must check the SRW bit to determine if it is to be a transmitter or a receiver. If the SRW bit is high, the microcontroller slave device should be setup to be a transmitter so the HTX bit in the SIMC1 register should be set to "1" if the SRW bit is low then the microcontroller slave device should be setup as a receiver and the HTX bit in the SIMC1 register should be set to "0".
- **Data Byte**
 The transmitted data is 8-bits wide and is transmitted after the slave device has acknowledged receipt of its slave address. The order of serial bit transmission is the MSB first and the LSB last. After receipt of 8-bits of data, the receiver must transmit an acknowledge signal, level "0", before it can receive the next data byte. If the transmitter does not receive an acknowledge bit signal from the receiver, then it will release the SDA line and the master will send out a STOP signal to release control of the I²C bus. The corresponding data will be stored in the SIMDR register. If setup as a transmitter, the microcontroller slave device must first write the data to be transmitted into the SIMDR register. If setup as a receiver, the microcontroller slave device must read the transmitted data from the SIMDR register.

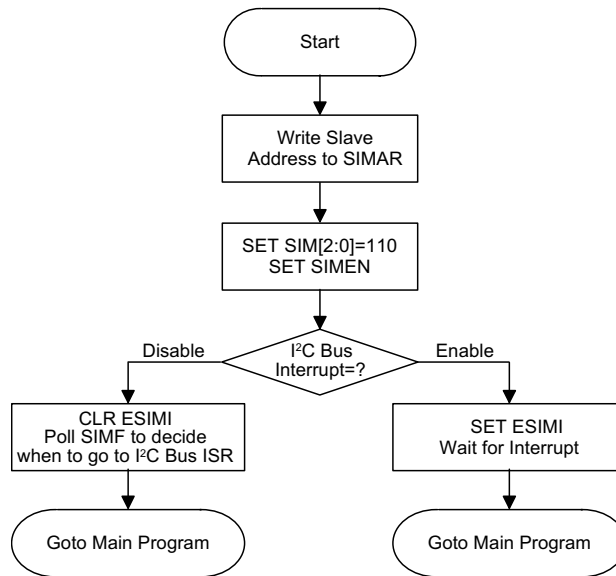


Data Timing Diagram

- **Receive Acknowledge Bit**
 When the receiver wishes to continue to receive the next data byte, it must generate an acknowledge bit, known as TXAK, on the 9th clock. The microcontroller slave device, which is setup as a transmitter will check the RXAK bit in the SIMC1 register to determine if it is to send another data byte, if not then it will release the SDA line and await the receipt of a STOP signal from the master.



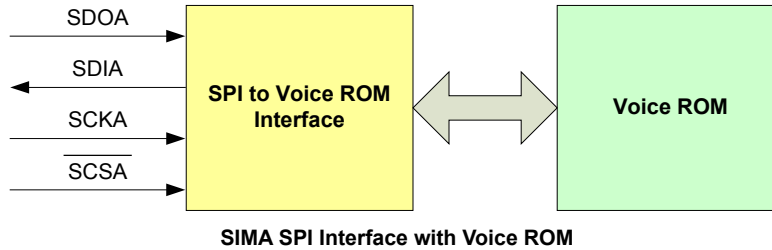
I²C Bus ISR Flow Chart



I²C Bus Initialisation Flow Chart

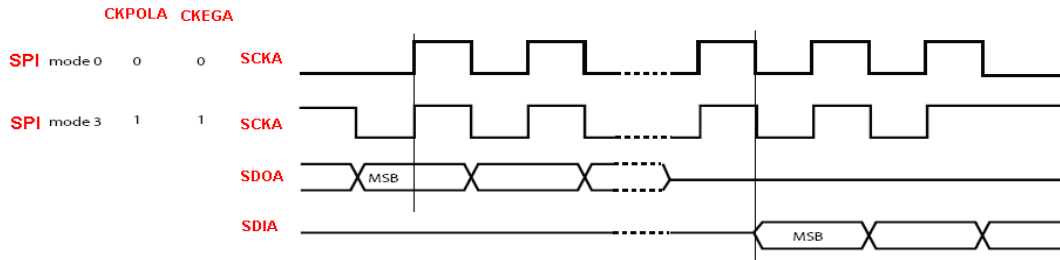
Voice ROM Access

The device provides two serial interface modules, called SIMA and SIMB. SIMA is dedicated to access the internal voice ROM while SIMB can be used as an independent SPI or I²C function to communicate with external devices. As SIMA communicates with the Voice ROM using its SPI interface, it must be setup to activate the SPIA function by the SIMC0A register. The PB4~PB7 pins are pin shared with the SPIA interface, SDOA, SCKA, SDIA and \overline{SCSA} pins respectively. In order not to interfere SPIA function, the pin-shared I/O pins, PB4~PB7, should be set as input pins using the application program, while PB5, PB6 and PB7 should also have pull high resistors enabled using configuration option. The accompanying diagram illustrates the SPI interface with the Voice ROM block diagram.



Voice ROM SPI Modes

The device provides the SPI mode 0 and mode 3 to access the internal voice ROM. The difference between these two modes is the setting on the SPI clock edge and polarity selections. The designer should follow the Voice ROM SPI modes to select the SPIA clock pin, namely SCKA, input edge and polarity by the CKPOLA and CKEGA bits in the SIMC2A register. The following diagram illustrates the timing diagram.

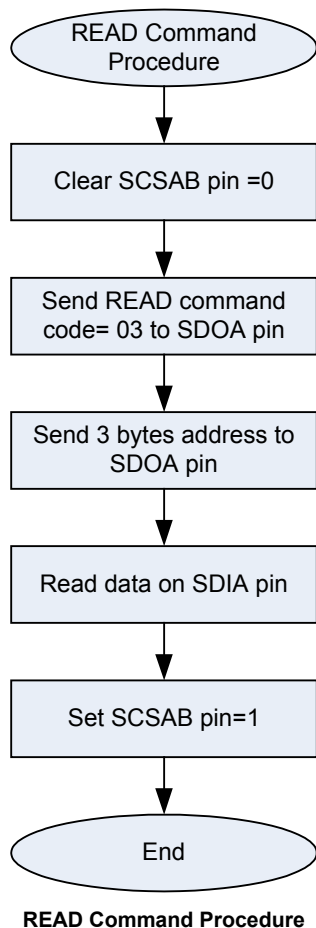


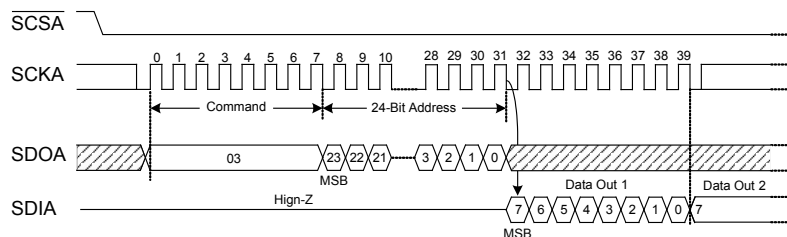
Voice ROM Read Commands

The device has READ and FAST_READ commands to access data from the internal Voice ROM. The READ command code is "03H" while the FAST_READ command code is "0BH". Both of the READ and FAST_READ commands can be used to read one byte or bulk data from the Voice ROM. The FAST_READ command is used to access the Voice ROM data using a higher speed SPI clock rate. The clock rate can be up to 85MHz, however, as the maximum system clock is 12MHz, these two commands will have the same performance.

READ Command

The READ command is used to read data from the Voice ROM. The address is latched on the rising edge of the SPI clock pin, namely SCKA, and the data will be shifted out on the falling edge of SCKA. The first address byte can point to any location in the Voice ROM. The address is automatically incremented to the next address after each byte data is shifted out, so the whole memory can be read out using a single READ command. The address will roll over to 0 when the highest address has been reached. The accompanying flowchart and diagram illustrate the READ data command setting procedure and the timing diagram.

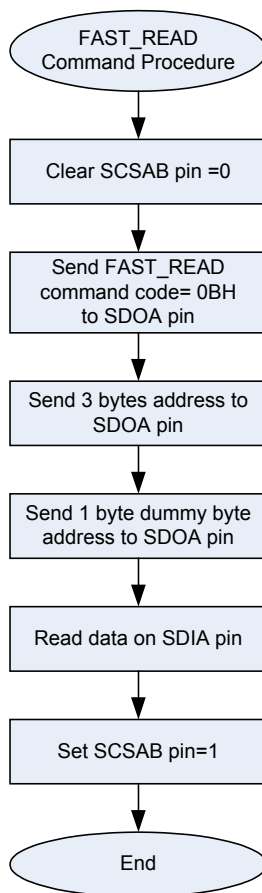




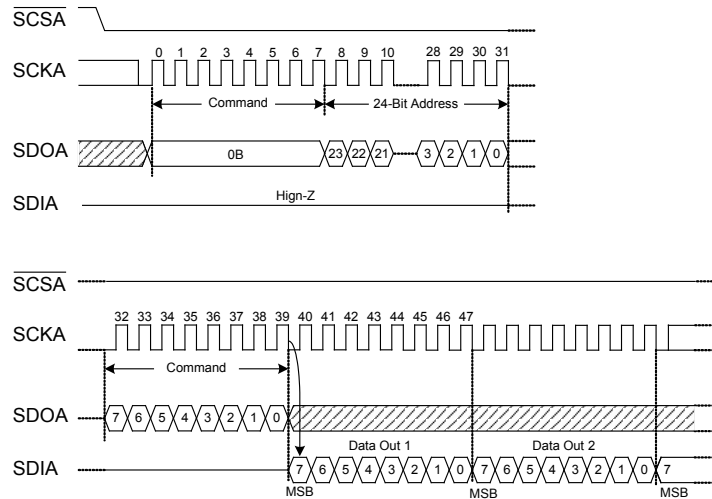
READ Command Procedure Timing Diagram

FAST_READ Command

The FAST_READ command provides a higher speed to access the Voice ROM data. The address is latched on the rising edge of the SPI clock pin, namely SCKA, and each bit of the data will be shifted out on the falling edge of SCKA. The first address byte can point to any location in the voice ROM. The address is automatically incremented to the next address after each byte data is shifted out, so the whole memory can be read out by a single FAST_READ command. The address will roll over to 0 when the highest address has been reached. The accompanying flowchart and diagram illustrate the FAST_READ data instruction setting procedure and the timing diagram.



FAST_READ Command Procedure



FAST_READ Command Procedure Timing Diagram

Voice Output

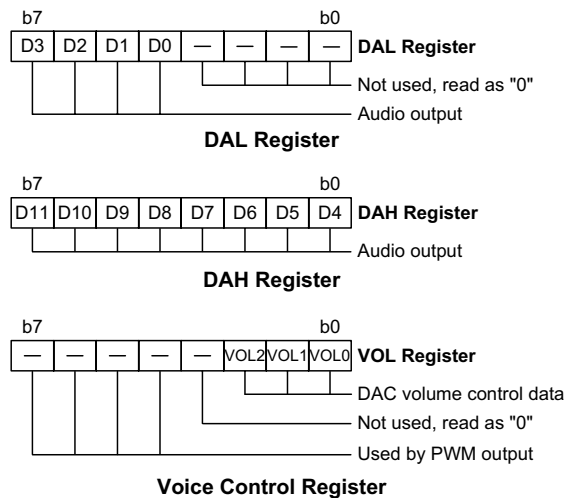
The device contains an internal 12-bit DAC function which can be used for audio signal generation.

