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Volume I

Technical description

TREBALL DE FI DE GRAU



**“DESIGN AND
CONSTRUCTION OF AN
AUTOMATIC SYSTEM
FOR WATER
MAINTENANCE OF
DOMESTIC POOL”**

TFG presentat per obtenir el títol de GRAU en
ENGINYERIA ELECTRONICA INDUSTRIAL I
AUTOMÀTICA

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RESUM

Aquest treball de final de grau consisteix en el disseny i construcció d'un sistema automàtic de dosificació dels productes químics necessaris pel manteniment i correcció del pH de l'aigua d'una piscina domèstica.

El sistema està controlat per un microcontrolador PIC el qual amb la informació recollida pel sensors de pH i temperatura i previ càlcul del programari, acciona la corresponent vàlvula del producte necessari. Després acciona la bomba peristàltica, enviant el producte al sistema de filtració estàndard de la piscina.

El microcontrolador també tindria control de la bomba centrífuga del sistema de filtració de la piscina per garantir que el producte químic es distribueixi per la piscina.

RESUMEN

Este trabajo de final de grado consiste en el diseño y construcción de un sistema automático de dosificación de los productos químicos necesarios para el mantenimiento y corrección del pH del agua de una piscina doméstica.

El sistema está controlado por un microcontrolador PIC el cual con la información recogida por el sensores de pH y temperatura y previo cálculo del software, accionara la correspondiente válvula del producto necesario. Después accionaría la bomba peristáltica, enviando el producto al sistema de filtración estándar de la piscina.

El microcontrolador también tendría control de la bomba centrífuga del sistema de filtración de la piscina para garantizar que el producto químico se distribuya por la piscina.

ABSTRACT

This final degree work involves the design and construction of an automatic dosing of chemicals required for maintenance and correction of pH water of a domestic swimming pool.

The system is controlled by a microcontroller PIC which with the information collected from the pH and temperature sensors and pre-calculation of the software, trigger the corresponding valve of the required product. After would also trigger the peristaltic pump, sending the product to the standard filtration system of the pool.

The microcontroller also would control the centrifugal pump filtration system from the pool to ensure that the chemical is distributed in the pool.

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CHAPTER 1:

INTRODUCTION

1.1. Description

System for automatic dosing of chemicals needed for pH correction and maintenance of a domestic pool.

The system is controlled by a PIC microcontroller which actuates the valves of the tanks of chemicals according to the program, opening only the valve corresponding to the required product and then operate the pump, sending the product to the standard filtering system of the pool.

The microcontroller also will take control of the pump of the filtration system to ensure that the chemical is distributed evenly in the pool.

The system has a pH sensor, which includes a pH probe and a driver signal for amplification and filtering. Once a week, the sensor sends the current value of pH to the microcontroller, using mathematical algorithms calculate the amount of acid or base needed to adjust the pool to 7.4 pH.

To make the calculation, the microcontroller know the water temperature (using an analogue temperature sensor) and ask to the user during the first run about the total amount of water and the concentration of acid or base storage in the chemical deposits.

Also the system daily adds a fix amount of chlorine based on the water volume that the user specified on the system.

The software loaded in this microcontroller is responsible of:

- Weekly pH control and temperature.
- Weekly pH correction, if necessary.
- Daily scheduled to add the amount of fixed liquid chlorine (routine maintenance).

The system can be split into the following parts:

- Peristaltic pump, for dosing.
- Press valves.
- pH sensor.
- Temperature Sensor.
- PIC microcontroller.
- Relay, to trigger the external water pump.

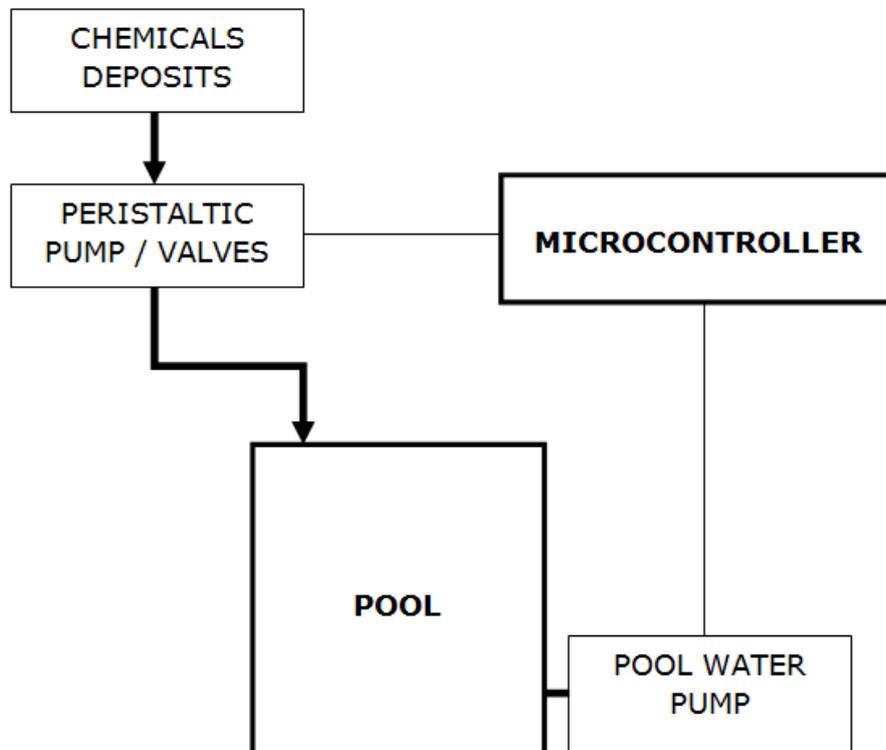


Figure 1 Block diagram of the system

The whole system is composed of a flexible tube. This peristaltic pump and the strangler valve are based on deforming the tube to block the flow of liquid or push it.

1.2. Motivation

All the people how have a garden with a swimming pool in his backyard know that you have to spend many time working on it to keep it nice and clean. Is an arduous task. My motivation is to make the most monotonous task automatic for the user. The idea is to take control of the related tasks for the maintenances of the water pool.

1.3. Specifications of the system

Below are the summary table with the general characteristics of the system:

Magnitudes	Max value	Min value	Resolution	Units
Temperature	40	5	0.1	°C
pH	14	1	0.1	pH
Time	7-12:59:59	1-00:00:00	1-01:01:01	*DoW- hh:mm:ss
Input voltage	230 AC	115 AC	-	V
Power consumption standby	3	2	0.1	W
Power consumption fully operative	4	2	0.1	W
Pool water volume	40000	500	500	L
Power consumption external pump	3680	1	-	W

*DoW = Day of the week

Table 1 General specifications of the system

1.4. Background and goals

Nowadays an owner of a swimming pool can find some similar systems to keep the water clean, but the unique one, which can do the maintenances of all the aspects of the water, is a salt chloride system.

The salt chloride system is based on salty water pool without chlorine. The system has diversions electrodes which using direct current performs a chemical reaction with the dissolved salt in the water. At the end the user doesn't have to add any chlorine or algaecide because this chemical reaction produce all the necessary products. Also the salt chloride system has and independent system to regulated the pH.

The disadvantage of this system is that is really expensive compared to the price of a small pool (less than 40.000 liters). The electrodes of this kind of system are made of titanium, gold or platinum. So at the end if you own a small swimming pool the unique way to maintain the water fully automatic is to spend the same amount of money that you spend on the construction of the pool, in the salt chloride system.

The goal is to make a cheap and easy system for these users with can't afford a salt chloride system. These are the followed step to achieve this goal:

1. Design of the electronic hardware.
2. Control Software.
3. Simulation of the system.
4. Construction of the prototype.
5. Set up of the system.

CHAPTER 2:

SENSORS

2.1. Sensor selection

The system needs some data from the measuring devices to begin with the different process. Is necessary to have some kind of interface to transform a physic magnitude to and electrical signal to be interpreted by the microcontroller.

These sensors generally use to be analogue voltage levels and provide proportional to the magnitude or intensity that measure, although there are also varying electrical properties such as conductivity or the ability and need to convert these stages of adaptation variations in intensity or voltage signals.

For every magnitude measuring station is necessary to have a sensor that specializes in measuring this magnitude. The sensors that are used in the system are explained in this chapter.

2.1.1. Temperature sensor

There are multitudes of sensors that measure temperature, but should always consider what is the purpose of the measure, and from there select

the most suitable. It is not the same, measure the temperature of an industrial process rather than the body temperature of man, because in the second case requires a remarkable accuracy compared to the first case.

The resistive sensors like PT-100 or thermocouples can be used to measure temperature, but there are other more reliable, for example, which are based on semiconductors. This semiconductor sensor also provides a digital output for the data.

The system operates with a LM-35 a lineal temperature sensor mounted in waterproof metal case.



Figure 2 Waterproof case
LM35

There are several reasons to choose this sensor:

- Low cost, in this system we are looking for the minimum cost of the equipment without losing so much precision.
- Linear sensor, the signal that you get from the sensor is a linear proportional, much easier to operate with.
- Low power consumption and interference, the low current consumption ($60\mu\text{A}$) allows you to be more precise to obtain the final measure.
- High precision between $0.5\text{ }^{\circ}\text{C}$ to $50\text{ }^{\circ}\text{C}$, between this range of temperatures the sensor is particularly more precise than normal ($\pm 0.5\text{ }^{\circ}\text{C}$). Fortunately the water pool during the summer season used to be inside this temperature range.

Therefore this sensor gives the temperature with less accuracy than other temperature sensors but in this system it is not necessary to have a highly precise sensor. Because we only use the temperature value to slightly correct the pH value.

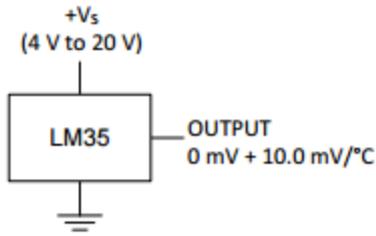


Figure 3 Pin out, basic centigrade temperature sensor
- Source: Datasheet LM35

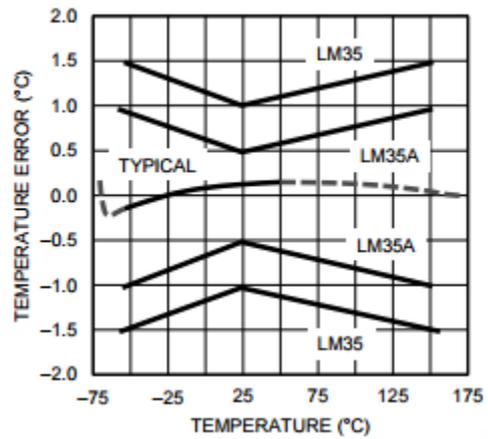


Figure 4 Accuracy vs Temperature -
Source: Datasheet LM35

2.1.2. PH meter

This device measure potentiometrically the pH, which is either the concentration or the activity of hydrogen ions, of an aqueous solution. It has a glass electrode and a reference electrode build in.

When the user submerge the probe in to a liquid solution the, electrons flow from the electrode to the reference electrode or vice versa. This electric current is converted to positive voltage, filtered and amplified by the pH sensor driver and send it to the microcontroller.

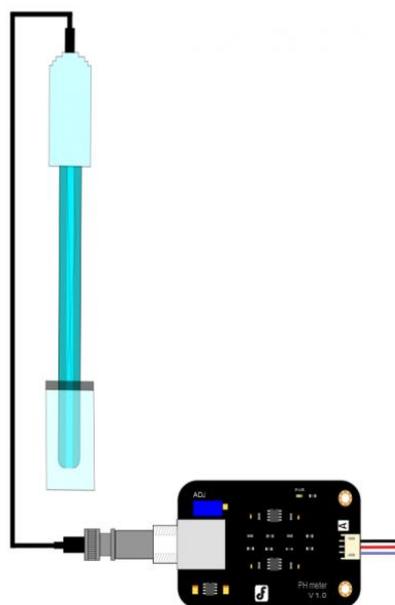


Figure 5 PH meter + driver
connection - Source: DFrobot.com

This driver is specifically designed from the manufacture of the pH prove, to ensure that the microcontroller receive a stable and accurate signal. This driver also has an adjustment potentiometer to slightly correct the pH signal. The user is able to calibrate the pH meter by submerging the prove into to a well calibrated solution and adjusting this potentiometer.