Voice Control

Two internal registers DAL and DAH contain the 12-bit digital value for conversion by the internal DAC. There is also a DAC enable/disable control bit in the PWMC control register for overall on/off control of the DAC circuit. If the DAC circuit is not enabled, the DAH/DAL value outputs will be invalid. Writing a "1" to the DAC bit in bit1 of PWMC will enable the enable DAC circuit, while writing a "0" to the DAC bit will disable the DAC circuit.

Audio Output and Volume Control - DAL, DAH, VOL

The audio output is 12-bits wide whose highest 8-bits are written into the DAH register and whose lowest four bits are written into the highest four bits of the DAL register. Bits 0~3 of the DAL register are always read as zero. There are 8 levels of volume which are setup using the VOL register. Only the lowest 3-bits of this register are used for volume control.



VOL[2:0]	DAC Volume Control
111	High Volume ↑
110	
101	
100	↓ Low Volume
011	
010	
001	
000	

Pulse Width Modulation Output

All devices include a single 12-bit PWM function which can directly drive external audio components such as speakers.

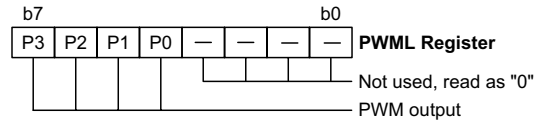
Pulse Width Modulator Operation

The PWM output is provided on two complimentary outputs on the PWM1 and PWM2 pins, providing a differential output pair and thus capable of higher drive power. These two pins can directly drive a piezo buzzer or an 8 ohm speaker without using external components. The PWM outputs can also be used single ended, where the signal is provided on the PWM1 output, and again can also be used by itself alone to drive a piezo buzzer or an 8 ohm speaker without external components. This single end output drive type is chosen using the SINGLE_PWM bit in the PWMC register.

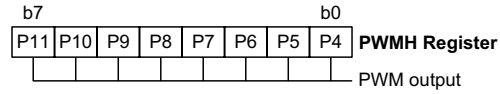
If the MSB_SIGN bit is low, then the signal that is provided on PWM1 and PWM2 will obtain a GND level voltage after setting the PWMCC bit high. If the MSB_SIGN bit is high, then the signal that is provided on PWM2 and PWM1 will have a GND level voltage when the PWMCC bit is set high.

The two PWM outputs will initially be at low levels, and if the PWM function is stopped will also return to a low level. If the PWMCC bit changes from low to high then the PWM function will start running and latch new data. If the data is not updated then the old value will remain. If the PWMCC bit changes from high to low, at the end of the duty cycle, the PWM output will stop.

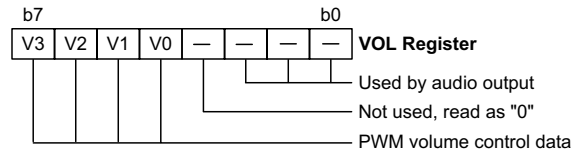
VOL[3:0]	PWM Volume Control
1xxx	High Volume ↑
0111	
0110	
0101	
0100	↓ Low Volume
0011	
0010	
0001	
0000	



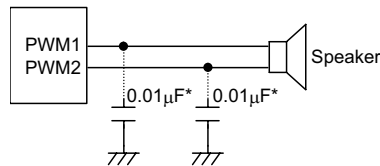
Pulse Width Modulator Data Low Register



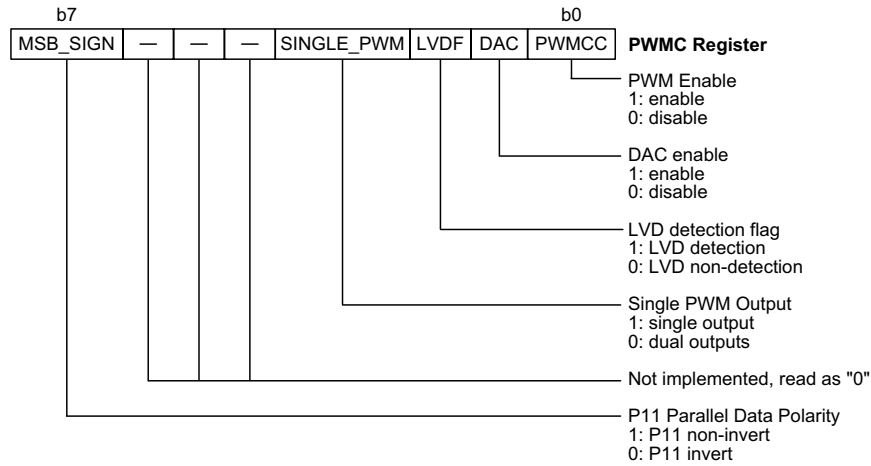
Pulse Width Modulator Data High Register



Voice Control Register



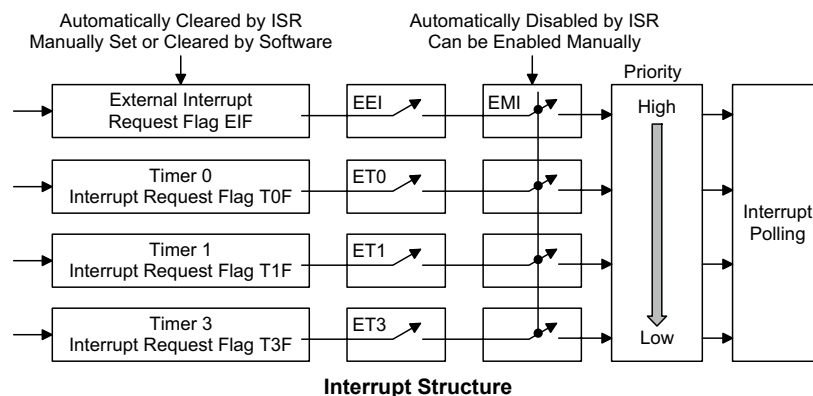
Note: "*" For reducing the digital noise that PWM may cause, can consider increment capacitors.



Pulse Width Modulator Control Register

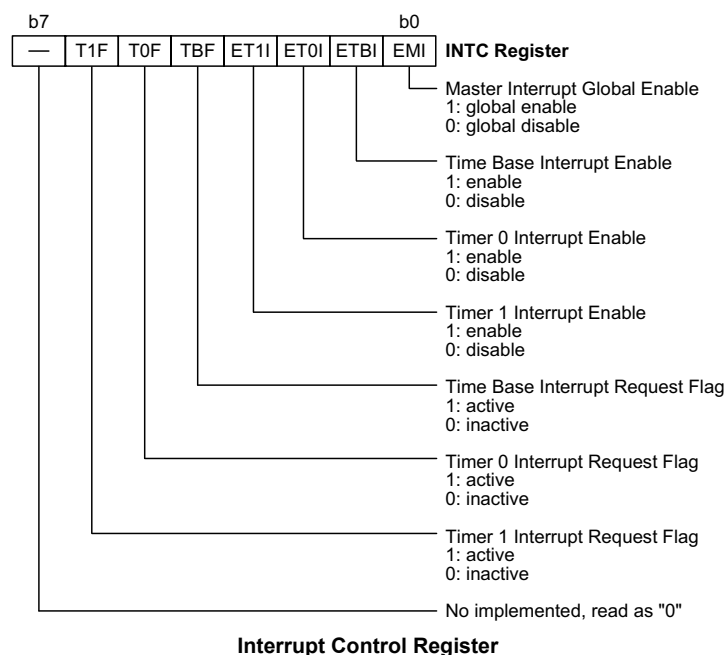
Interrupts

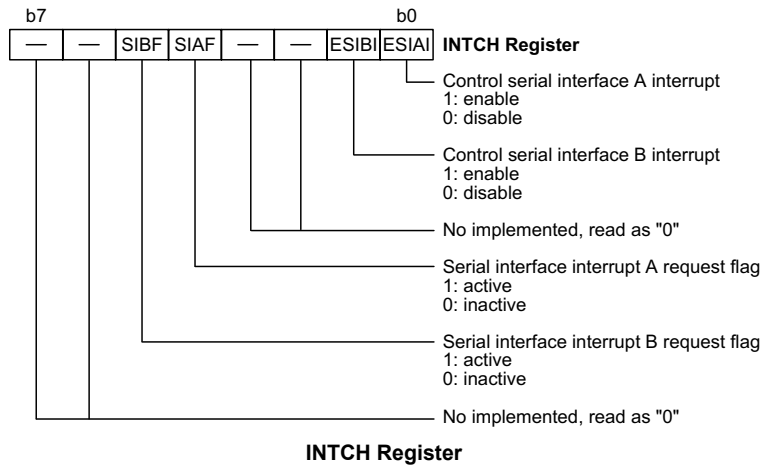
Interrupts are an important part of any microcontroller system. When an internal function such as a Time Base or Timer requires microcontroller attention, their corresponding interrupt will enforce a temporary suspension of the main program allowing the microcontroller to direct attention to their respective needs. Each device contains a Time Base interrupt and two internal timer interrupt functions. The Time Base interrupt is controlled by bit 1 of INTC register, while the internal interrupt is controlled by the Timer Counter overflow.



Interrupt Register

Overall interrupt control, which means interrupt enabling and flag setting, is controlled using two registers, known as INTC and INTCH, which are located in the Data Memory. By controlling the appropriate enable bits in these registers each individual interrupt can be enabled or disabled. Also when an interrupt occurs, the corresponding request flag will be set by the microcontroller. The global enable flag if cleared to zero will disable all interrupts.





Interrupt Operation

A timer or Time Base overflow or by setting their corresponding request flag, if their appropriate interrupt enable bit is set. When this happens, the Program Counter, which stores the address of the next instruction to be executed, will be transferred onto the stack. The Program Counter will then be loaded with a new address which will be the value of the corresponding interrupt vector. The microcontroller will then fetch its next instruction from this interrupt vector. The instruction at this vector will usually be a JMP statement which will take program execution to another section of program which is known as the interrupt service routine. Here is located the code to control the appropriate interrupt. The interrupt service routine must be terminated with a RETI statement, which retrieves the original Program Counter address from the stack and allows the microcontroller to continue with normal execution at the point where the interrupt occurred.

The various interrupt enable bits, together with their associated request flags, are shown in the accompanying diagram with their order of priority.

Once an interrupt subroutine is serviced, all the other interrupts will be blocked, as the EMI bit will be cleared automatically. This will prevent any further interrupt nesting from occurring. However, if other interrupt requests occur during this interval, although the interrupt will not be immediately serviced, the request flag will still be recorded. If an interrupt requires immediate servicing while the program is already in another interrupt service routine, the EMI bit should be set after entering the routine, to allow interrupt nesting. If the stack is full, the interrupt request will not be acknowledged, even if the related interrupt is enabled, until the Stack Pointer is decremented. If immediate service is desired, the stack must be prevented from becoming full.

Interrupt Priority

Interrupts, occurring in the interval between the rising edges of two consecutive T2 pulses, will be serviced on the latter of the two T2 pulses, if the corresponding interrupts are enabled. In case of simultaneous requests, the accompanying table shows the priority that is applied.

Interrupt Source	Interrupt Vector	HT83B60 Priority
Time Base Interrupt	04H	1
Timer 0 Overflow	08H	2
Timer 1 Overflow	0CH	3
SIM A Interrupt	10H	4
SIM B Interrupt	14H	5

Suitable masking of the individual interrupts using the INTC and INTCH registers can prevent simultaneous occurrences.

Time Base Interrupt

Each device contains a Time Base whose corresponding interrupt enable bits are known as ETBI and is located in the INTC register. For a Time Base generated interrupt to occur, the corresponding Time Base interrupt enable bit must be first set. Time Base also has a corresponding Time Base interrupt request flag, which is known as TBF, also located in the INTC register. When the master interrupt and corresponding timer interrupt enable bits are enabled, the stack is not full, and when the corresponding timer overflows a subroutine call to the corresponding Time Base interrupt vector will occur. The corresponding Program Memory vector locations for the Time Base is 04H. After entering the interrupt execution routine, the corresponding interrupt request flag, TBF will be reset and the EMI bit will be cleared to disable other interrupts.

Timer Interrupt

For a timer generated interrupt to occur, the corresponding timer interrupt enable bit must be first set. Each device contains two 8-bit timers whose corresponding interrupt enable bits are known as ET0 and ET1 and are located in the INTC register. Each timer also has a corresponding timer interrupt request flag, which are known as T0F and T1F, also located in the INTC register. When the master interrupt and corresponding timer interrupt enable bits are enabled, the stack is not full, and when the corresponding timer overflows a subroutine call to the corresponding timer interrupt vector will occur. The corresponding Program Memory vector locations for Timer 0 and Timer1 are 08H and 0CH. After entering the interrupt execution routine, the corresponding interrupt request flags, T0F or T1F will be reset and the EMI bit will be cleared to disable other interrupts.

Serial Interface Module - SIM - Interrupt

SIMA/B Interrupts include both the SPI and I²C Interrupts. The SIMA/B Mode is determined by the SIM2A/B, SIM1A/B and SIM0A/B bits in the SIMC0A/B register.

For a SPI Interrupt to occur, the global interrupt enable bit, EMI, and the corresponding SIMA/B interrupt enable bit, ESII, must be first set. The SIMENA/B bit in the SIMC0A/B register must also be set. An actual SPI Interrupt will take place when the flag, SIFA/B, is set, a situation that will occur when 8-bits of data are transferred or received from either of the SPI interfaces. When the interrupt is enabled, the stack is not full and an SIMA/B interrupt occurs, a subroutine call to the SIMA/B interrupt vector at location 10H, will take place. When the interrupt is serviced, the SPIA/B interrupt request flag, SIFA/B, will be automatically reset and the EMI bit will be automatically cleared to disable other interrupts.

For an I²C interrupt to occur, the corresponding interrupt enable bit ESIIA/B must be first set. An actual I²C interrupt will be initialized when the SIMA/B interrupt request flag, SIFA/B, is set, a situation that will occur when a matching I²C slave address is received or from the completion of an I²C data byte transfer. When the interrupt is enabled, the stack is not full and a SIMA/B interrupt occurs, a subroutine call to the SIMA/B interrupt vector at location 14H, will take place. When an I²C interrupt occurs, the interrupt request flag SIFA/B will be reset and the EMI bit will be cleared to disable other interrupts.

Programming Considerations

By disabling the interrupt enable bits, a requested interrupt can be prevented from being serviced, however, once an interrupt request flag is set, it will remain in this condition in the INTC or INTCH register until the corresponding interrupt is serviced or until the request flag is cleared by a software instruction.

It is recommended that programs do not use the "CALL subroutine" instruction within the interrupt subroutine. Interrupts often occur in an unpredictable manner or need to be serviced immediately in some applications. If only one stack is left and the interrupt is not well controlled, the original control sequence will be damaged once a "CALL subroutine" is executed in the interrupt subroutine.

All of these interrupts have the capability of waking up the processor when in the Power Down Mode. Only the Program Counter is pushed onto the stack. If the contents of the register or status register are altered by the interrupt service program, which may corrupt the desired control sequence, then the contents should be saved in advance.

Reset and Initialisation

A reset function is a fundamental part of any microcontroller ensuring that the device can be set to some predetermined condition irrespective of outside parameters. The most important reset condition is after power is first applied to the microcontroller. In this case, internal circuitry will ensure that the microcontroller, after a short delay, will be in a well defined state and ready to execute the first program instruction. After this power-on reset, certain important internal registers will be set to defined states before the program commences. One of these registers is the Program Counter, which will be reset to zero forcing the microcontroller to begin program execution from the lowest Program Memory address.

In addition to the power-on reset, situations may arise where it is necessary to forcefully apply a reset condition when the microcontroller is running. One example of this is where after power has been applied and the microcontroller is already running, the RES line is forcefully pulled low. In such a case, known as a normal operation reset, some of the microcontroller registers remain unchanged allowing the microcontroller to proceed with normal operation after the reset line is allowed to return high. Another type of reset is when the Watchdog Timer overflows and resets the microcontroller. All types of reset operations result in different register conditions being setup.

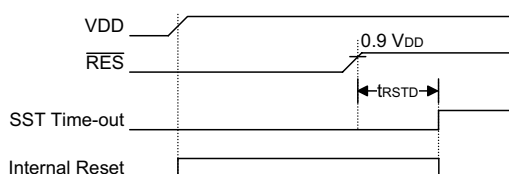
Reset Functions

There are five ways in which a microcontroller reset can occur, through events occurring both internally and externally.

Power-on Reset

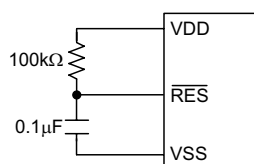
The most fundamental and unavoidable reset is the one that occurs after power is first applied to the microcontroller. As well as ensuring that the Program Memory begins execution from the first memory address, a power-on reset also ensures that certain other registers are preset to known conditions. All the I/O port and port control registers will power up in a high condition ensuring that all pins will be first set to inputs.

Although the microcontroller has an internal RC reset function, if the V_{DD} power supply rise time is not fast enough or does not stabilise quickly at power-on, the internal reset function may be incapable of providing proper reset operation. For this reason it is recommended that an external RC network is connected to the \overline{RES} pin, whose additional time delay will ensure that the \overline{RES} pin remains low for an extended period to allow the power supply to stabilise. During this time delay, normal operation of the microcontroller will be inhibited. After the \overline{RES} line reaches a certain voltage value, the reset delay time t_{RSTD} is invoked to provide an extra delay time after which the microcontroller will begin normal operation. The abbreviation SST in the figures stands for System Start-up Timer.



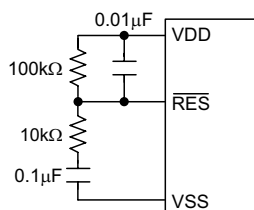
Power-On Reset Timing Chart

For most applications a resistor connected between V_{DD} and the \overline{RES} pin and a capacitor connected between V_{SS} and the \overline{RES} pin will provide a suitable external reset circuit. Any wiring connected to the \overline{RES} pin should be kept as short as possible to minimise any stray noise interference.



Basic Reset Circuit

For applications that operate within an environment where more noise is present the Enhanced Reset Circuit shown is recommended.

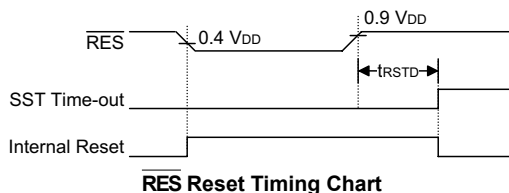


Enhanced Reset Circuit

More information regarding external reset circuits is located in Application Note HA0075E on the Holtek website.

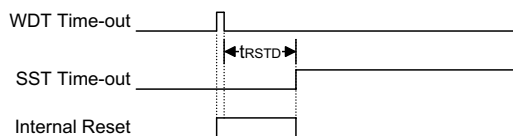
RES Pin Reset

This type of reset occurs when the microcontroller is already running and the $\overline{\text{RES}}$ pin is forcefully pulled low by external hardware such as an external switch. In this case as in the case of other reset, the Program Counter will reset to zero and program execution initiated from this point.



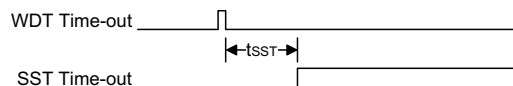
Watchdog Time-out Reset during Normal Operation

The Watchdog time-out Reset during normal operation is the same as a hardware $\overline{\text{RES}}$ pin reset except that the Watchdog time-out flag TO will be set to "1".



Watchdog Time-out Reset during Power Down

The Watchdog time-out Reset during Power Down is a little different from other kinds of reset. Most of the conditions remain unchanged except that the Program Counter and the Stack Pointer will be cleared to "0" and the TO flag will be set to "1". Refer to the A.C. Characteristics for t_{SST} details.



Reset Initial Conditions

The different types of reset described affect the reset flags in different ways. These flags, known as PDF and TO are located in the status register and are controlled by various microcontroller operations, such as the Power Down function or Watchdog Timer. The reset flags are shown in the table:

TO	PDF	RESET Conditions
0	0	$\overline{\text{RES}}$ reset during power-on
u	u	$\overline{\text{RES}}$ or LVR reset during normal operation
1	u	WDT time-out reset during normal operation
1	1	WDT time-out reset during Power Down

Note: "u" stands for unchanged

The following table indicates the way in which the various components of the microcontroller are affected after a power-on reset occurs.

Item	Condition After RESET
Program Counter	Reset to zero
Interrupts	All interrupts will be disabled
WDT	Clear after reset, WDT begins counting
Timer	All Timer will be turned off
Prescaler	The Timer Prescaler will be cleared
Input/Output Ports	I/O ports will be setup as inputs
Stack Pointer	Stack Pointer will point to the top of the stack

The different kinds of resets all affect the internal registers of the microcontroller in different ways. To ensure reliable continuation of normal program execution after a reset occurs, it is important to know what condition the microcontroller is in after a particular reset occurs. The following table describes how each type of reset affects each of the microcontroller internal registers. Note that where more than one package type exists the table will reflect the situation for the larger package type.