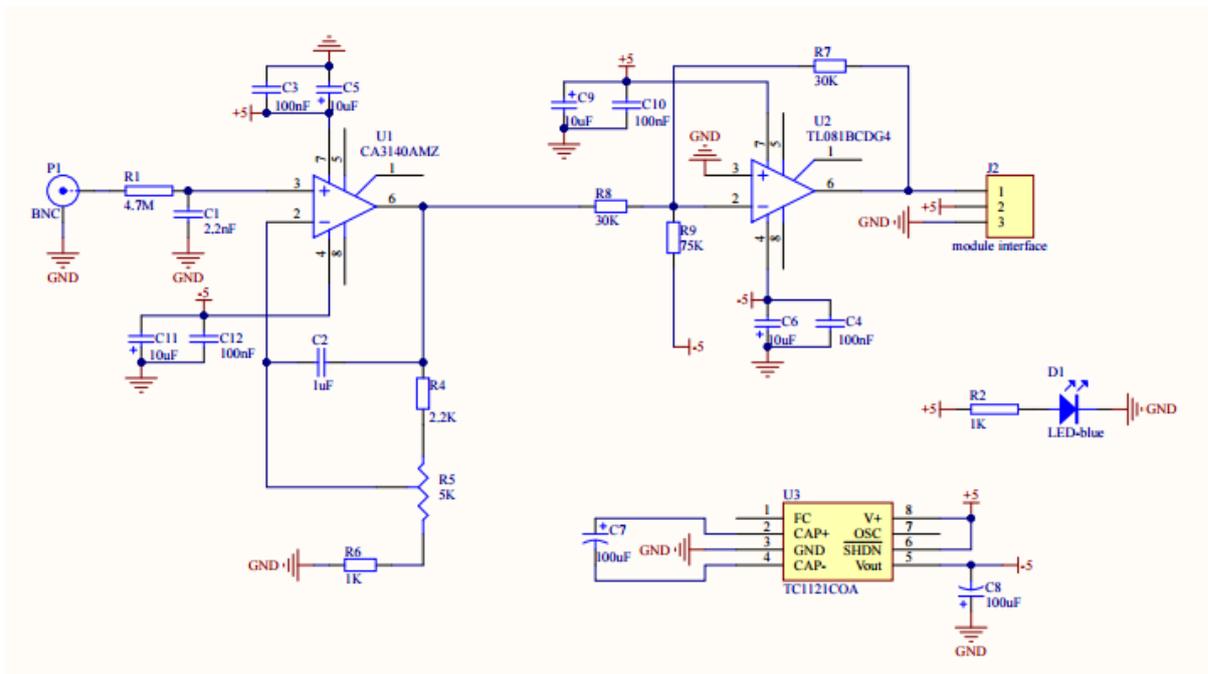


Figure 6 pH driver schematic - Source: DFrobot.com

The Figure 9 is the diagram for the pH driver. The probe signal enters IC1 via an RC circuit designed to allow only relatively slow signal variations (and avoid getting parasite HF signals). IC1 is a CMOS op-amp and thus has very high impedance. The gain of IC1 is adjusted with the potentiometer P1. C2 is there for the amplifier stability.

Once the signal has been amplified it enters an offset circuit built around IC2. IC2 is a more classic TL081 op-amp commonly found in audio devices, among others. The offset is defined by two potentiometers R9, this allows the range swept by P2 to be symmetric. The circuit is designed to provide an average offset of 2V. This step is necessary to eliminate de negative voltage of the signal because the analogue input of the microcontroller is not capable to measure it.

The voltages for the signal evolve in the circuit as follows:

- Before IC1, input voltage: $-0.414/+0.414V$ (this might depend on the electrode used and its age)
- After IC1, the low pass filter: $-2/+2V$
- After IC2, the inverter OPAMP: $0/+4V$
- Output voltage, on the microcontroller: $0.00 - 14.00 pH$

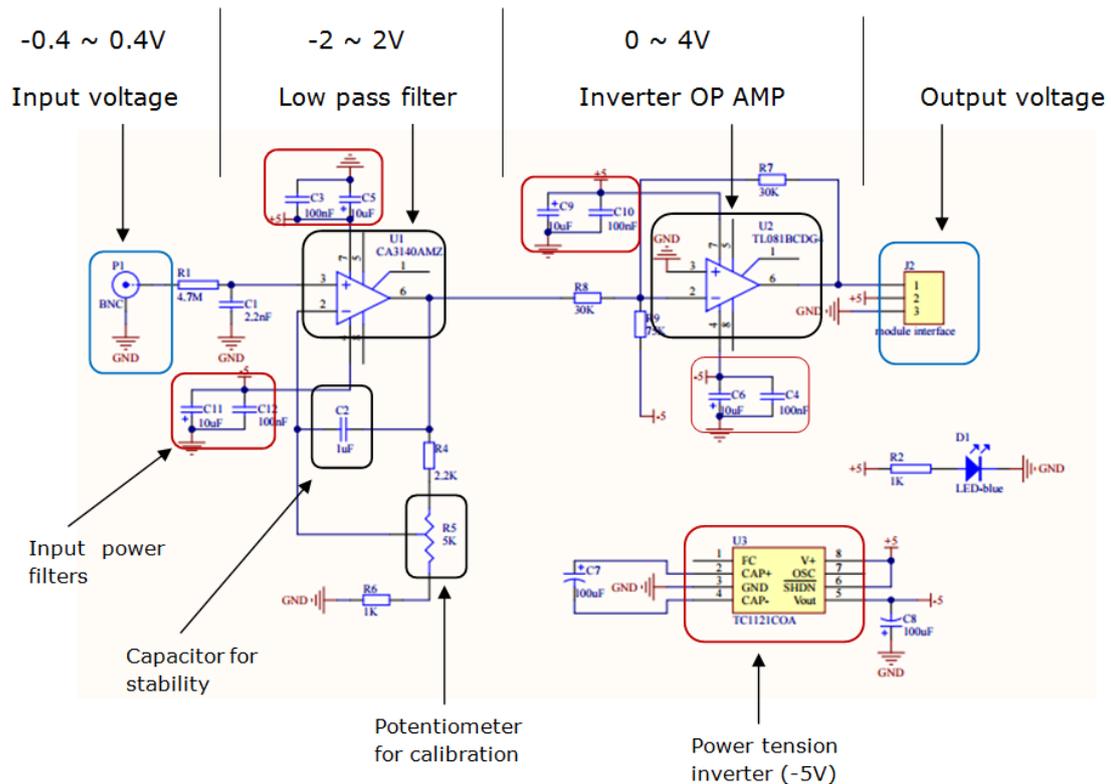


Figure 7 pH driver schematic described

In the stage of the low pass filter the gain change according to a potentiometer on the board.

The value of the R_5 depends on the actual value that the user set on the potentiometer. The full resistance of the resistor R_5 is equal to $4,7K\Omega$

$$R_{5A} = R_{5FULL} - R_{5ACTUAL}$$

$$R_{5B} = R_{5ACTUAL}$$

Equations 1 Actual value of the calibration potentiometer

In case of a good calibration the actual value of R_5 is around $4,1K\Omega$, so the gain of the low pass filter will be like so:

$$Gain = \left(1 + \frac{R_{5A} + R_4}{R_6 + R_{5B}}\right) = \left(1 + \frac{0,6K + 2,2K}{1K + 4,1K}\right) = 1.549$$

Equations 2 Gain of the low pass filter stage

For the next stage, the inverter, the gain is fixe to the next valve:

$$Gain = -\frac{R_7}{R_8} = -\frac{30K}{30K} = -1$$

Equations 3 Gain of the inverter stage

As the equation 3 shows, the gain don't amplify the signal it just invert the output in order to convert the negative voltage to positive voltage

2.2. Sensor troubles

The chosen pH sensor for this system is not the best choice, because it cannot stay for long periods of time under water, it may rest in the storage solution. But it was more costly and complicated to use the suitable sensor form this purpose.

The software of the system adds a fixed amount of chloride based on the amount of water that the user specified on the menu. Exist some chloride sensor on the market but they are really expensive and extremely delicate, can't be installed outside. For that reason no chloride sensor have been used in this system.

CHAPTER 3: ELECTRONIC DESIGN

The electronics design go from with components are necessary to the finally position to be mounted. Also is really important how to configuration those devices using the software inside the microcontrollers. In this chapter are explained all the step to design the main board of the system

3.1. Block diagram

In the block diagram of the system, blocks connected by arrows that show the relationships between them represent the principal parts or functions.

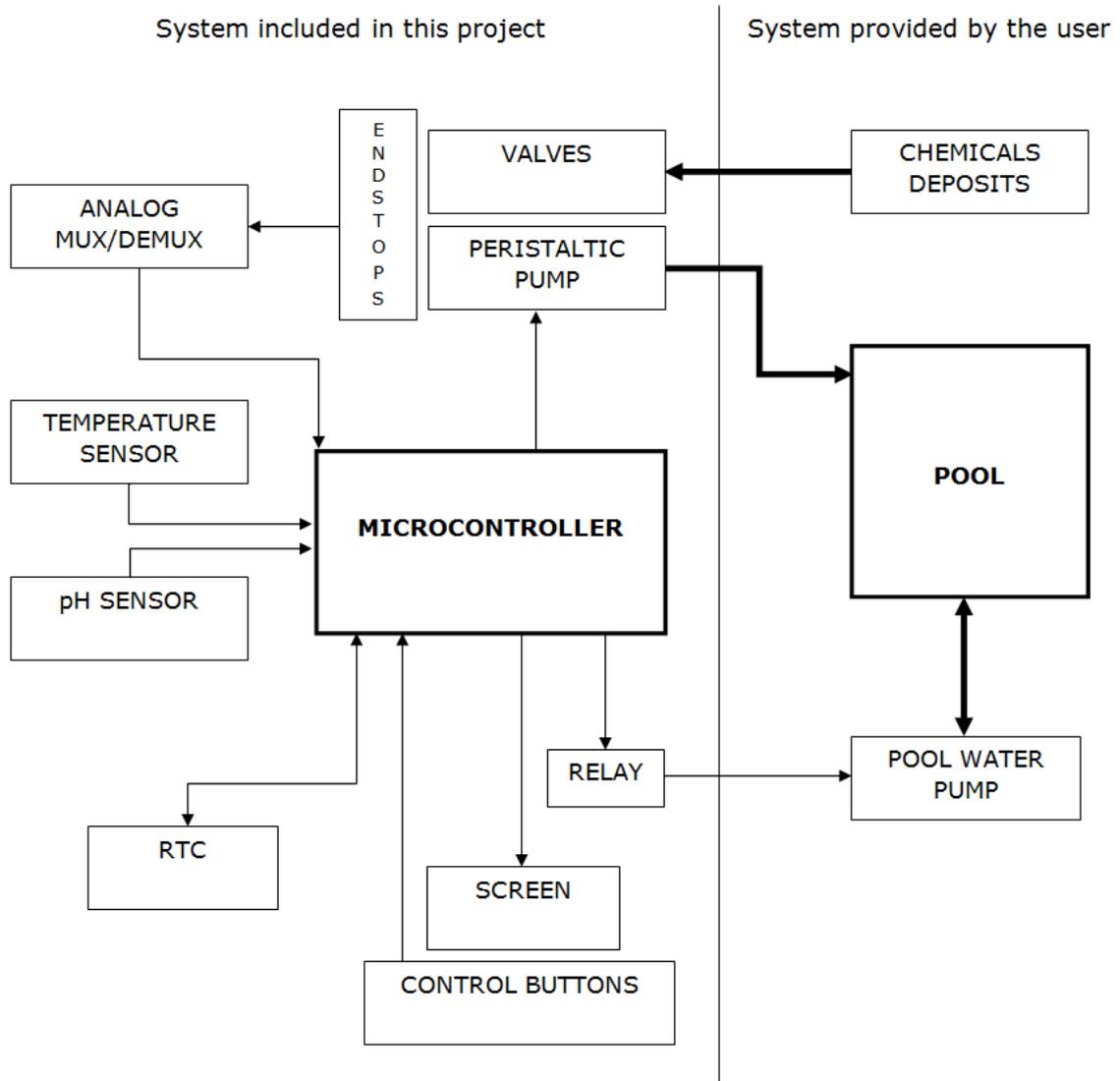


Figure 8 Complete block diagram of the system

There are two main parts, the one on the left side with describe the hardware of the actual system of this project. On the right side is the hardware expect from the user who install this system.