Register	Reset (Power-on)	WDT Time-out (Normal Operation)	RES Reset (Normal Operation)	RES Reset (HALT)	WDT Time-out from HALT
MP0	x x x x x x x x	u u u u u u u u	u u u u u u u u	u u u u u u u u	u u u u u u u u
ACC	x x x x x x x x	u u u u u u u u	u u u u u u u u	u u u u u u u u	u u u u u u u u
PCL	0 0 0 0 0 0 0 0	0 0 0 0 0 0 0 0	0 0 0 0 0 0 0 0	0 0 0 0 0 0 0 0	0 0 0 0 0 0 0 0
TBLP	x x x x x x x x	u u u u u u u u	u u u u u u u u	u u u u u u u u	u u u u u u u u
TBLH	x x x x x x x x	u u u u u u u u	u u u u u u u u	u u u u u u u u	u u u u u u u u
WDTS	0 0 0 0 0 1 1 1	0 0 0 0 0 1 1 1	0 0 0 0 0 1 1 1	0 0 0 0 0 1 1 1	u u u u u u u u
STATUS	-- 0 0 x x x x	-- 1 u u u u u	-- u u u u u u	-- 0 1 u u u u	-- 1 1 u u u u
INTC	- 0 0 0 0 0 0 0 0	- 0 0 0 0 0 0 0 0	- 0 0 0 0 0 0 0 0	- 0 0 0 0 0 0 0 0	- u u u u u u u u
TMR0	0 0 0 0 0 0 0 0	0 0 0 0 0 0 0 0	0 0 0 0 0 0 0 0	0 0 0 0 0 0 0 0	u u u u u u u u
TMR0C	0 1 0 0 0 0 0 0	0 1 0 0 0 0 0 0	0 1 0 0 0 0 0 0	0 1 0 0 0 0 0 0	u u u u u u u u
TMR1	0 0 0 0 0 0 0 0	0 0 0 0 0 0 0 0	0 0 0 0 0 0 0 0	0 0 0 0 0 0 0 0	u u u u u u u u
TMR1C	0 1 0 0 0 0 0 0	0 1 0 0 0 0 0 0	0 1 0 0 0 0 0 0	0 1 0 0 0 0 0 0	u u u u u u u u
PA	1 1 1 1 1 1 1 1	1 1 1 1 1 1 1 1	1 1 1 1 1 1 1 1	1 1 1 1 1 1 1 1	u u u u u u u u
PAC	1 1 1 1 1 1 1 1	1 1 1 1 1 1 1 1	1 1 1 1 1 1 1 1	1 1 1 1 1 1 1 1	u u u u u u u u
PB	1 1 1 1 1 1 1 1	1 1 1 1 1 1 1 1	1 1 1 1 1 1 1 1	1 1 1 1 1 1 1 1	u u u u u u u u
PBC	1 1 1 1 1 1 1 1	1 1 1 1 1 1 1 1	1 1 1 1 1 1 1 1	1 1 1 1 1 1 1 1	u u u u u u u u
PC	---- - 1 1 1	---- - 1 1 1	---- - 1 1 1	---- - 1 1 1	---- - u u u
PCC	---- - 1 1 1	---- - 1 1 1	---- - 1 1 1	---- - 1 1 1	---- - u u u
INTCH	-- 0 0 -- 0 0	-- 0 0 -- 0 0	-- 0 0 -- 0 0	-- 0 0 -- 0 0	-- u u -- u u
DAL	x x x x ----	u u u u ----	u u u u ----	u u u u ----	u u u u ----
DAH	x x x x x x x x	u u u u u u u u	u u u u u u u u	u u u u u u u u	u u u u u u u u
PWMC	0 --- 0 0 0 0	0 --- 0 0 0 0	0 --- 0 0 0 0	0 --- 0 0 0 0	u --- u u u u
PWML	x x x x ----	u u u u ----	u u u u ----	u u u u ----	u u u u ----
PWMH	x x x x x x x x	u u u u u u u u	u u u u u u u u	u u u u u u u u	u u u u u u u u
VOL	x x x x - x x x	u u u u - u u u	u u u u - u u u	u u u u - u u u	u u u u - u u u
SIMC0A	1 1 1 x x x 0 -	1 1 1 x x x 0 -	1 1 1 x x x 0 -	1 1 1 x x x 0 -	u u u x x x u -
SIMC1A	1 0 0 x x 0 x 1	1 0 0 x x 0 x 1	1 0 0 x x 0 x 1	1 0 0 x x 0 x 1	u u u x x u x u
SIMDRA	x x x x x x x x	x x x x x x x x	x x x x x x x x	x x x x x x x x	x x x x x x x x
SIMARA/ SIMC2A	0 0 0 0 0 0 0 0	0 0 0 0 0 0 0 0	0 0 0 0 0 0 0 0	0 0 0 0 0 0 0 0	u u u u u u u u
SIMC0B	1 1 1 x x x 0 -	1 1 1 x x x 0 -	1 1 1 x x x 0 -	1 1 1 x x x 0 -	u u u x x x u -
SIMC1B	1 0 0 x x 0 x 1	1 0 0 x x 0 x 1	1 0 0 x x 0 x 1	1 0 0 x x 0 x 1	u u u x x u x u
SIMDRB	x x x x x x x x	x x x x x x x x	x x x x x x x x	x x x x x x x x	x x x x x x x x
SIMARB/ SIMC2B	0 0 0 0 0 0 0 0	0 0 0 0 0 0 0 0	0 0 0 0 0 0 0 0	0 0 0 0 0 0 0 0	u u u u u u u u
PCPHC	---- - 0 0 0	---- - 0 0 0	---- - 0 0 0	---- - 0 0 0	---- - u u u

Note: "u" stands for unchanged
"x" stands for unknown
"-" stands for undefined

Oscillator

Various oscillator options offer the user a wide range of functions according to their various application requirements. Three types of system clocks can be selected while various clock source options for the Watchdog Timer are provided for maximum flexibility. All oscillator options are selected through the configuration options.

The three methods of generating the system clock are:

- External crystal/resonator oscillator
- External RC oscillator
- Internal RC oscillator

One of these three methods must be selected using the configuration options.

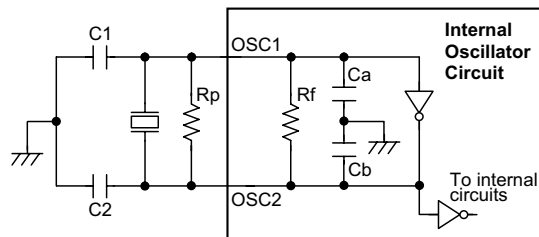
More information regarding the oscillator is located in Application Note HA0075E on the Holtek website.

External Crystal/Resonator Oscillator

The simple connection of a crystal across OSC1 and OSC2 will create the necessary phase shift and feedback for oscillation, and will normally not require external capacitors. However, for some crystals and most resonator types, to ensure oscillation and accurate frequency generation, it may be necessary to add two small value external capacitors, C1 and C2. The exact values of C1 and C2 should be selected in consultation with the crystal or resonator manufacturer's specification. The external parallel feedback resistor, Rp, is normally not required but in some cases may be needed to assist with oscillation start up.

Internal Ca, Cb, Rf Typical Values @ 5V, 25°C		
Ca	Cb	Rf
11~13pF	13~15pF	800kΩ

Oscillator Internal Component Values

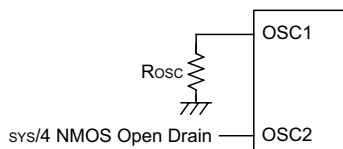


- Note:
1. Rp is normally not required.
 2. Although not shown OSC1/OSC2 pins have a parasitic capacitance of around 7pF.

Crystal/Resonator Oscillator

External RC Oscillator

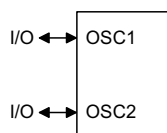
Using the external system RC oscillator requires that a resistor, with a value between 150k Ω and 300k Ω , is connected between OSC1 and VSS. The generated system clock divided by 4 will be provided on OSC2 as an output which can be used for external synchronization purposes. Note that as the OSC2 output is an NMOS open-drain type, a pull high resistor should be connected if it is to be used to monitor the internal frequency. Although this is a cost effective oscillator configuration, the oscillation frequency can vary with VDD, temperature and process variations and is therefore not suitable for applications where timing is critical or where accurate oscillator frequencies are required. For the value of the external resistor R_{osc} refer to the Holtek website for typical RC Oscillator vs. Temperature and VDD characteristics graphics. Note that it is the only microcontroller internal circuitry together with the external resistor, that determine the frequency of the oscillator. The external capacitor shown on the diagram does not influence the frequency of oscillation.



External RC Oscillator

Internal RC Oscillator

The internal RC oscillator is a fully integrated system oscillator requiring no external components. The internal RC oscillator has three fixed frequencies of either 4MHz, 8MHz or 12MHz selected by configuration options. Device trimming during the manufacturing process and the inclusion of internal frequency compensation circuits are used to ensure that the influence of the power supply voltage, temperature and process variations on the oscillation frequency are minimised. As a result, at a power supply of either 3.3V or 5V and at a temperature of 25° degrees, the fixed oscillation frequency of 4MHz, 8MHz or 12MHz will have a tolerance within 2%. Note that if this internal system clock option is selected, as it requires no external pins for its operation, I/O pins PC1 and PC2 are free for use as normal I/O pins.



Internal RC Oscillator -- HIRC

Watchdog Timer Oscillator

The WDT oscillator is a fully self-contained free running on-chip RC oscillator with a typical period of 65 μ s at 5V requiring no external components. When the device enters the Power Down Mode, the system clock will stop running but the WDT oscillator continues to free-run and to keep the watchdog active. However, to preserve power in certain applications the WDT oscillator can be disabled via a configuration option.

Power Down Mode and Wake-up

Power Down Mode

All of the Holtek microcontrollers have the ability to enter a Power Down Mode, also known as the "HALT" Mode or Sleep Mode. When the device enters this mode, the normal operating current, will be reduced to an extremely low standby current level. This occurs because when the device enters the Power Down Mode, the system oscillator is stopped which reduces the power consumption to extremely low levels, however, as the device maintains its present internal condition, it can be woken up at a later stage and continue running, without requiring a full reset. This feature is extremely important in application areas where the MCU must have its power supply constantly maintained to keep the device in a known condition but where the power supply capacity is limited such as in battery applications.

Entering the Power Down Mode

There is only one way for the device to enter the Power Down Mode and that is to execute the "HALT" instruction in the application program. When this instruction is executed, the following will occur:

- The system oscillator will stop running and the application program will stop at the "HALT" instruction.
- The Data Memory contents and registers will maintain their present condition.
- The WDT will be cleared and resume counting if the WDT clock source is selected to come from the WDT oscillator. The WDT will stop if its clock source originates from the system clock.
- The I/O ports will maintain their present condition.
- In the status register, the Power Down flag, PDF, will be set and the Watchdog time-out flag, TO, will be cleared.

Standby Current Considerations

As the main reason for entering the Power Down Mode is to keep the current consumption of the MCU to as low a value as possible, perhaps only in the order of several micro-amps, there are other considerations which must also be taken into account by the circuit designer if the power consumption is to be minimized. Special attention must be made to the I/O pins on the device. All high-impedance input pins must be connected to either a fixed high or low level as any floating input pins could create internal oscillations and result in increased current consumption. Care must also be taken with the loads, which are connected to I/Os, which are setup as outputs. These should be placed in a condition in which minimum current is drawn or connected only to external circuits that do not draw current, such as other CMOS inputs. Also note that additional standby current will also be required if the configuration options have enabled the Watchdog Timer internal oscillator.

Wake-up

After the system enters the Power Down Mode, it can be woken up from one of various sources listed as follows:

- An external reset
- An external falling edge on Port A
- A system interrupt
- A WDT overflow

If the system is woken up by an external reset, the device will experience a full system reset, however, if the device is woken up by a WDT overflow, a Watchdog Timer reset will be initiated. Although both of these wake-up methods will initiate a reset operation, the actual source of the wake-up can be determined by examining the TO and PDF flags. The PDF flag is cleared by a system power-up or executing the clear Watchdog Timer instructions and is set when executing the "HALT" instruction. The TO flag is set if a WDT time-out occurs, and causes a wake-up that only resets the Program Counter and Stack Pointer, the other flags remain in their original status.

Each pin on Port A can be setup via an individual configuration option to permit a negative transition on the pin to wake-up the system. When a Port A pin wake-up occurs, the program will resume execution at the instruction following the "HALT" instruction.

If the system is woken up by an interrupt, then two possible situations may occur. The first is where the related interrupt is disabled or the interrupt is enabled but the stack is full, in which case the program will resume execution at the instruction following the "HALT" instruction. In this situation, the interrupt which woke-up the device will not be immediately serviced, but will rather be serviced later when the related interrupt is finally enabled or when a stack level becomes free. The other situation is where the related interrupt is enabled and the stack is not full, in which case the regular interrupt response takes place. If an interrupt request flag is set to "1" before entering the Power Down Mode, the wake-up function of the related interrupt will be disabled.

No matter what the source of the wake-up event is, once a wake-up situation occurs, a time period equal to 1024 system clock periods will be required before normal system operation resumes. However, if the wake-up has originated due to an interrupt, the actual interrupt subroutine execution will be delayed by an additional one or more cycles. If the wake-up results in the execution of the next instruction following the "HALT" instruction, this will be executed immediately after the 1024 system clock period delay has ended.

Low Voltage Reset - LVR

The microcontroller contains a low voltage reset circuit in order to monitor the supply voltage of the device, which is selected via a configuration option. If the supply voltage of the device drops to within a range of $0.9V \sim V_{LVR}$ such as might occur when changing the battery, the LVR will automatically reset the device internally.