The bloc diagram is build it with arrow, the wider one represent liquid pipes, and the thin ones, electrical connections. If the arrow have two triangles at both ends represent a bidirectional connection.

3.2. Hardware of the PIC 18F4550

The PIC18F4550 is the main body of the system. It is a of the popular PIC microcontroller Microchip Technology, characterized for easy programming and performance combined with a high ratio quality - price really attractive.

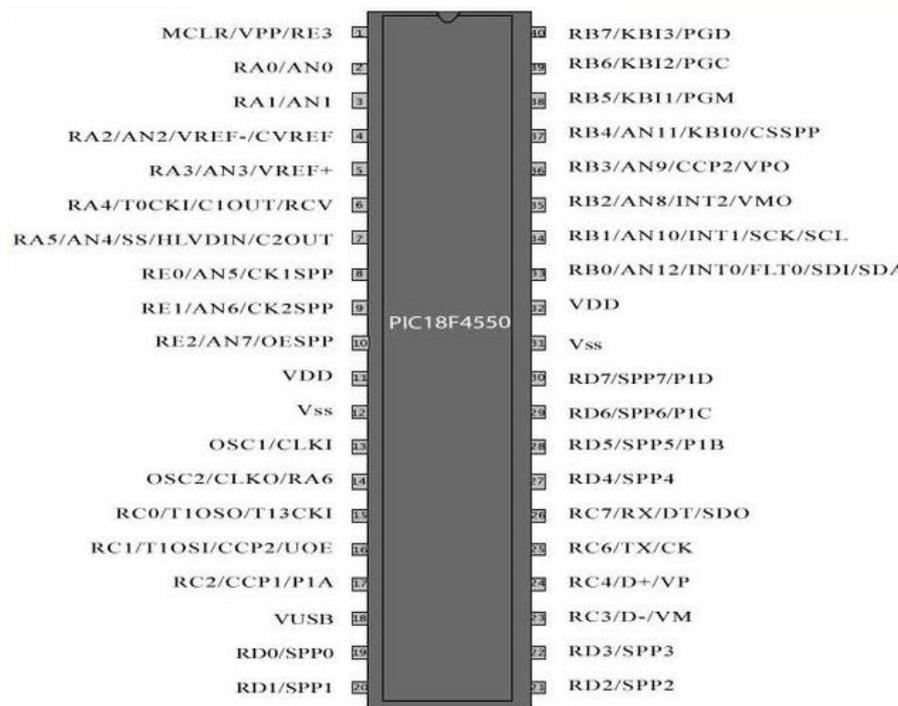


Figure 9 Pin diagram PIC 18F4550 - Source: engineersgarage.com

PIC18F4550 is an 8-bit microcontroller of PIC18 family. PIC18F family is based on 16-bit instruction set architecture. PIC18F4550 consists of 32 KB flash memory, 2 KB SRAM and 256 Bytes EEPROM.

This is a 40-pin PIC microcontroller consisting of 5 I/O ports (PORTA, PORTB, PORTC, PORTD and PORTE). PORTB and PORTD have 8 pins to receive/transmit 8-bit I/O data. The remaining ports have different numbers of pins for I/O data communications.

PIC18F4550 can work on different internal and external clock sources. It can work on a varied range of frequency from 31 KHz to 48 MHz. PIC18F4550 has four in-built timers. For this system and for the program that we will run inside the microcontroller the frequencies will be 4MHz. There are various inbuilt peripherals like ADC, comparators etc. in this controller.

PIC18F4550 is an advanced microcontroller, which is equipped with enhanced communication protocols like EUSART, SPI, I2C, USB etc.

Features	PIC18F4550
Operating Frequency	DC – 48 MHz
Program Memory (Bytes)	32768
Program Memory (Instructions)	16384
Data Memory (Bytes)	2048
Data EEPROM Memory (Bytes)	256
Interrupt Sources	20
I/O Ports	Ports A, B, C, D, E
Timers	4
Capture/Compare/PWM Modules	1
Enhanced Capture/Compare/PWM Modules	1
Serial Communications	MSSP, Enhanced USART
Universal Serial Bus (USB) Module	1
Streaming Parallel Port (SPP)	Yes
Analog-to-Digital Module	13 Input Channels, 10-bit
Comparators	2
Resets (and Delays)	POR, BOR, RESET Instruction, Stack Full, Stack Underflow (PWRT, OST), MCLR (optional), WDT
Programmable Low-Voltage Detect	Yes
Programmable Brown-out Reset	Yes
Instruction Set	75 Instructions; 83 with Extended Instruction Set enabled
Packages	40-pin PDIP 44-pin QFN 44-pin TQFP

Table 2 Specs and features of PIC18f4550

3.2.1. Analog-to-Digital ports (ADC)

One of the most important benefits of this microcontroller is that converts digital values into analogue measurements with a 10 bits resolution.

It is a successive approximation converter with four multiplexed analogue channels that are part of the Port A. The input voltage V_{ref} reference limits the maximum voltage conversion. The provision of these channels is not fixed and can be adjusted to suit the user by modifying a register as discussed below.

At the entrance of the converter there is a system that sampled the sample-hold and stores the signal voltage level in a condenser, which is later, used to do the conversion. All these components are internally connected, no external components required to operate.

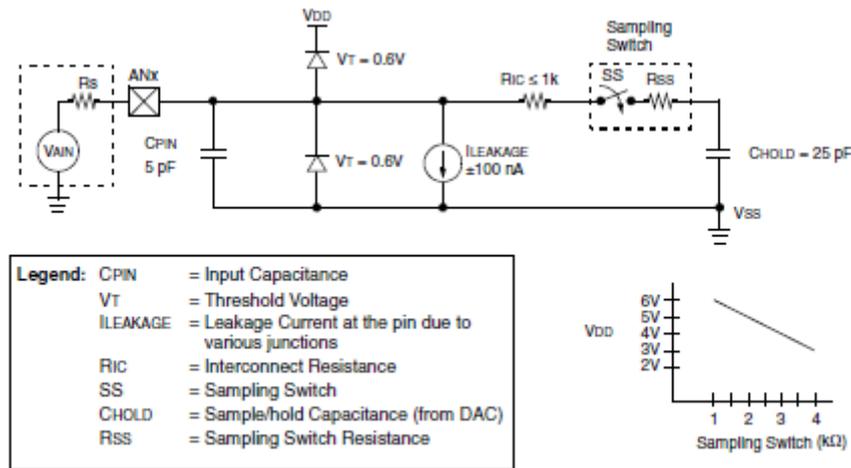


Figure 10 Model analog input converter - Source: Datasheet PIC18f4550

The load capacitor requires an acquisition time (T_{acq}) usually $19,72\mu s$ be about, plus the conversion time-dependent frequency converter that works. This time (TAD) is defined, as time required for converting a bit, while the conversion complete (10 bits) the manufacturer says it can count to $12TAD$. This time is configurable by changing the clock speed or working converter means a record, but it depends on the maximum operating frequency of the microcontroller.

The converter control registers are ADCON0 and ADCON1, while conversion result is stored in registers ADRESH and ADRESL.

Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
-	-	CHS3	CHS2	CHS1	CHS0	GO/DONE	ADON

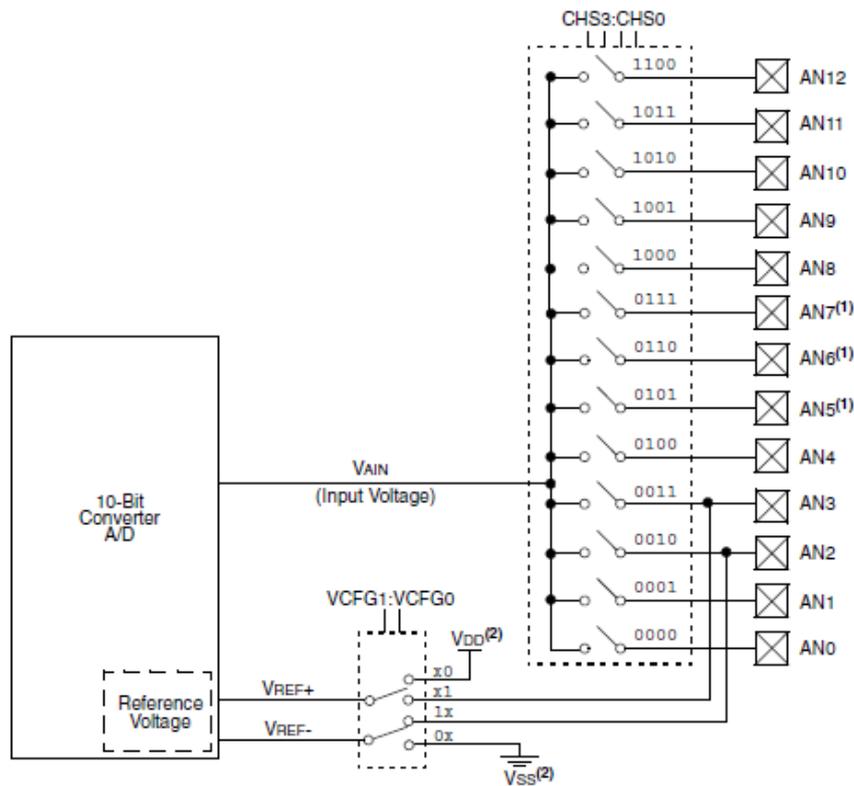
Table 3 ADCON0 register bits that control the ADC

Description of the register bits:

- CHS3 to CHS0: Bits selection of analog inputs: with "000" is selects AN0 input until "100" is selected AN4 entry.
- GO / DONE: Ability converter, placing this bit to '1' initialize the system conversion, and returns a "0" once the conversion is complete.
- ADON: Bit Enabling the converter:

'0': The converter remains offline and does not consume anything.

1 ': The converter is enabled.



Note 1: Channels AN5 through AN7 are not available on 28-pin devices.
Note 2: I/O pins have diode protection to VDD and VSS.

Figure 11 A/D block diagram - Source: Datasheet PIC18f4550

Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
-	-	VCFG 0	VCFG 0	PCFG 3	PCFG20	PCFG1	PCFG0

Table 4 ADCON1 register bits that control the ADC

Description of the register bits:

- VCFG0: Voltage Reference Configuration bit (VREF- source)
 - 1 = VREF- (AN2)
 - 0 = VSS
- VCFG0: Voltage Reference Configuration bit (VREF+ source)
 - 1 = VREF+ (AN3)
 - 0 = VDD
- PCFG3:PCFG0: A/D Port Configuration Control bits:
 - 1101 = Digital I/O from AN12 to AN2
 - Analog input to AN1 and AN0

Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
ADFM	-	ACQT2	ACQT1	ACQT0	ADCS2	ADCS1	ADCS0

Table 5 ADCON2 register bits that control the ADC

Description of the register bits:

- ADFM: A/D Result Format Select bit
 - 1 = Right justified
 - 0 = Left justified
- ACQT2:ACQT0: A/D Acquisition Time Select bits
 - 111 = 20 TAD
 - 110 = 16 TAD
 - 101 = 12 TAD
 - 100 = 8 TAD
 - 011 = 6 TAD
 - 010 = 4 TAD

001 = 2 TAD

000 = 0 TAD

- ADCS2:ADCS0: A/D Conversion Clock Select bits
 - 111 = FRC (clock derived from A/D RC oscillator)
 - 110 = FOSC/64
 - 101 = FOSC/16
 - 100 = FOSC/4
 - 011 = FRC (clock derived from A/D RC oscillator)
 - 010 = FOSC/32
 - 001 = FOSC/8
 - 000 = FOSC/2

In order to do the conversion properly, these steps must be follow as described below:

1. Configure entries in Port bits and justification through ADCON1.
2. Select one of the entrances to the Port through ADCON0.
3. Select the clock frequency of the converter through ADCS1 and ADCS0 registry ADCON0.
4. Enable the converter putting noticed ADCON0 bit to '1'.
5. Initiate the conversion putting the bit GO / DONE ADCON0 of a 'one'.
6. Wait time conversion until GO / DONE back to '0'.
7. Make reading records that contain the ADRESL and ADRESH conversion.

In the program the converter station is configured so that the working frequency is FOSC / 2 bits of justification is on the right, leaving the first eight bits of less weight in the register ADRESL and the two last more weight ADRESH and entries Port A (AN0 to AN1) are configured as analog. In the system we don't need any voltage reference to extend the accuracy of the ADC.

3.2.2. Input and Output port (I/O)

Input and Output ports are used for the microcontroller to communicate with the outside. These ports include the digital inputs and outputs, but in

the case of the PIC is also has multiplexed inputs and outputs with other special features like entries analog data entries interruptions entries, programming divers, etc. That is why each port topology changes substantially having these extra features are all up and each pin port has its special configuration.

The PIC18F4550 has five ports A, B, C, D and E. The ports A to D are 8 bits while the E port is just 4 bits. All ports work equally and are associated with a control register that sets of if they were reading or write. The first register and placing TRISX bits called a '1' or '0' pin port associated this bit becomes read or write, so that within a port can having inputs and outputs simultaneously. The second is called PORTX and is to write or read the contents of the port via this record.

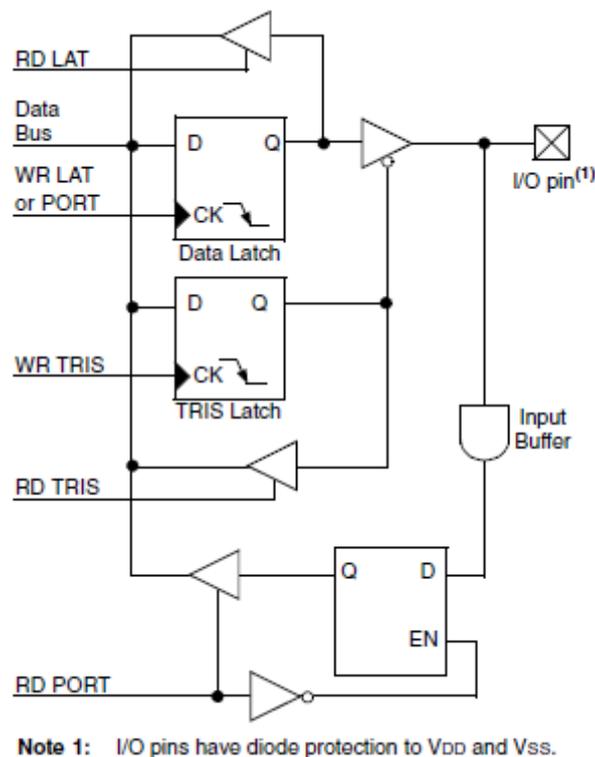


Figure 12 Generic I/O port operation -
Source: Datasheet PIC 18f4550

However each port has its particularity and is known for its architecture master its operation and its special features.

Port A is an 8-bit port is controlled from the registers TRISA and PORTA. Putting a "0" bits of the TRISA pin becomes associated with writing, while if set to "1", the pin is read.

The architecture of the pins RA2 to RA5 is the same. It has an output stage push-pull MOSFET's formed by two P-type and N, which makes the stage can give zeros and ones and either put in high mode impedance should be in reading mode. These pins are also multiplexed analog inputs of the ADC converter and must be taken into mind as to operate as digital inputs must configure the registry ADCON1 properly.

The pin RA6 / OSC2 is different from the other pins, this pin is primarily used to connect and input clock signal as and oscillator for the microcontroller. In order to use this port the user must activate ECIO, ECPIO and INTIO mode and use the internal oscillator.

Port B is an 8-bit port that works like other ports in TRISB through records and PORTB. This port, part has multiplexed pins divers communication I2C and SMBus, which makes the architecture is more complex than other ports. On the other hand, each pin has a push-pull output stage formed by MOSFET's, can therefore to '0', '1' or put pins in high impedance in the case of reading.

Port C is an 8-bit port that works like other ports in TRISC through records and PORTC. This port has multiplexed pins divers for USB serial communication. On the other hand, each pin has a push-pull output stage formed by MOSFET's, can therefore to '0', '1' or put pins in high impedance in the case of reading.

The Port D is 8 bits BO and its control registers are TRISD and PORTD that work like Port A. The architecture, however, is different and the output stages each pin under normal conditions can only "0" or high impedance.

Optionally, you can give the pin 1 'putting' 0 'bit of RBPU OPTION-REG registration (which was the control register of Timer 0). This P-type MOSFET is achieved by incorporating each pin and connecting the supply voltage pin (weak pull-up) to the '1'.

The RD0 pin has multiplexed input and interrupt pins RD3, RD6 and RD7 are multiplexed inputs programming the microcontroller. On the other hand, Architecture pins RD4 to RD7 varies with respect to the other pins because these have been the interruption to change the port.

Finally Port E is an 4-bit port that works like other ports in TRISE through records and PORTE. This port, have the external master clear input with is use to restart de microcontroller manually. It also carry the SSP clock and enable in it ports.

3.2.3. i2c communication

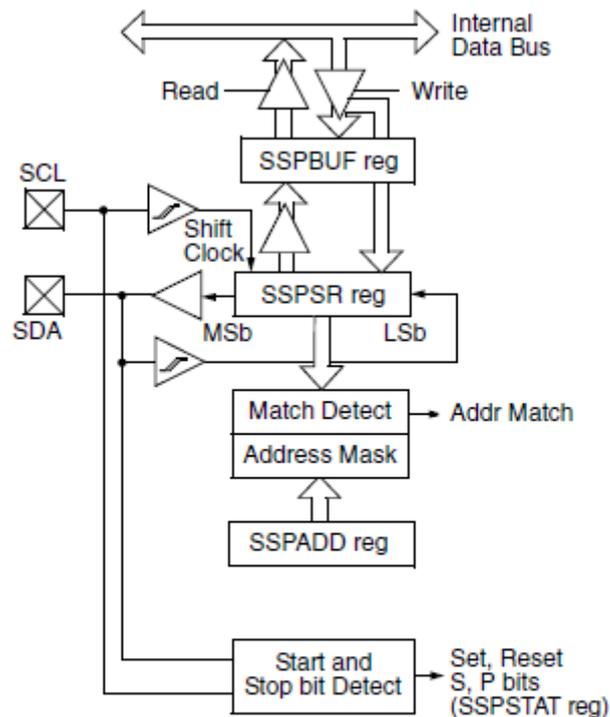
Most of PIC controllers especially 16F and 18F series have on-chip I2C Modules. I going to describe how to configure the registers of I2C Module and all derivatives of PIC have same module i.e. similar registers to configure.

In this system we going to use this communication module to read and set the current time in a RTC module.

Two pins are used for data transfer:

- Serial clock (SCL) – RB1/AN10/INT1/SCK/SCL
- Serial data (SDA) – RB0/AN12/INT0/FLT0/SDI/SDA

We already configure these pins as inputs by setting the associated TRIS bits on Ports B.



Note: Only port I/O names are used in this diagram for the sake of brevity. Refer to the text for a full list of multiplexed functions.

Figure 13 MSSSP block diagram for i2c mode - Source: Datasheet PIC 18f4550

For I2C master mode, there are 6 registers to be configured:

- SSPSTAT: MSSP Status Register
- SSPCON1: MSSP Control Register 1
- SSPCON2: MSSP Control Register 2
- Serial Receive/Transmit Buffer Register (SSPBUF)
- MSSP Shift Register (SSPSR) – Not directly accessible
- MSSP Address Register (SSPADD)

SSPCON1, SSPCON2 and SSPSTAT are the control and status registers in I2C mode operation. The SSPCON1 and SSPCON2 registers are readable and writable. The lower six bits of the SSPSTAT are read-only.

The upper two bits of the SSPSTAT are read/write. SSPSR is the shift register used for shifting data in or out. SSPBUF is the buffer register to which data bytes are written to or read from.

SSPADD register holds the slave device address when the MSSP is configured in I2C Slave mode. When the MSSP is configured in Master mode, the lower seven bits of SSPADD act as the Baud Rate Generator reload value.

In receive operations, SSPSR and SSPBUF together create a double-buffered receiver. When SSPSR receives a complete byte, it is transferred to SSPBUF and the SSPIF interrupt is set.

During transmission, the SSPBUF is not double buffered. A write to SSPBUF will write to both SSPBUF and SSPSR.

Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
SMP	CKE	D/A	P	S	R/W	UA	BF

Table 6 *SSPSTAT, i2c register*

Description of the register bits:

- SMP: Slew Rate Control bit
 - In Master or Slave mode:
 - 1 = Slew rate control disabled for Standard Speed mode (100 kHz and 1 MHz)
 - 0 = Slew rate control enabled for High-Speed mode (400 kHz)
- CKE: SMBus Select bit

In Master or Slave mode:

1 = Enable SMBus specific inputs

0 = Disable SMBus specific inputs

- D/A: Data/Address bit

In Master mode: Reserved.

- P: Stop bit(1)

1 = Indicates that a Stop bit has been detected last

0 = Stop bit was not detected last

- S: Start bit(1)

1 = Indicates that a Start bit has been detected last

0 = Start bit was not detected last

- R/W: Read/Write Information bit(2,3)

In Master mode:

1 = Transmit is in progress

0 = Transmit is not in progress

- UA: Update Address bit (10-Bit Slave mode only)

1 = Indicates that the user needs to update the address in the SSPADD register

0 = Address does not need to be updated

- BF: Buffer Full Status bit

In Transmit mode:

1 = SSPBUF is full

0 = SSPBUF is empty

In Receive mode:

1 = SSPBUF is full (does not include the ACK and Stop bits)

0 = SSPBUF is empty (does not include the ACK and Stop bits)

Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
WCOL	SSPOV	SSPEN	CKP	SSPM3	SSPM2	SSPM1	SSPM0

Table 7 SSPCON1, i2c register

Description of the register bits:

- WCOL: Write Collision Detect bit

In Master Transmit mode:

1 = A write to the SSPBUF register was attempted while the I2C conditions were not valid for a transmission to be started (must be cleared in software)

0 = No collision

In Receive mode (Master or Slave modes):

This is a "don't care" bit.

- SSPOV: Receive Overflow Indicator bit

In Receive mode:

1 = A byte is received while the SSPBUF register is still holding the previous byte (must be cleared in software)

0 = No overflow

In Transmit mode:

This is a "don't care" bit in Transmit mode.

- SSPEN: Master Synchronous Serial Port Enable bit

1 = Enables the serial port and configures the SDA and SCL pins as the serial port pins

0 = Disables serial port and configures these pins as I/O port pins

- CKP: SCK Release Control bit

In Master mode:

Unused in this mode.