Low Voltage Detector - LVD

This Low Voltage Detect internal function provides a means for the user to monitor when the power supply voltage falls below a certain fixed level as specified in the DC characteristics. Bit 2 of PWMC register and Low Voltage Detector option are used to control the overall function of the LVD. Low Voltage Detector option is the enable/disable control bit, when select disable the overall function of the LVD will be disabled.

Bit 2 is the LVD detector output bit and is known as LVDF. Under normal operation, and when the power supply voltage is above the specified VLVD value in the DC characteristic section, the LVDF bit will remain at a zero value. If the power supply voltage should fall below this VLVD value then the LVDF bit will change to a high value indicating a low voltage condition. Note that the LVDF bit is a read-only bit. By polling the LVDF bit in the PWMC register, the application program can therefore determine the presence of a low voltage condition.

Operation

The Low Voltage Detector must first be enabled using a configuration option.

The LVD control bit is bit 2 of the PWMC register and is known as LVDF. Under normal operation, and when the power supply voltage is above the specified VLVD value in the DC characteristic section, the LVDF bit will remain at a zero value. If the power supply voltage should fall below this VLVD value then the LVDF bit will change to a high value indicating a low voltage condition. Note that the LVDF bit is a read-only bit. By polling the LVDF bit in the PWMC register, the application program can therefore determine the presence of a low voltage condition.

Watchdog Timer

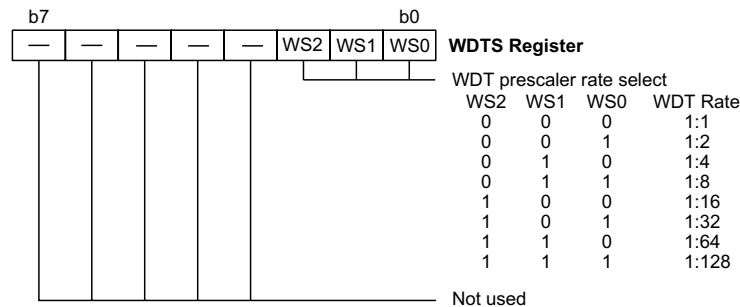
The Watchdog Timer is provided to prevent program malfunctions or sequences from jumping to unknown locations, due to certain uncontrollable external events such as electrical noise. It operates by providing a device reset when the WDT counter overflows. The WDT clock is supplied by one of two sources selected by configuration option: its own self-contained dedicated internal WDT oscillator, or the instruction clock which is the system clock divided by 4. Note that if the WDT configuration option has been disabled, then any instruction relating to its operation will result in no operation.

The internal WDT oscillator has an approximate period of 65 μ s at a supply voltage of 5V. If selected, it is first divided by 256 via an 8-stage counter to give a nominal period of 17ms. Note that this period can vary with VDD, temperature and process variations. For longer WDT time-out periods the WDT prescaler can be utilized. By writing the required value to bits 0, 1 and 2 of the WDTS register, known as WS0, WS1 and WS2, longer time-out periods can be achieved. With WS0, WS1 and WS2 all equal to 1, the division ratio is 1:128 which gives a maximum time-out period of about 2.1s.

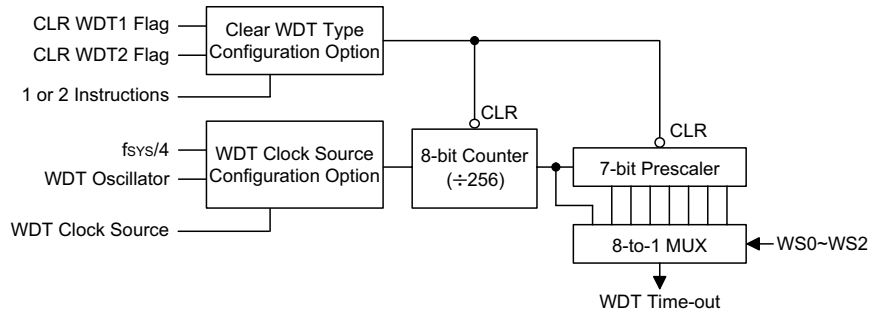
A configuration option can select the instruction clock, which is the system clock divided by 4, as the WDT clock source instead of the internal WDT oscillator. If the instruction clock is used as the clock source, it must be noted that when the system enters the Power Down Mode, as the system clock is stopped, then the WDT clock source will also be stopped. Therefore the WDT will lose its protecting purposes. In such cases the system cannot be restarted by the WDT and can only be restarted using external signals. For systems that operate in noisy environments, using the internal WDT oscillator is therefore the recommended choice.

Under normal program operation, a WDT time-out will initialise a device reset and set the status bit TO. However, if the system is in the Power Down Mode, when a WDT time-out occurs, only the Program Counter and Stack Pointer will be reset. Three methods can be adopted to clear the contents of the WDT and the WDT prescaler. The first is an external hardware reset, which means a low level on the $\overline{\text{RES}}$ pin, the second is using the watchdog software instructions and the third is via a "HALT" instruction.

There are two methods of using software instructions to clear the Watchdog Timer, one of which must be chosen by configuration option. The first option is to use the single "CLR WDT" instruction while the second is to use the two commands "CLR WDT1" and "CLR WDT2". For the first option, a simple execution of "CLR WDT" will clear the WDT while for the second option, both "CLR WDT1" and "CLR WDT2" must both be executed to successfully clear the WDT. Note that for this second option, if "CLR WDT1" is used to clear the WDT, successive executions of this instruction will have no effect, only the execution of a "CLR WDT2" instruction will clear the WDT. Similarly, after the "CLR WDT2" instruction has been executed, only a successive "CLR WDT1" instruction can clear the Watchdog Timer.



Watchdog Timer Register



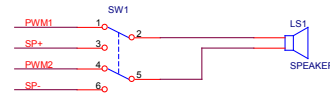
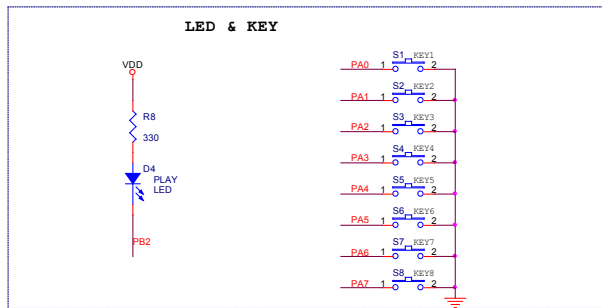
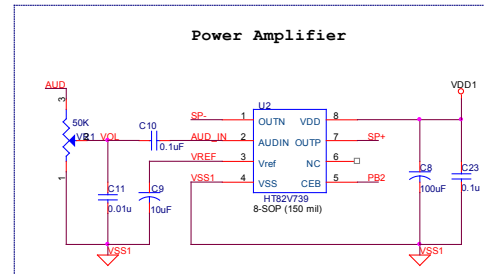
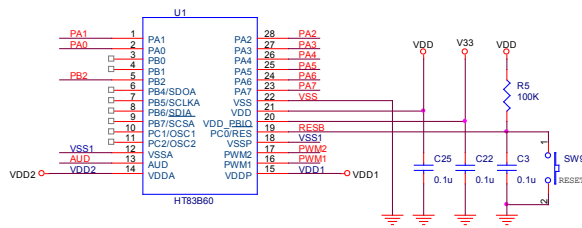
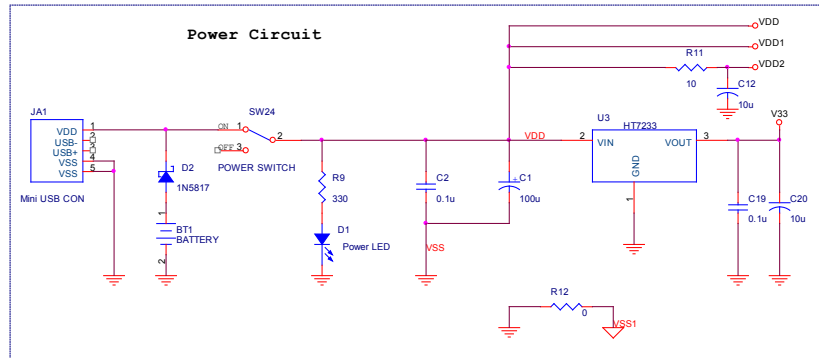
Watchdog Timer

Configuration Options

Configuration options refer to certain options within the MCU that are programmed into the device during the programming process. During the development process, these options are selected using the HT-IDE software development tools. As these options are programmed into the device using the hardware programming tools, once they are selected they cannot be changed later by the application software.

No.	Options
I/O Options	
1	PA0~PA7: wake-up enable or disable
2	PA0~PA7: pull-high enable or disable
3	PB0~PB7: pull-high enable or disable
Oscillator Options	
4	OSC type selection: ERC, crystal or HIRC
HIRC Options	
5	HIRC option: 4MHz, 8MHz, 12MHz
Watchdog Options	
6	WDT: enable or disable
7	WDT clock source: WDTOSC or T1
PB I/O Port Output Voltage Options	
8	VDD_PBIO/VDD type selection: VDD_PBIO or VDD for Port B, SPI, I ² C I/O per bit
LVR Option	
9	LVR function: enable or disable
LVD Option	
10	LVD function: enable or disable
Reset Options	
11	Reset function: PC0 or reset pin
SIMA Options	
12	SIMA Function: enable or disable
13	SPIA S/W CSEN: enable or disable
14	SPIA S/W WCOL: enable or disable
15	I ² CA RNIC: enable or disable
16	I ² CA debounce time: 0/1/2 system clocks
SIMB Options	
17	SIMB Function: enable or disable
18	SPIB S/W CSEN: enable or disable
19	SPIB S/W WCOL: enable or disable
20	I ² CB RNIC: enable or disable
21	I ² CB debounce time: 0/1/2 system clocks

Application Circuits



Instruction Set

Introduction

Central to the successful operation of any microcontroller is its instruction set, which is a set of program instruction codes that directs the microcontroller to perform certain operations. In the case of Holtek microcontrollers, a comprehensive and flexible set of over 60 instructions is provided to enable programmers to implement their application with the minimum of programming overheads.

For easier understanding of the various instruction codes, they have been subdivided into several functional groupings.

Instruction Timing

Most instructions are implemented within one instruction cycle. The exceptions to this are branch, call, or table read instructions where two instruction cycles are required. One instruction cycle is equal to 4 system clock cycles, therefore in the case of an 8MHz system oscillator, most instructions would be implemented within 0.5 μ s and branch or call instructions would be implemented within 1 μ s. Although instructions which require one more cycle to implement are generally limited to the JMP, CALL, RET, RETI and table read instructions, it is important to realize that any other instructions which involve manipulation of the Program Counter Low register or PCL will also take one more cycle to implement. As instructions which change the contents of the PCL will imply a direct jump to that new address, one more cycle will be required. Examples of such instructions would be "CLR PCL" or "MOV PCL, A". For the case of skip instructions, it must be noted that if the result of the comparison involves a skip operation then this will also take one more cycle, if no skip is involved then only one cycle is required.

Moving and Transferring Data

The transfer of data within the microcontroller program is one of the most frequently used operations. Making use of three kinds of MOV instructions, data can be transferred from registers to the Accumulator and vice-versa as well as being able to move specific immediate data directly into the Accumulator. One of the most important data transfer applications is to receive data from the input ports and transfer data to the output ports.

Arithmetic Operations

The ability to perform certain arithmetic operations and data manipulation is a necessary feature of most microcontroller applications. Within the Holtek microcontroller instruction set are a range of add and subtract instruction mnemonics to enable the necessary arithmetic to be carried out. Care must be taken to ensure correct handling of carry and borrow data when results exceed 255 for addition and less than 0 for subtraction. The increment and decrement instructions INC, INCA, DEC and DECA provide a simple means of increasing or decreasing by a value of one of the values in the destination specified.