- SSPM3: SSPM0: Master Synchronous Serial Port Mode Select bits

1000 = I2C Master mode, $\text{clock} = \text{FOSC}/(4 * (\text{SSPADD} + 1))$

Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
GCEN	ACKSTAT	ACKDT	ACKEN	RCEN	PEN	RSEN	SEN

Table 8 SSPCON2, i2c register

Description of the register bits:

- GCEN: General Call Enable bit (Slave mode only)
Unused in Master mode.
- ACKSTAT: Acknowledge Status bit (Master Transmit mode only)
1 = Acknowledge was not received from slave
0 = Acknowledge was received from slave
- ACKDT: Acknowledge Data bit (Master Receive mode only)(1)
1 = Not Acknowledge
0 = Acknowledge
- ACKEN: Acknowledge Sequence Enable bit(2)
1 = Initiate Acknowledge sequence on SDA and SCL pins and transmit ACKDT data bit. Automatically cleared by hardware.
0 = Acknowledge sequence Idle
- RCEN: Receive Enable bit (Master Receive mode only)(2)
1 = Enables Receive mode for I2C
0 = Receive Idle
- PEN: Stop Condition Enable bit(2)
1 = Initiate Stop condition on SDA and SCL pins. Automatically cleared by hardware.
0 = Stop condition Idle
- RSEN: Repeated Start Condition Enable bit(2)
1 = Initiate Repeated Start condition on SDA and SCL pins. Automatically cleared by hardware.
0 = Repeated Start condition Idle

- SEN: Start Condition Enable/Stretch Enable bit(2)
 - 1 = Initiate Start condition on SDA and SCL pins. Automatically cleared by hardware.
 - 0 = Start condition Idle

3.2.4. Table summary of the used inputs and outputs

The following tables present a summary of the inputs and outputs used the PIC18F4550 and the layout, pin number and comments if are necessary:

Port	Pin	Purpose	Comments
V _{DD}	11,32	Power supply +5V	
V _{SS}	12,31	Power supply GND	
V _{USB}	18		Not used
OSC1/CLK1	13	Port for an external oscillator	4MHz Cristal oscillator

Table 9 General pins PIC 18f4550

Port	Pin	Purpose	Comments
RA0/AN0	2	Voltage pHmeter	Analog input
RA1/AN1	3	Voltage temp sensor	Analog input
RA2/AN2/Vref-	4	IN1motor	Digital output
RA3/AN3/Vref+	5	IN2motor	Digital output
RA4/T0CKI	6	Multiplexor Input1	Digital input
RA5/AN4	7	Multiplexor Input2	Digital input
RA6/OSC2/CLK0	14	Port for an external oscillator	4MHz Cristal oscillator

Table 10 PortA pins PIC 18f4550

Port	Pin	Purpose	Comments
RB0/AN12/SDA	33	i2c data communication	SDA
RB1/AN10/SCL	34	i2c clock communication	SCL
RB2/AN8/INT2	35	Enable 1 motor	Digital output
RB3/AN9/CCP2	36	Enable 2 motor	Digital output
RB4/AN11/CSSPP	37	Enable 3 motor	Digital output
RB5/KBI1/PGM	38	Enable 4 motor	Digital output
RB6/KBI2/PGC	39	Enable 5 motor	Digital output
RB7/KBI3/PGD	40	Enable 6 motor	Digital output

Table 11 PortB pins PIC 18f4550

Port	Pin	Purpose	Comments
RC0/T1OSO/T1CKI	15	Switch ok	Digital input
RC1/T1OSI/CCP2	16	Switch up	Digital input
RC2/CCP1	17	Switch down	Digital input
RC4/D-/VM	23		Not used
RC5/D+/VP	24		Not used
RC6/TX/CK	25		Not used
RC7/RX/SDO	26		Not used

Table 12 Port C pins PIC 18f4550

Port	Pin	Purpose	Comments
RD0/SPP0	19	Enable LCD	Digital output
RD1/SPP1	20	Reset LCD	Digital output
RD2/SPP2	21	Write LCD	Digital output
RD3/SPP3	22	Enable external water pump	Digital output
RD4/SPP4	27	D4 LCD	LCD bit
RD5/SPP5/P1B	28	D5 LCD	LCD bit
RD6/SPP6/P1C	29	D6 LCD	LCD bit
RD7/SPP7/P1D	30	D7 LCD	LCD bit

Table 13 Port D pins PIC 18f4550

Port	Pin	Purpose	Comments
RE0/AN5/CK1SPP	8	Multiplexor bit A	Digital output
RE1/AN6/CK2PP	9	Multiplexor bit B	Digital output
RE2/AN7/OESPP	10	Multiplexor bit C	Digital output
RE3/MCLR/CP	1	Master clear button	Digital input

Table 14 Port E pins PIC 18f4550

3.3. RTC

The DS3231 is a low-cost, extremely accurate i2c real-time clock (RTC) with an integrated temperature compensated crystal oscillator (TCXO) and crystal. The device incorporates a battery input, and maintains accurate timekeeping when main power to the device is interrupted we install a 3v button battery. The integrated the crystal resonator enhances the long-term accuracy of the device.

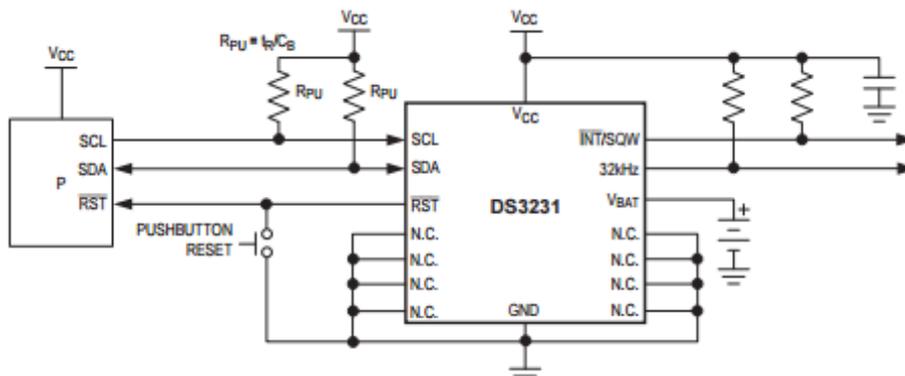


Figure 14 Operational circuit for RTC DS 3221 - Source: Datasheet DS3231

The RTC maintains seconds, minutes, hours, day, date, month, and year information. The date at the end of the month is automatically adjusted for months with fewer than 31 days, including corrections for leap year. The clock operates in either the 24-hour or 12-hour format with an AM/PM indicator.

Address and data are transferred serially through an I2C bidirectional bus. A precision temperature-compensated voltage reference and comparator circuit monitors the status of VCC to detect power failures, to provide a reset output, and to automatically switch to the backup supply when necessary. Additionally, the RST pin is monitored as a push button input for generating a μ P reset.

Features	DS3231
Real-Time Clock Counts	Seconds, Minutes, Hours, Date of the Month, Month, Day of the Week, and Year, with Leap-Year Compensation Valid Up to 2100
Accuracy	$\pm 2\text{ppm}$ from 0°C to $+40^\circ\text{C}$ $\pm 3.5\text{ppm}$ from -40°C to $+85^\circ\text{C}$
Digital temp sensor output accuracy	$\pm 3^\circ\text{C}$
Register for Aging Trim	Yes
Output/Pushbutton Reset	Yes
Debounce Input	
Time-of-Day Alarms	2
Programmable Square-Wave Output Signal	Yes, 32KHz
Extends Battery-Backup	Yes, 3.3V
Operating Temperature Ranges:	Commercial (0°C to $+70^\circ\text{C}$) and Industrial (-40°C to $+85^\circ\text{C}$)

Table 15 Specs and features of DS3231

In order to operate this chip it need some external components, back up battery (green), pull-up resistors (blue) and i2c connections (purple):

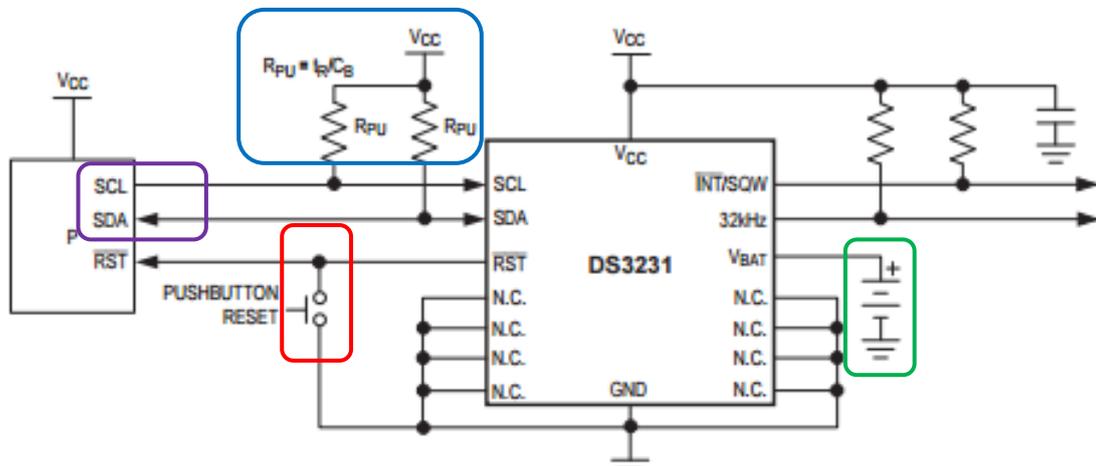


Figure 15 DS3231 schematic described

The I2C bus transmits data and clock with SDA and SCL. First thing to realize: SDA and SCL are *open-drain* (also known as *open-collector* in the TTL world), that is I2C master and slave devices can only drive these lines low or leave them open. The *termination resistor* R_p (show in blue at figure 18) pulls the line up to V_{CC} if no I2C device is pulling it down. This allows for features like concurrent operation of more than one I2C master (if they are *multi-master* capable) or *stretching* (slaves can slow down communication by holding down SCL).

Together with the wire capacitance C_p the termination resistor R_p affects the temporal behaviour of the signals on SDA and SCL. While I2C devices pull down the lines with open drain drivers or FETs which can in general drive at least about 10mA or more, the pull-up resistor R_p is responsible to get the signal back to high level. R_p commonly ranges from 1 k Ω to 10 k Ω , resulting in typical pull-up currents of about 1 mA and less. This is the reason for the characteristic saw tooth-like look of I2C signals. In fact, every 'tooth' shows the charge-characteristic of the line on the rising edge and the discharge-characteristic on the falling edge.

Particularity in the chip DS3231 the $C_b = 400$ pF and $I = 1$ mA. The SCL clock runs with 100 kHz (nominal).

$$R_{PU\ MAX} = \frac{I_r}{C_b} (100Khz)$$

Equations 4 Rpu max value

$$R_{PU\ MIN} = \frac{V_{cc} - 0.4}{3mA} (100Khz)$$

Equations 5 Rpu min value

The Rpu must be between 1KΩ and 10KΩ so installing a 4,7KΩ resistor in the SDA and SCL line is necessary.

Use a digital oscilloscope connected to the SDA (Yellow) and SCL (Green) line we get the next graphics.



Figure 16 Start bit for the communication i2c

As is shown in the figure above the communication through the i2c module is working, the definition of the register of the chapter 3.2.3 is sending a 0 on the SDA line, with is forced to 1 for the pull-up resistor.



Figure 17 Transferring data between RTC and the PIC

In this last oscilloscope capture we observe how the data is transferred to the RTC. In green (SCL) we can see the clock sending the pulse trains and in yellow (SDA) the RTC or the microcontroller sending the instructions.