Logical and Rotate Operations

The standard logical operations such as AND, OR, XOR and CPL all have their own instruction within the Holtek microcontroller instruction set. As with the case of most instructions involving data manipulation, data must pass through the Accumulator which may involve additional programming steps. In all logical data operations, the zero flag may be set if the result of the operation is zero. Another form of logical data manipulation comes from the rotate instructions such as RR, RL, RRC and RLC which provide a simple means of rotating one bit right or left. Different rotate instructions exist depending on program requirements. Rotate instructions are useful for serial port programming applications where data can be rotated from an internal register into the Carry bit from where it can be examined and the necessary serial bit set high or low. Another application where rotate data operations are used is to implement multiplication and division calculations.

Branches and Control Transfer

Program branching takes the form of either jumps to specified locations using the JMP instruction or to a subroutine using the CALL instruction. They differ in the sense that in the case of a subroutine call, the program must return to the instruction immediately when the subroutine has been carried out. This is done by placing a return instruction RET in the subroutine which will cause the program to jump back to the address right after the CALL instruction. In the case of a JMP instruction, the program simply jumps to the desired location. There is no requirement to jump back to the original jumping off point as in the case of the CALL instruction. One special and extremely useful set of branch instructions are the conditional branches. Here a decision is first made regarding the condition of a certain data memory or individual bits. Depending upon the conditions, the program will continue with the next instruction or skip over it and jump to the following instruction. These instructions are the key to decision making and branching within the program perhaps determined by the condition of certain input switches or by the condition of internal data bits.

Bit Operations

The ability to provide single bit operations on Data Memory is an extremely flexible feature of all Holtek microcontrollers. This feature is especially useful for output port bit programming where individual bits or port pins can be directly set high or low using either the "SET [m].i" or "CLR [m].i" instructions respectively. The feature removes the need for programmers to first read the 8-bit output port, manipulate the input data to ensure that other bits are not changed and then output the port with the correct new data. This read-modify-write process is taken care of automatically when these bit operation instructions are used.

Table Read Operations

Data storage is normally implemented by using registers. However, when working with large amounts of fixed data, the volume involved often makes it inconvenient to store the fixed data in the Data Memory. To overcome this problem, Holtek microcontrollers allow an area of Program Memory to be setup as a table where data can be directly stored. A set of easy to use instructions provides the means by which this fixed data can be referenced and retrieved from the Program Memory.

Other Operations

In addition to the above functional instructions, a range of other instructions also exist such as the "HALT" instruction for Power-down operations and instructions to control the operation of the Watchdog Timer for reliable program operations under extreme electric or electromagnetic environments. For their relevant operations, refer to the functional related sections.

Instruction Set Summary

The following table depicts a summary of the instruction set categorised according to function and can be consulted as a basic instruction reference using the following listed conventions.

Table conventions:

x: Bits immediate data

m: Data Memory address

A: Accumulator

i: 0~7 number of bits

addr: Program memory address

Mnemonic	Description	Cycles	Flag Affected
Arithmetic			
ADD A,[m]	Add Data Memory to ACC	1	Z, C, AC, OV
ADDM A,[m]	Add ACC to Data Memory	1 ^{Note}	Z, C, AC, OV
ADD A,x	Add immediate data to ACC	1	Z, C, AC, OV
ADC A,[m]	Add Data Memory to ACC with Carry	1	Z, C, AC, OV
ADCM A,[m]	Add ACC to Data memory with Carry	1 ^{Note}	Z, C, AC, OV
SUB A,x	Subtract immediate data from the ACC	1	Z, C, AC, OV
SUB A,[m]	Subtract Data Memory from ACC	1	Z, C, AC, OV
SUBM A,[m]	Subtract Data Memory from ACC with result in Data Memory	1 ^{Note}	Z, C, AC, OV
SBC A,[m]	Subtract Data Memory from ACC with Carry	1	Z, C, AC, OV
SBCM A,[m]	Subtract Data Memory from ACC with Carry, result in Data Memory	1 ^{Note}	Z, C, AC, OV
DAA [m]	Decimal adjust ACC for Addition with result in Data Memory	1 ^{Note}	C
Logic Operation			
AND A,[m]	Logical AND Data Memory to ACC	1	Z
OR A,[m]	Logical OR Data Memory to ACC	1	Z
XOR A,[m]	Logical XOR Data Memory to ACC	1	Z
ANDM A,[m]	Logical AND ACC to Data Memory	1 ^{Note}	Z
ORM A,[m]	Logical OR ACC to Data Memory	1 ^{Note}	Z
XORM A,[m]	Logical XOR ACC to Data Memory	1 ^{Note}	Z
AND A,x	Logical AND immediate Data to ACC	1	Z
OR A,x	Logical OR immediate Data to ACC	1	Z
XOR A,x	Logical XOR immediate Data to ACC	1	Z
CPL [m]	Complement Data Memory	1 ^{Note}	Z
CPLA [m]	Complement Data Memory with result in ACC	1	Z
Increment & Decrement			
INCA [m]	Increment Data Memory with result in ACC	1	Z
INC [m]	Increment Data Memory	1 ^{Note}	Z
DECA [m]	Decrement Data Memory with result in ACC	1	Z
DEC [m]	Decrement Data Memory	1 ^{Note}	Z
Rotate			
RRA [m]	Rotate Data Memory right with result in ACC	1	None
RR [m]	Rotate Data Memory right	1 ^{Note}	None
RRCA [m]	Rotate Data Memory right through Carry with result in ACC	1	C
RRC [m]	Rotate Data Memory right through Carry	1 ^{Note}	C
RLA [m]	Rotate Data Memory left with result in ACC	1	None
RL [m]	Rotate Data Memory left	1 ^{Note}	None
RLCA [m]	Rotate Data Memory left through Carry with result in ACC	1	C
RLC [m]	Rotate Data Memory left through Carry	1 ^{Note}	C
Data Move			
MOV A,[m]	Move Data Memory to ACC	1	None
MOV [m],A	Move ACC to Data Memory	1 ^{Note}	None
MOV A,x	Move immediate data to ACC	1	None
Bit Operation			
CLR [m].i	Clear bit of Data Memory	1 ^{Note}	None
SET [m].i	Set bit of Data Memory	1 ^{Note}	None

Mnemonic	Description	Cycles	Flag Affected
Branch			
JMP addr	Jump unconditionally	2	None
SZ [m]	Skip if Data Memory is zero	1 ^{Note}	None
SZA [m]	Skip if Data Memory is zero with data movement to ACC	1 ^{note}	None
SZ [m].i	Skip if bit i of Data Memory is zero	1 ^{Note}	None
SNZ [m].i	Skip if bit i of Data Memory is not zero	1 ^{Note}	None
SIZ [m]	Skip if increment Data Memory is zero	1 ^{Note}	None
SDZ [m]	Skip if decrement Data Memory is zero	1 ^{Note}	None
SIZA [m]	Skip if increment Data Memory is zero with result in ACC	1 ^{Note}	None
SDZA [m]	Skip if decrement Data Memory is zero with result in ACC	1 ^{Note}	None
CALL addr	Subroutine call	2	None
RET	Return from subroutine	2	None
RET A,x	Return from subroutine and load immediate data to ACC	2	None
RETI	Return from interrupt	2	None
Table Read			
TABRDC [m]	Read table (current page) to TBLH and Data Memory	2 ^{Note}	None
TABRDL [m]	Read table (last page) to TBLH and Data Memory	2 ^{Note}	None
Miscellaneous			
NOP	No operation	1	None
CLR [m]	Clear Data Memory	1 ^{Note}	None
SET [m]	Set Data Memory	1 ^{Note}	None
CLR WDT	Clear Watchdog Timer	1	TO, PDF
CLR WDT1	Pre-clear Watchdog Timer	1	TO, PDF
CLR WDT2	Pre-clear Watchdog Timer	1	TO, PDF
SWAP [m]	Swap nibbles of Data Memory	1 ^{Note}	None
SWAPA [m]	Swap nibbles of Data Memory with result in ACC	1	None
HALT	Enter power down mode	1	TO, PDF

Note: 1. For skip instructions, if the result of the comparison involves a skip then two cycles are required, if no skip takes place only one cycle is required.

- Any instruction which changes the contents of the PCL will also require 2 cycles for execution.
- For the "CLR WDT1" and "CLR WDT2" instructions the TO and PDF flags may be affected by the execution status. The TO and PDF flags are cleared after both "CLR WDT1" and "CLR WDT2" instructions are consecutively executed. Otherwise the TO and PDF flags remain unchanged.

Instruction Definition

ADC A,[m]	Add Data Memory to ACC with Carry
Description	The contents of the specified Data Memory, Accumulator and the carry flag are added. The result is stored in the Accumulator.
Operation	$ACC \leftarrow ACC + [m] + C$
Affected flag(s)	OV, Z, AC, C
ADCM A,[m]	Add ACC to Data Memory with Carry
Description	The contents of the specified Data Memory, Accumulator and the carry flag are added. The result is stored in the specified Data Memory.
Operation	$[m] \leftarrow ACC + [m] + C$
Affected flag(s)	OV, Z, AC, C
ADD A,[m]	Add Data Memory to ACC
Description	The contents of the specified Data Memory and the Accumulator are added. The result is stored in the Accumulator.
Operation	$ACC \leftarrow ACC + [m]$
Affected flag(s)	OV, Z, AC, C
ADD A,x	Add immediate data to ACC
Description	The contents of the Accumulator and the specified immediate data are added. The result is stored in the Accumulator.
Operation	$ACC \leftarrow ACC + x$
Affected flag(s)	OV, Z, AC, C
ADDM A,[m]	Add ACC to Data Memory
Description	The contents of the specified Data Memory and the Accumulator are added. The result is stored in the specified Data Memory.
Operation	$[m] \leftarrow ACC + [m]$
Affected flag(s)	OV, Z, AC, C
AND A,[m]	Logical AND Data Memory to ACC
Description	Data in the Accumulator and the specified Data Memory perform a bitwise logical AND operation. The result is stored in the Accumulator.
Operation	$ACC \leftarrow ACC \text{ "AND" } [m]$
Affected flag(s)	Z
AND A,x	Logical AND immediate data to ACC
Description	Data in the Accumulator and the specified immediate data perform a bit wise logical AND operation. The result is stored in the Accumulator.
Operation	$ACC \leftarrow ACC \text{ "AND" } x$
Affected flag(s)	Z
ANDM A,[m]	Logical AND ACC to Data Memory
Description	Data in the specified Data Memory and the Accumulator perform a bitwise logical AND operation. The result is stored in the Data Memory.
Operation	$[m] \leftarrow ACC \text{ "AND" } [m]$
Affected flag(s)	Z