ADDRESS	BIT 7 MSB	BIT 6	BIT 5	BIT 4	BIT 3	BIT 2	BIT 1	BIT 0 LSB	FUNCTION	RANGE
00h	0	10 Seconds			Seconds			Seconds	Seconds	00–59
01h	0	10 Minutes			Minutes			Minutes	Minutes	00–59
02h	0	12/24	AM/PM 20 Hour	10 Hour	Hour			Hour	Hours	1–12 + AM/PM 00–23
03h	0	0	0	0	0	Day		Day	Day	1–7
04h	0	0	10 Date		Date			Date	Date	01–31
05h	Century	0	0	10 Month	Month			Month/ Century	Month/ Century	01–12 + Century
06h	10 Year			Year			Year	Year	Year	00–99
07h	A1M1	10 Seconds			Seconds			Alarm 1 Seconds	Alarm 1 Seconds	00–59
08h	A1M2	10 Minutes			Minutes			Alarm 1 Minutes	Alarm 1 Minutes	00–59
09h	A1M3	12/24	AM/PM 20 Hour	10 Hour	Hour			Alarm 1 Hours	Alarm 1 Hours	1–12 + AM/PM 00–23
0Ah	A1M4	DY/DT	10 Date		Day			Alarm 1 Day	Alarm 1 Day	1–7
					Date			Alarm 1 Date	Alarm 1 Date	1–31
0Bh	A2M2	10 Minutes			Minutes			Alarm 2 Minutes	Alarm 2 Minutes	00–59
0Ch	A2M3	12/24	AM/PM 20 Hour	10 Hour	Hour			Alarm 2 Hours	Alarm 2 Hours	1–12 + AM/PM 00–23
0Dh	A2M4	DY/DT	10 Date		Day			Alarm 2 Day	Alarm 2 Day	1–7
					Date			Alarm 2 Date	Alarm 2 Date	1–31
0Eh	EOSC	BBSQW	CONV	RS2	RS1	INTCN	A2IE	A1IE	Control	—
0Fh	OSF	0	0	0	EN32kHz	BSY	A2F	A1F	Control/Status	—
10h	SIGN	DATA	DATA	DATA	DATA	DATA	DATA	DATA	Aging Offset	—
11h	SIGN	DATA	DATA	DATA	DATA	DATA	DATA	DATA	MSB of Temp	—
12h	DATA	DATA	0	0	0	0	0	0	LSB of Temp	—

Table 16 Address map of the DS3231- Source: Datasheet DS3231

Thought the i2c module we send the bit ADDRESS which the RTC chip read and send back the corresponding number as a respond. According to the table above the different address from 0 to 10 correspond to different time values and 11 and 12 are for and internal digital temperature sensor.

The time and calendar data are set by writing the appropriate register bytes. The contents of the time and calendar registers are in the binary-coded decimal (BCD) format.

In order to show the value of the data get from the register is necessary to convert the number to decimal, and to change the value of the register is necessary to write it in BCD value:

$$Value_2 = \left(\frac{Value_{BCD}}{16}\right) \cdot 10 + \frac{Value_{BCD}}{16} \text{ (only integral number)}$$

Equations 6 Transform from BCD value to binary

$$Value_{BCD} = \left(\frac{Value_2}{10}\right) \cdot 16 + \frac{Value_2}{10} \text{ (only integral number)}$$

Equations 7 Transform from binary value to BCD

The DS3231 can be run in either 12-hour or 24-hour mode. Bit 6 of the hours register is defined as the 12- or 24-hour mode select bit. When high, the 12-hour mode is selected. In the 12-hour mode, bit 5 is the AM/PM bit with logic-high being PM. In the 24-hour mode, bit 5 is the 20-hour bit (20–23 hours). The century bit (bit 7 of the month register) is toggled when the years register overflows from 99 to 00.

The day-of-week register increments at midnight. Values that correspond to the day of week are user-defined but must be sequential (i.e., if 1 equals Sunday, then 2 equals Monday, and so on). Illogical time and date entries result in undefined operation.

When reading or writing the time and date registers, secondary buffers are used to prevent errors when the internal registers update. When reading the time and date registers, the user buffers are synchronized to the internal registers on any START and when the register pointer rolls over to zero. The time information is read from these secondary registers, while the clock continues to run. This eliminates the need to reread the registers in case the main registers update during a read.

The countdown chain is reset whenever the seconds register is written. Write transfers occur on the acknowledgement from the DS3231. Once the countdown chain is reset, to avoid rollover issues, the remaining time and date registers must be written within 1 second. The 1Hz square-wave output, if enabled, transitions high 500ms after the seconds data transfer, provided the oscillator is already running.

3.4. Multiplexor/Demultiplexor

The Multiplexor used in the system is the HEF4051B, is an 8-channel analog multiplexer/demultiplexer with three address inputs (S1 to S3), an active LOW enable input (E), eight independent inputs/outputs (Y0 to Y7) and a common input/output (Z). The device contains eight bidirectional analog switches, each with one side connected to an independent input/output (Y0 to Y7) and the other side connected to a common input/output (Z). With E LOW, one of the eight switches is selected (low-impedance ON-state) by S1 to S3. With E HIGH, all switches are in the high-impedance OFF-state, independent of S1 to S3

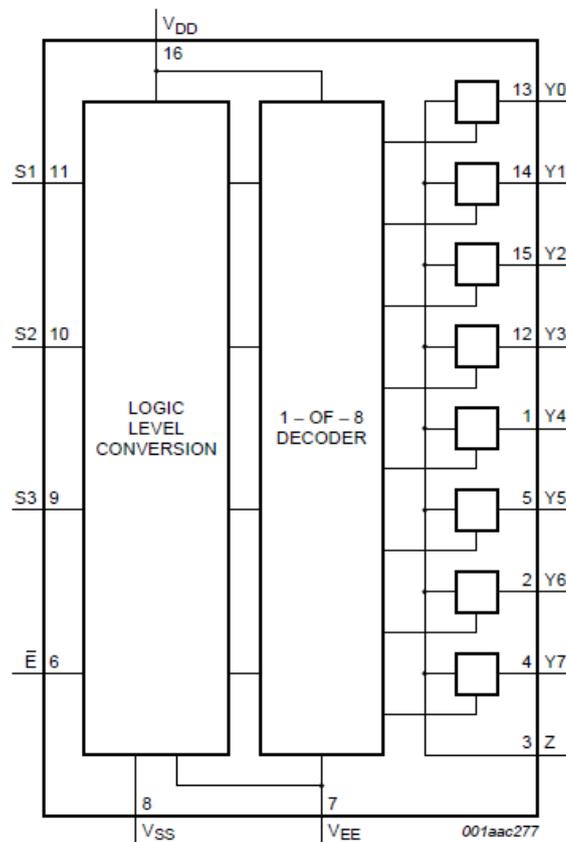


Figure 18 Functional diagram HEF4051
 - Source: Datasheet HEF4051

The reason to use a multiplexor is because the microcontroller don't have enough general input. The system need a motor for a peristaltic pump, and at least 3 motors for the 3 valves, each motor use 2 endstops, so we need 8 input to control de motors. Plus each motor need and extra 3 outputs to chose the spin directions and extra 12 inputs. So for that reason is necessary to use a multiplexor. The best choice is to connect the simple endstops, which send a simple 5V signal to the microcontroller thought a multiplexor. Actually we need 2 multiplexors with up to 16 extra I/O pins.

Features	HEF4051
Fully static operation	Yes
Parametric ratings	5 V, 10 V, and 15 V
Standardized symmetrical output characteristics	Yes
Complies with JEDEC standard	JESD 13-B
Analog channels	8
Operating Temperature Ranges:	-40 °C to +85 °C and -40 °C to +125 °C

Table 17 Specs and features of HEF4051

VDD and VSS are the supply voltage connections for the digital control inputs (S1 to S3, and E). The VDD to VSS range is 3 V to 15 V. The analog inputs/outputs (Y0 to Y7, and Z) can swing between VDD as a positive limit and VEE as a negative limit. VDD - VEE may not exceed 15 V. Unused inputs must be connected to VDD, VSS, or another input. For operation as a digital multiplexer/demultiplexer, VEE is connected to VSS (typically ground). VEE and VSS are the supply voltage connections for the switches.

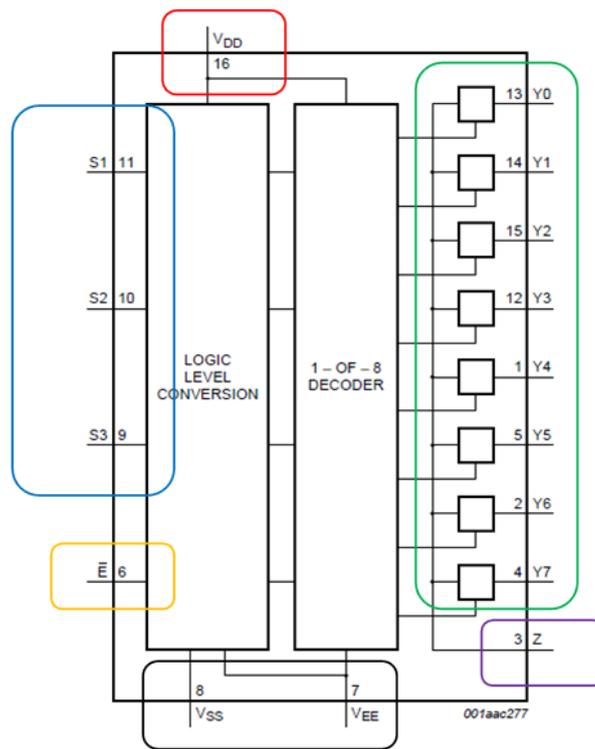


Figure 19 HEF4051 chip description

Symbol	Pin	Description	Connected to
E	6	Enable input	Ground
Vee	7	Supply voltage	Ground
Vss	8	Ground supply voltage	Ground
S1,S2,S3	11,10,9	Select input	Microcontroller output selector
Y0, Y1, Y2, Y3, Y4, Y5, Y6, Y7	13,14,15,1,2,1,5,2,4	Independent input or output	Endstops
Z	3	Common output or input	Microcontroller input receiver
Vdd	16	Supply voltage	+5V

Table 18 Pin description and connexion HEF4051

For our purpose and for with voltage the system can provide, the Vee and Vss are 0V and the Vdd is +5V. With this configuration the system work inside the operation zone of the chip.

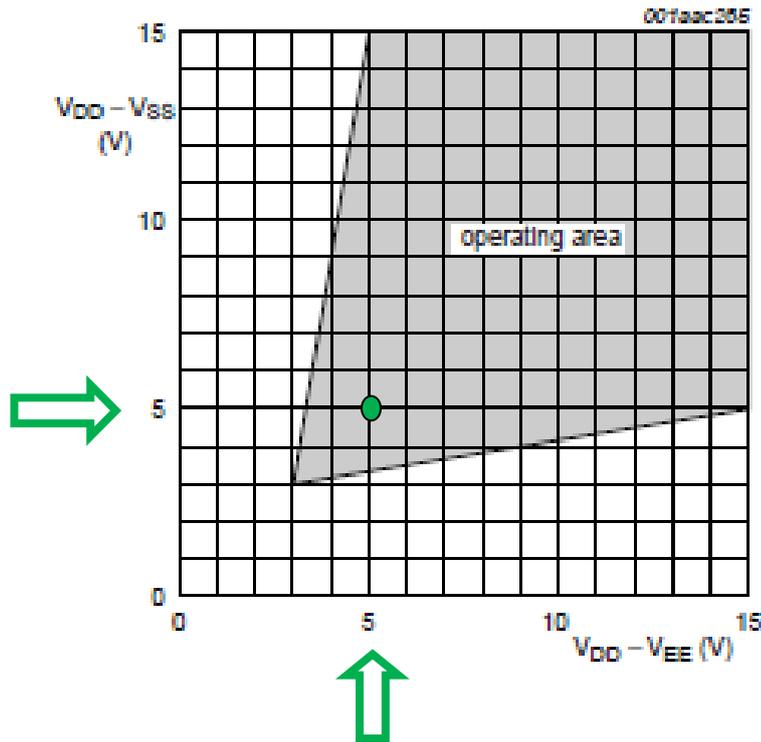


Figure 20 Operating area of the HEF4051 for the system - Source: Datasheet HEF4051

3.5. Motor driver

The L293 and L293D are quadruple high-current half-H drivers. The L293 is designed to provide bidirectional drive currents of up to 1A at voltages from 4.5 V to 36 V. The L293D is designed to provide bidirectional drive currents of up to 600mA at voltages from 4.5 V to 36 V. Both devices are designed to drive inductive loads such as relays, solenoids, dc and bipolar stepping motors, as well as other high-current/high-voltage loads in positive-supply applications.

All inputs are TTL compatible. Each output is a complete totem-pole drive circuit, with a Darlington transistor sink and a pseudo Darlington source. Drivers are enabled in pairs, with drivers 1 and 2 enabled by 1,2EN and drivers 3 and 4 enabled by 3, 4 EN. When an enable input is high, the associated drivers are enabled, and their outputs are active and in phase with their inputs. When the enable input is low, those drivers are disabled, and their outputs are off and in the high-impedance state. With the proper data inputs, each pair of drivers forms a full-H (or bridge) reversible drive suitable for solenoid or motor applications.

Features	L293D
Supply voltage for the motors	4.5V to 36V
Supply voltage	4.5 V to 7V
Peak output current	±2 A
Continuous output current	±600 mA
Maximum junction temperature	150°C

Table 19 Specs and features L293D

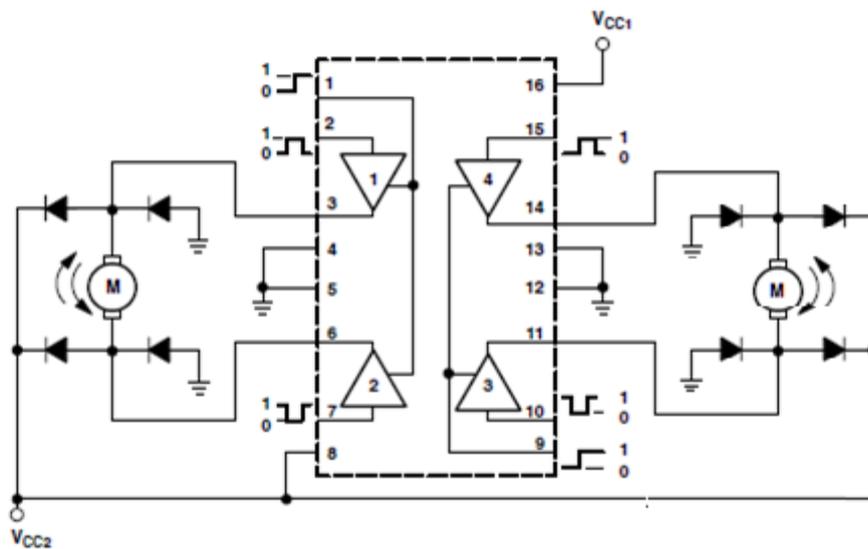


Figure 21 Diagram of the motor driver

With this configuration show above we can run the DC motor in both direction with also the system to open or close the valves or run the pump to suck liquid or push it thought the plumbing.

To achieve that, the integrated circuit control 4 MOSFET transistor for each motor, in the architecture of the L293 there 8 of this transistor and is capable to fully control 2 DC motor for a single chip.

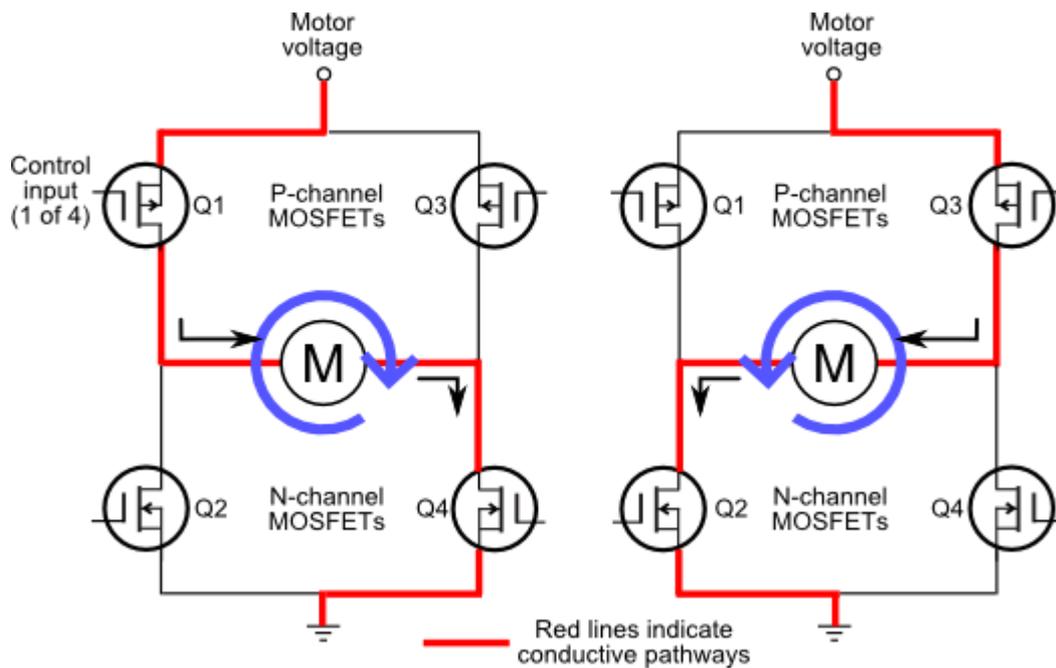


Figure 22 Internal schematics of an H bridge motor control - Source: robotid.com

As it can be seen in the figure 25, when the circuit close the circuit through the transistor Q1 and Q4 the motor spin in one direction. Just by changing the ON transistor to Q3 and Q2 the motor spin in reverse.

In the chip L293 to operate the direction of the motor we have to provide 2 bits of data, 01 or 10 to change the speed, the other possible bits are for blocking the motor, 00 and 11.

3.6. Relay

The relay SLA-05VDC is a mechanical switch to operate high loads by just using a 5V low signal from a microcontroller.

A relay is a mechanical contact actuated through a magnetic coil. When the coil is energised according to the specifications of the relay a magnetic flux moves the contact from the normal position to a new one.

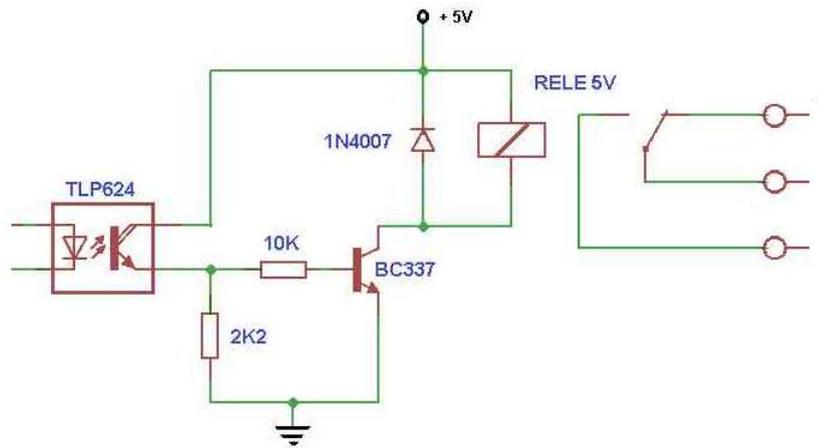


Figure 23 Schematic relay module

The contact has 1 common pin and 2 contacts to choose between connect or disconnect a signal to control.

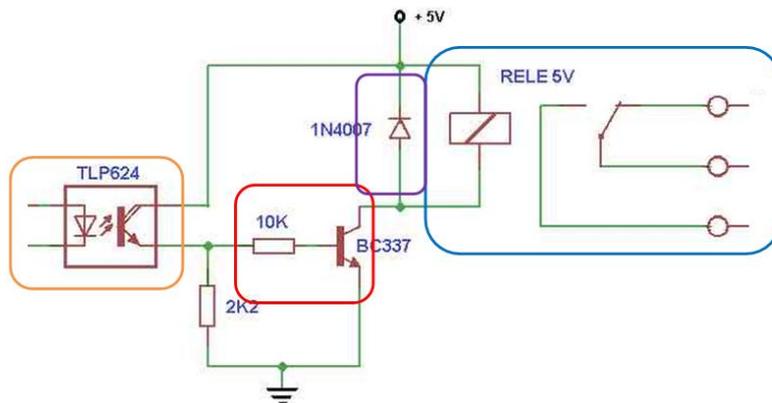


Figure 24 Schematic explanation

The relay module is formed by optocoupler (orange), which is activated by a transistor (red). Right after this transistor close the circuit through its gate, the 5V coil is excited and activate the main switch, the metal contact of the relay.

The optocoupler is to insulate the system that sends the signal, the microcontroller, from the high power, which the relay is controlling. In case of short circuit on the high power the microcontroller can't be damage.

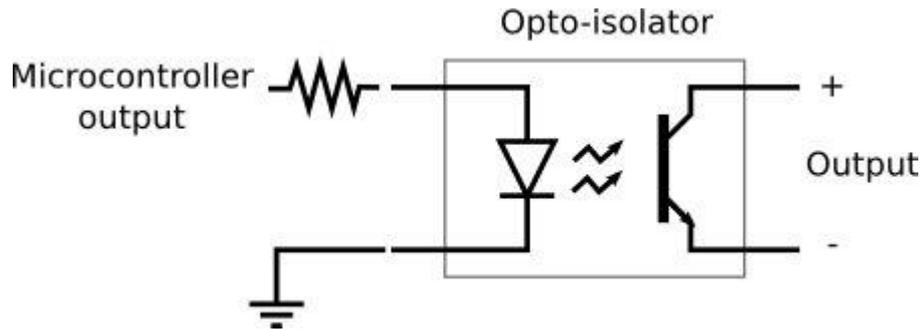


Figure 25 *Optocoupler diagram - Source: electronics-lab.com*

The optocoupler as show in the figure 28 is a diode light emitter (LED) pointing to a transistor photosensitive, exited by light, there is not electrical communication.

The diode, on figure 27 (purple), in parallel with the coils of the relay is mandatory to be installed to avoid damage on the circuit after few uses. When the coil is exited and magnetise the contact, the coil is also charged, so for a few millisecond after been disconnected it still having energy storage and this voltage is discharged thought this diode instead of thought the sensible transistor.

3.7. Electronic circuit

Once all the integrated chips are properly selected and powered, is time to connect them to their corresponding places in order to achieve the main goal of the project.