CALL addr	Subroutine call
Description	Unconditionally calls a subroutine at the specified address. The Program Counter then increments by 1 to obtain the address of the next instruction which is then pushed onto the stack. The specified address is then loaded and the program continues execution from this new address. As this instruction requires an additional operation, it is a two cycle instruction.
Operation	Stack ← Program Counter + 1 Program Counter ← addr
Affected flag(s)	None
CLR [m]	Clear Data Memory
Description	Each bit of the specified Data Memory is cleared to 0.
Operation	[m] ← 00H
Affected flag(s)	None
CLR [m].i	Clear bit of Data Memory
Description	Bit i of the specified Data Memory is cleared to 0.
Operation	[m].i ← 0
Affected flag(s)	None
CLR WDT	Clear Watchdog Timer
Description	The TO, PDF flags and the WDT are all cleared.
Operation	WDT cleared TO ← 0 PDF ← 0
Affected flag(s)	TO, PDF
CLR WDT1	Pre-clear Watchdog Timer
Description	The TO, PDF flags and the WDT are all cleared. Note that this instruction works in conjunction with CLR WDT2 and must be executed alternately with CLR WDT2 to have effect. Repetitively executing this instruction without alternately executing CLR WDT2 will have no effect.
Operation	WDT cleared TO ← 0 PDF ← 0
Affected flag(s)	TO, PDF
CLR WDT2	Pre-clear Watchdog Timer
Description	The TO, PDF flags and the WDT are all cleared. Note that this instruction works in conjunction with CLR WDT1 and must be executed alternately with CLR WDT1 to have effect. Repetitively executing this instruction without alternately executing CLR WDT1 will have no effect.
Operation	WDT cleared TO ← 0 PDF ← 0
Affected flag(s)	TO, PDF
CPL [m]	Complement Data Memory
Description	Each bit of the specified Data Memory is logically complemented (1's complement). Bits which previously contained a 1 are changed to 0 and vice versa.
Operation	[m] ← $\overline{[m]}$
Affected flag(s)	Z

CPLA [m]	Complement Data Memory with result in ACC
Description	Each bit of the specified Data Memory is logically complemented (1's complement). Bits which previously contained a 1 are changed to 0 and vice versa. The complemented result is stored in the Accumulator and the contents of the Data Memory remain unchanged.
Operation	$ACC \leftarrow \overline{[m]}$
Affected flag(s)	Z
DAA [m]	Decimal-Adjust ACC for addition with result in Data Memory
Description	Convert the contents of the Accumulator value to a BCD (Binary Coded Decimal) value resulting from the previous addition of two BCD variables. If the low nibble is greater than 9 or if AC flag is set, then a value of 6 will be added to the low nibble. Otherwise the low nibble remains unchanged. If the high nibble is greater than 9 or if the C flag is set, then a value of 6 will be added to the high nibble. Essentially, the decimal conversion is performed by adding 00H, 06H, 60H or 66H depending on the Accumulator and flag conditions. Only the C flag may be affected by this instruction which indicates that if the original BCD sum is greater than 100, it allows multiple precision decimal addition.
Operation	$[m] \leftarrow ACC + 00H$ or $[m] \leftarrow ACC + 06H$ or $[m] \leftarrow ACC + 60H$ or $[m] \leftarrow ACC + 66H$
Affected flag(s)	C
DEC [m]	Decrement Data Memory
Description	Data in the specified Data Memory is decremented by 1.
Operation	$[m] \leftarrow [m] - 1$
Affected flag(s)	Z
DECA [m]	Decrement Data Memory with result in ACC
Description	Data in the specified Data Memory is decremented by 1. The result is stored in the Accumulator. The contents of the Data Memory remain unchanged.
Operation	$ACC \leftarrow [m] - 1$
Affected flag(s)	Z
HALT	Enter power down mode
Description	This instruction stops the program execution and turns off the system clock. The contents of the Data Memory and registers are retained. The WDT and prescaler are cleared. The power down flag PDF is set and the WDT time-out flag TO is cleared.
Operation	TO \leftarrow 0 PDF \leftarrow 1
Affected flag(s)	TO, PDF
INC [m]	Increment Data Memory
Description	Data in the specified Data Memory is incremented by 1.
Operation	$[m] \leftarrow [m] + 1$
Affected flag(s)	Z
INCA [m]	Increment Data Memory with result in ACC
Description	Data in the specified Data Memory is incremented by 1. The result is stored in the Accumulator. The contents of the Data Memory remain unchanged.
Operation	$ACC \leftarrow [m] + 1$
Affected flag(s)	Z

JMP addr	Jump unconditionally
Description	The contents of the Program Counter are replaced with the specified address. Program execution then continues from this new address. As this requires the insertion of a dummy instruction while the new address is loaded, it is a two cycle instruction.
Operation	Program Counter ← addr
Affected flag(s)	None
MOV A,[m]	Move Data Memory to ACC
Description	The contents of the specified Data Memory are copied to the Accumulator.
Operation	ACC ← [m]
Affected flag(s)	None
MOV A,x	Move immediate data to ACC
Description	The immediate data specified is loaded into the Accumulator.
Operation	ACC ← x
Affected flag(s)	None
MOV [m],A	Move ACC to Data Memory
Description	The contents of the Accumulator are copied to the specified Data Memory.
Operation	[m] ← ACC
Affected flag(s)	None
NOP	No operation
Description	No operation is performed. Execution continues with the next instruction.
Operation	No operation
Affected flag(s)	None
OR A,[m]	Logical OR Data Memory to ACC
Description	Data in the Accumulator and the specified Data Memory perform a bitwise logical OR operation. The result is stored in the Accumulator.
Operation	ACC ← ACC "OR" [m]
Affected flag(s)	Z
OR A,x	Logical OR immediate data to ACC
Description	Data in the Accumulator and the specified immediate data perform a bitwise logical OR operation. The result is stored in the Accumulator.
Operation	ACC ← ACC "OR" x
Affected flag(s)	Z
ORM A,[m]	Logical OR ACC to Data Memory
Description	Data in the specified Data Memory and the Accumulator perform a bitwise logical OR operation. The result is stored in the Data Memory.
Operation	[m] ← ACC "OR" [m]
Affected flag(s)	Z
RET	Return from subroutine
Description	The Program Counter is restored from the stack. Program execution continues at the restored address.
Operation	Program Counter ← Stack
Affected flag(s)	None

RET A,x	Return from subroutine and load immediate data to ACC
Description	The Program Counter is restored from the stack and the Accumulator loaded with the specified immediate data. Program execution continues at the restored address.
Operation	Program Counter ← Stack ACC ← x
Affected flag(s)	None
RETI	Return from interrupt
Description	The Program Counter is restored from the stack and the interrupts are re-enabled by setting the EMI bit. EMI is the master interrupt global enable bit. If an interrupt was pending when the RETI instruction is executed, the pending Interrupt routine will be processed before returning to the main program.
Operation	Program Counter ← Stack EMI ← 1
Affected flag(s)	None
RL [m]	Rotate Data Memory left
Description	The contents of the specified Data Memory are rotated left by 1 bit with bit 7 rotated into bit 0.
Operation	[m].(i+1) ← [m].i; (i = 0~6) [m].0 ← [m].7
Affected flag(s)	None
RLA [m]	Rotate Data Memory left with result in ACC
Description	The contents of the specified Data Memory are rotated left by 1 bit with bit 7 rotated into bit 0. The rotated result is stored in the Accumulator and the contents of the Data Memory remain unchanged.
Operation	ACC.(i+1) ← [m].i; (i = 0~6) ACC.0 ← [m].7
Affected flag(s)	None
RLC [m]	Rotate Data Memory left through Carry
Description	The contents of the specified Data Memory and the carry flag are rotated left by 1 bit. Bit 7 replaces the Carry bit and the original carry flag is rotated into bit 0.
Operation	[m].(i+1) ← [m].i; (i = 0~6) [m].0 ← C C ← [m].7
Affected flag(s)	C
RLCA [m]	Rotate Data Memory left through Carry with result in ACC
Description	Data in the specified Data Memory and the carry flag are rotated left by 1 bit. Bit 7 replaces the Carry bit and the original carry flag is rotated into the bit 0. The rotated result is stored in the Accumulator and the contents of the Data Memory remain unchanged.
Operation	ACC.(i+1) ← [m].i; (i = 0~6) ACC.0 ← C C ← [m].7
Affected flag(s)	C
RR [m]	Rotate Data Memory right
Description	The contents of the specified Data Memory are rotated right by 1 bit with bit 0 rotated into bit 7.
Operation	[m].i ← [m].(i+1); (i = 0~6) [m].7 ← [m].0
Affected flag(s)	None

RRA [m]	Rotate Data Memory right with result in ACC
Description	Data in the specified Data Memory and the carry flag are rotated right by 1 bit with bit 0 rotated into bit 7. The rotated result is stored in the Accumulator and the contents of the Data Memory remain unchanged.
Operation	$ACC.i \leftarrow [m].(i+1); (i = 0\sim 6)$ $ACC.7 \leftarrow [m].0$
Affected flag(s)	None
RRC [m]	Rotate Data Memory right through Carry
Description	The contents of the specified Data Memory and the carry flag are rotated right by 1 bit. Bit 0 replaces the Carry bit and the original carry flag is rotated into bit 7.
Operation	$[m].i \leftarrow [m].(i+1); (i = 0\sim 6)$ $[m].7 \leftarrow C$ $C \leftarrow [m].0$
Affected flag(s)	C
RRCA [m]	Rotate Data Memory right through Carry with result in ACC
Description	Data in the specified Data Memory and the carry flag are rotated right by 1 bit. Bit 0 replaces the Carry bit and the original carry flag is rotated into bit 7. The rotated result is stored in the Accumulator and the contents of the Data Memory remain unchanged.
Operation	$ACC.i \leftarrow [m].(i+1); (i = 0\sim 6)$ $ACC.7 \leftarrow C$ $C \leftarrow [m].0$
Affected flag(s)	C
SBC A,[m]	Subtract Data Memory from ACC with Carry
Description	The contents of the specified Data Memory and the complement of the carry flag are subtracted from the Accumulator. The result is stored in the Accumulator. Note that if the result of subtraction is negative, the C flag will be cleared to 0, otherwise if the result is positive or zero, the C flag will be set to 1.
Operation	$ACC \leftarrow ACC - [m] - C$
Affected flag(s)	OV, Z, AC, C
SBCM A,[m]	Subtract Data Memory from ACC with Carry and result in Data Memory
Description	The contents of the specified Data Memory and the complement of the carry flag are subtracted from the Accumulator. The result is stored in the Data Memory. Note that if the result of subtraction is negative, the C flag will be cleared to 0, otherwise if the result is positive or zero, the C flag will be set to 1.
Operation	$[m] \leftarrow ACC - [m] - C$
Affected flag(s)	OV, Z, AC, C
SDZ [m]	Skip if decrement Data Memory is 0
Description	The contents of the specified Data Memory are first decremented by 1. If the result is 0 the following instruction is skipped. As this requires the insertion of a dummy instruction while the next instruction is fetched, it is a two cycle instruction. If the result is not 0 the program proceeds with the following instruction.
Operation	$[m] \leftarrow [m] - 1$ Skip if $[m] = 0$
Affected flag(s)	None

SDZA [m]	Skip if decrement Data Memory is zero with result in ACC
Description	The contents of the specified Data Memory are first decremented by 1. If the result is 0, the following instruction is skipped. The result is stored in the Accumulator but the specified Data Memory contents remain unchanged. As this requires the insertion of a dummy instruction while the next instruction is fetched, it is a two cycle instruction. If the result is not 0, the program proceeds with the following instruction.
Operation	$ACC \leftarrow [m] - 1$ Skip if $ACC = 0$
Affected flag(s)	None
SET [m]	Set Data Memory
Description	Each bit of the specified Data Memory is set to 1.
Operation	$[m] \leftarrow FFH$
Affected flag(s)	None
SET [m].i	Set bit of Data Memory
Description	Bit i of the specified Data Memory is set to 1.
Operation	$[m].i \leftarrow 1$
Affected flag(s)	None
SIZ [m]	Skip if increment Data Memory is 0
Description	The contents of the specified Data Memory are first incremented by 1. If the result is 0, the following instruction is skipped. As this requires the insertion of a dummy instruction while the next instruction is fetched, it is a two cycle instruction. If the result is not 0 the program proceeds with the following instruction.
Operation	$[m] \leftarrow [m] + 1$ Skip if $[m] = 0$
Affected flag(s)	None
SIZA [m]	Skip if increment Data Memory is zero with result in ACC
Description	The contents of the specified Data Memory are first incremented by 1. If the result is 0, the following instruction is skipped. The result is stored in the Accumulator but the specified Data Memory contents remain unchanged. As this requires the insertion of a dummy instruction while the next instruction is fetched, it is a two cycle instruction. If the result is not 0 the program proceeds with the following instruction.
Operation	$ACC \leftarrow [m] + 1$ Skip if $ACC = 0$
Affected flag(s)	None
SNZ [m].i	Skip if bit i of Data Memory is not 0
Description	If bit i of the specified Data Memory is not 0, the following instruction is skipped. As this requires the insertion of a dummy instruction while the next instruction is fetched, it is a two cycle instruction. If the result is 0 the program proceeds with the following instruction.
Operation	Skip if $[m].i \neq 0$
Affected flag(s)	None
SUB A,[m]	Subtract Data Memory from ACC
Description	The specified Data Memory is subtracted from the contents of the Accumulator. The result is stored in the Accumulator. Note that if the result of subtraction is negative, the C flag will be cleared to 0, otherwise if the result is positive or zero, the C flag will be set to 1.
Operation	$ACC \leftarrow ACC - [m]$
Affected flag(s)	OV, Z, AC, C

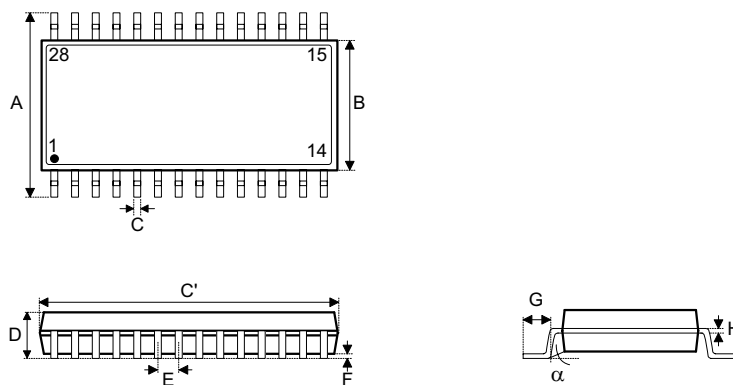
SUBM A,[m]	Subtract Data Memory from ACC with result in Data Memory
Description	The specified Data Memory is subtracted from the contents of the Accumulator. The result is stored in the Data Memory. Note that if the result of subtraction is negative, the C flag will be cleared to 0, otherwise if the result is positive or zero, the C flag will be set to 1.
Operation	$[m] \leftarrow ACC - [m]$
Affected flag(s)	OV, Z, AC, C
SUB A,x	Subtract immediate data from ACC
Description	The immediate data specified by the code is subtracted from the contents of the Accumulator. The result is stored in the Accumulator. Note that if the result of subtraction is negative, the C flag will be cleared to 0, otherwise if the result is positive or zero, the C flag will be set to 1.
Operation	$ACC \leftarrow ACC - x$
Affected flag(s)	OV, Z, AC, C
SWAP [m]	Swap nibbles of Data Memory
Description	The low-order and high-order nibbles of the specified Data Memory are interchanged.
Operation	$[m].3 \sim [m].0 \leftrightarrow [m].7 \sim [m].4$
Affected flag(s)	None
SWAPA [m]	Swap nibbles of Data Memory with result in ACC
Description	The low-order and high-order nibbles of the specified Data Memory are interchanged. The result is stored in the Accumulator. The contents of the Data Memory remain unchanged.
Operation	$ACC.3 \sim ACC.0 \leftarrow [m].7 \sim [m].4$ $ACC.7 \sim ACC.4 \leftarrow [m].3 \sim [m].0$
Affected flag(s)	None
SZ [m]	Skip if Data Memory is 0
Description	If the contents of the specified Data Memory is 0, the following instruction is skipped. As this requires the insertion of a dummy instruction while the next instruction is fetched, it is a two cycle instruction. If the result is not 0 the program proceeds with the following instruction.
Operation	Skip if $[m] = 0$
Affected flag(s)	None
SZA [m]	Skip if Data Memory is 0 with data movement to ACC
Description	The contents of the specified Data Memory are copied to the Accumulator. If the value is zero, the following instruction is skipped. As this requires the insertion of a dummy instruction while the next instruction is fetched, it is a two cycle instruction. If the result is not 0 the program proceeds with the following instruction.
Operation	$ACC \leftarrow [m]$ Skip if $[m] = 0$
Affected flag(s)	None
SZ [m].i	Skip if bit i of Data Memory is 0
Description	If bit i of the specified Data Memory is 0, the following instruction is skipped. As this requires the insertion of a dummy instruction while the next instruction is fetched, it is a two cycle instruction. If the result is not 0, the program proceeds with the following instruction.
Operation	Skip if $[m].i = 0$
Affected flag(s)	None

TABRDC [m]	Read table (current page) to TBLH and Data Memory
Description	The low byte of the program code (current page) addressed by the table pointer (TBLP) is moved to the specified Data Memory and the high byte moved to TBLH.
Operation	[m] ← program code (low byte) TBLH ← program code (high byte)
Affected flag(s)	None
TABRDL [m]	Read table (last page) to TBLH and Data Memory
Description	The low byte of the program code (last page) addressed by the table pointer (TBLP) is moved to the specified Data Memory and the high byte moved to TBLH.
Operation	[m] ← program code (low byte) TBLH ← program code (high byte)
Affected flag(s)	None
XOR A,[m]	Logical XOR Data Memory to ACC
Description	Data in the Accumulator and the specified Data Memory perform a bitwise logical XOR operation. The result is stored in the Accumulator.
Operation	ACC ← ACC "XOR" [m]
Affected flag(s)	Z
XORM A,[m]	Logical XOR ACC to Data Memory
Description	Data in the specified Data Memory and the Accumulator perform a bitwise logical XOR operation. The result is stored in the Data Memory.
Operation	[m] ← ACC "XOR" [m]
Affected flag(s)	Z
XOR A,x	Logical XOR immediate data to ACC
Description	Data in the Accumulator and the specified immediate data perform a bitwise logical XOR operation. The result is stored in the Accumulator.
Operation	ACC ← ACC "XOR" x
Affected flag(s)	Z

Package Information

Note that the package information provided here is for consultation purposes only. As this information may be updated at regular intervals users are reminded to consult the Holtek website (<http://www.holtek.com.tw/english/literature/package.pdf>) for the latest version of the package information.

28-pin SOP (300mil) Outline Dimensions

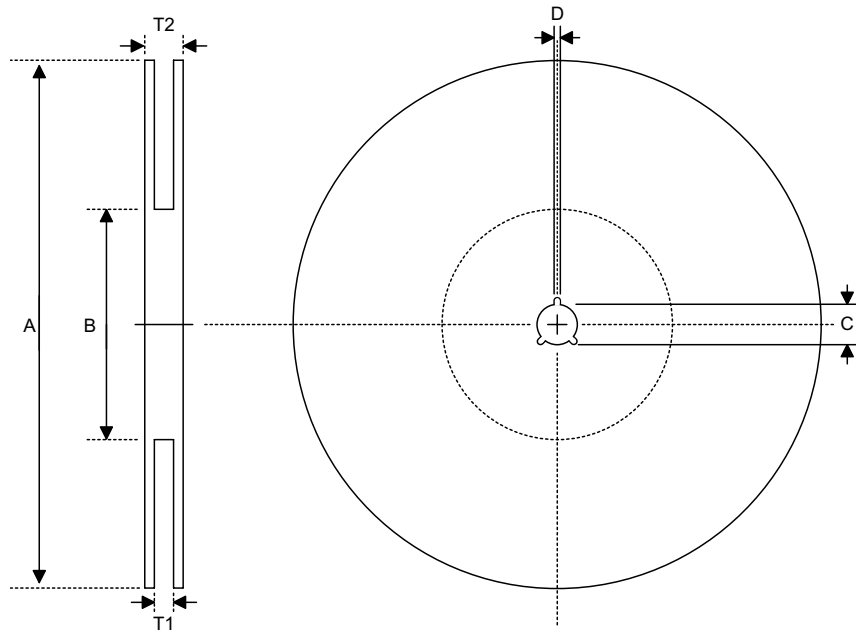


MS-013

Symbol	Dimensions in inch		
	Min.	Nom.	Max.
A	0.393	—	0.419
B	0.256	—	0.300
C	0.012	—	0.020
C'	0.697	—	0.713
D	—	—	0.104
E	—	0.050	—
F	0.004	—	0.012
G	0.016	—	0.050
H	0.008	—	0.013
α	0°	—	8°

Symbol	Dimensions in mm		
	Min.	Nom.	Max.
A	9.98	—	10.64
B	6.50	—	7.62
C	0.30	—	0.51
C'	17.70	—	18.11
D	—	—	2.64
E	—	1.27	—
F	0.10	—	0.30
G	0.41	—	1.27
H	0.20	—	0.33
α	0°	—	8°

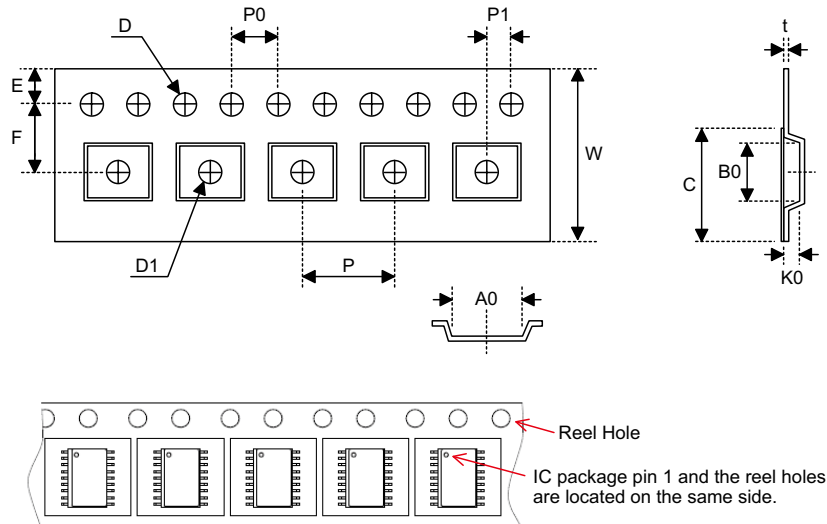
Reel Dimensions



SOP 28W (300mil)

Symbol	Description	Dimensions in mm
A	Reel Outer Diameter	330.0±1.0
B	Reel Inner Diameter	100.0±1.5
C	Spindle Hole Diameter	13.0 ^{+0.5/-0.2}
D	Key Slit Width	2.0±0.5
T1	Space Between Flang	24.8 ^{+0.3/-0.2}
T2	Reel Thickness	30.2±0.2

Carrier Tape Dimensions



SOP 28W (300mil)

Symbol	Description	Dimensions in mm
W	Carrier Tape Width	24.00±0.30
P	Cavity Pitch	12.00±0.10
E	Perforation Position	1.75±0.10
F	Cavity to Perforation(Width Direction)	11.50±0.10
D	Perforation Diameter	1.50 ^{+0.10/-0.00}
D1	Cavity Hole Diameter	1.50 ^{+0.25/-0.00}
P0	Perforation Pitch	4.0±0.1
P1	Cavity to Perforation(Length Direction)	2.0±0.1
A0	Cavity Length	10.85±0.10
B0	Cavity Width	18.34±0.10
K0	Cavity Depth	2.97±0.10
t	Carrier Tape Thickness	0.35±0.01
C	Cover Tape Width	21.3±0.1

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