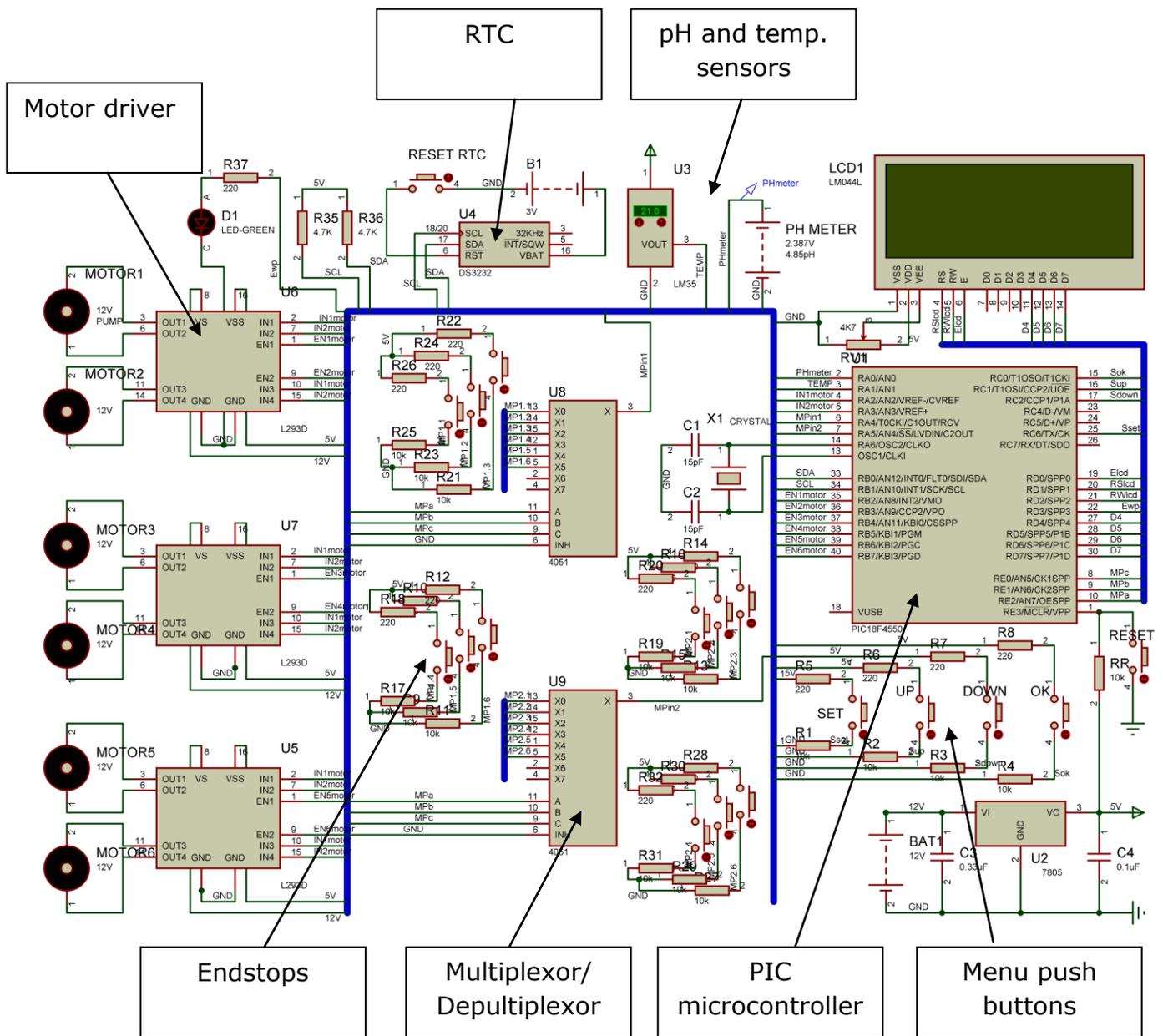


Figure 26 Electronics circuits scheme

The microcontroller is the heart of the electronics; it received the signal from the sensor and the real time from the RTC. The motor drives are control also by the microcontroller and use external power to drive the different motors. The user is able to interact with the system using the push buttons and the LCD.

To allow the microcontroller to know what the motor are doing a bunch of endstops have been connected though a multiplexor.

3.8. PCB design

In order to obtain a PCB to place the entire component described above is necessary to design the routed of the tract to connect them. This process was made from the simulation described in chapter 6. It was necessary to make some modifications to the simulation like, changing the packaging of the component to the actual package that I bought from the electronic component shop. Also the packaging of all the motor and sensor have been change for male connector because this won't be attached to the PCB

3.8.1. PCB layout

After cheeking all the packaging of all the components I run the PCB design program to proceed to place the actual components.

The program use is a tool from the software Proteus 7.8 is the ARES PCB layout program.

This system was set to have two layer of cooper per PCB, after placing and position all the components the PCB look like this:

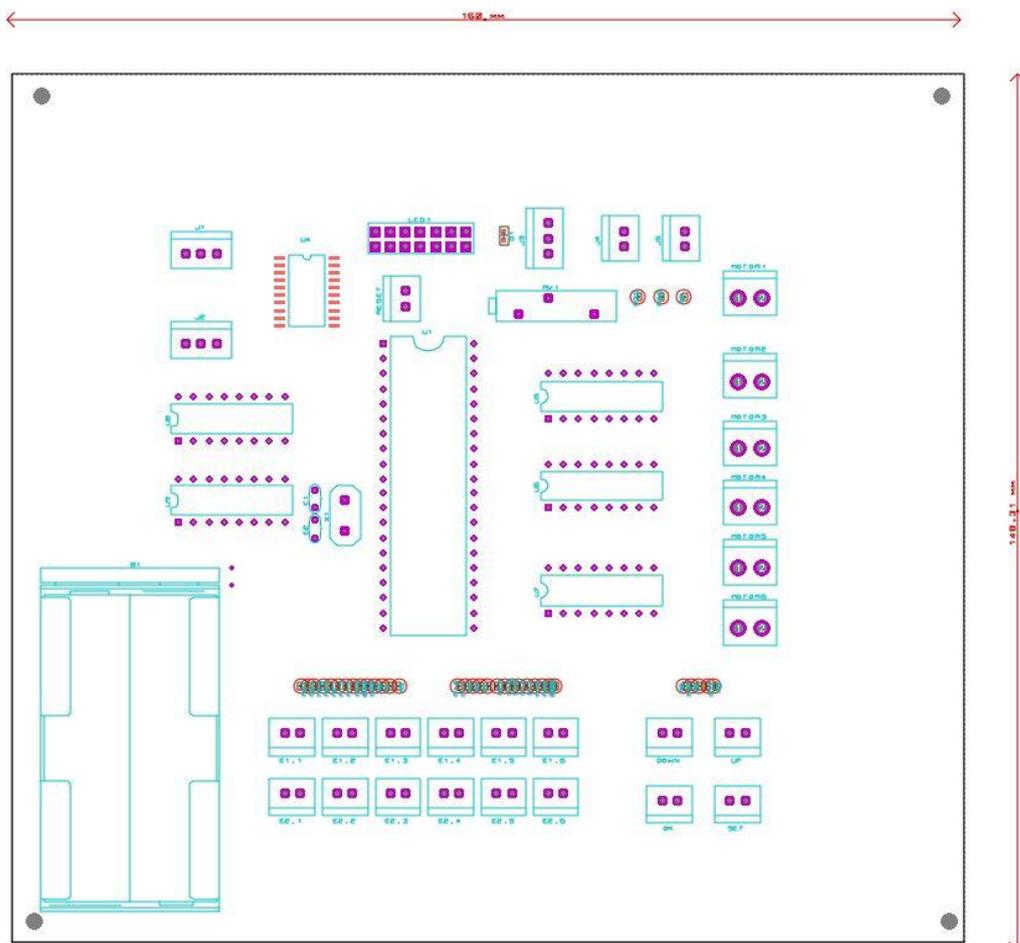


Figure 27 PCB layout, all the component placed

On figure 30 is possible to spot, on the centre is the microcontroller and on its left side the multiplexer for the endstops, and on the right side are the drivers for the motors. At the bottom is all the connector for the endstops with its resistor on top and on the right side are the connector for the motor.

On the top from left to right are the connectors for the sensors the RTC the connector for the LCD and the connector for the relay and the push buttons for the menu. The big rectangle on the bottom left corner is the 3V battery for the battery backup of the RTC.

Once all the components have been placed on the best position are necessary to rout as it was on the simulation.

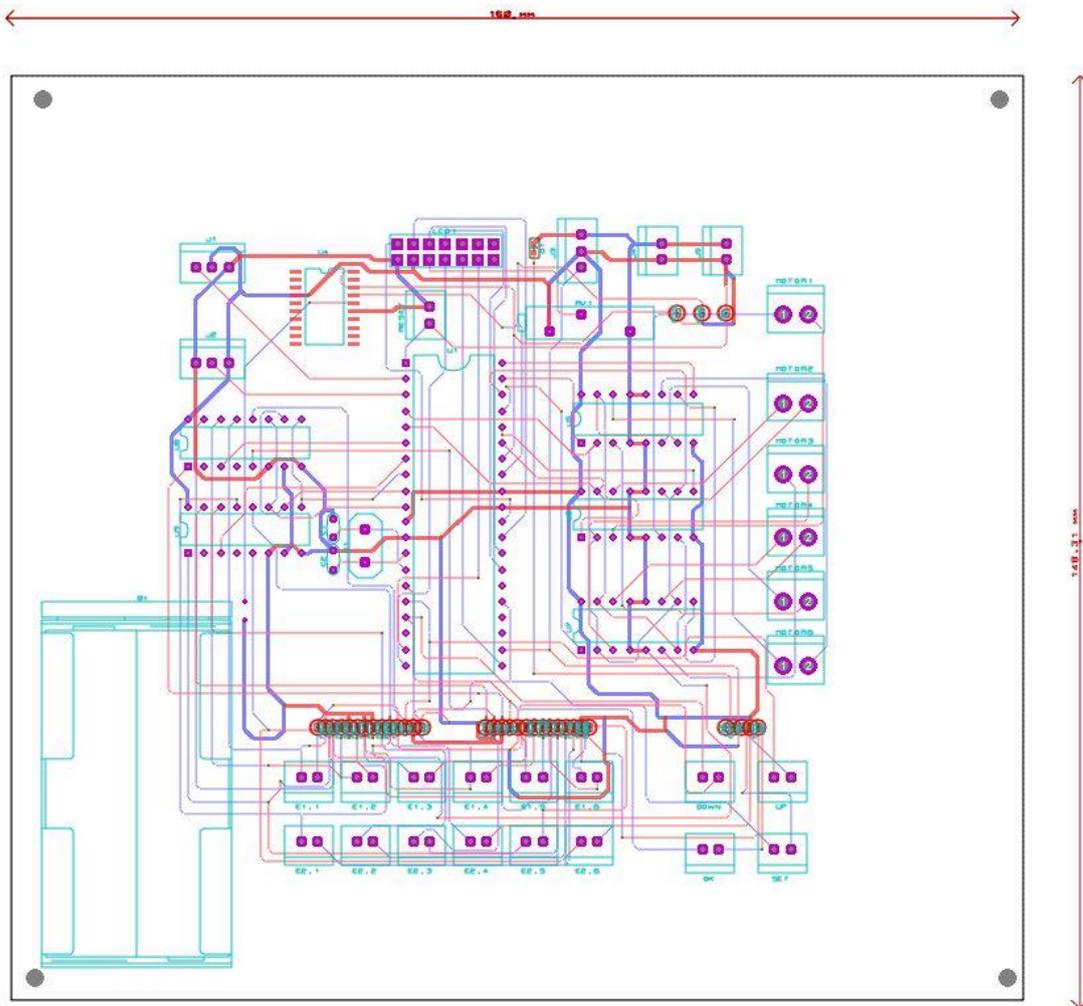


Figure 28 PCB layout, routed of all the components

On figure 31, the track on red are those with run on the top copper layer and the sea blue are those which run on the bottom copper layer, the corners of a track have been changes to a 45° angle to avoid any interference with the other tracks. The entire tracks are equally spaced to each other.

On the Technical schemes volume are the 6 images files needed to made the PCB:

- Top copper, the copper line to connect the devices of the upper layer
- Bottom copper, the copper line connect the devices of the lower layer
- Top resist, the spots where is needed a ring around the holes to solder the devices on the top layer
- Bottom resist, the spots where is needed a ring around the holes to solder the devices on the bottom layer
- Top silk, a schematic picture of the device to identify its place.
- Drill, the spot to drill the holes.

3.8.2. PCB components (BOM)

From the simulation software is also possible to obtain a build of material for all the components used:

Family	Quantity	Reference	Value
35 Resistors	16	R1-R4, R9, R11, R13, R15, R17, R19, R21, R23, R25, R27, R29, R31,RR	10K
	17	R5-R8, R10, R12, R14, R16, R18, R20, R22, R24, R26, R28, R30, R32, R37	220
	2	R35, R36	4.7K
	1	RV1	4k7 Potentiometer
2 Capacitors	2	C1,C2	15pF
7 Integrated circuits	1	U1	PIC18f4550
	1	U4	DS3232
	3	U5-U7	L293D
	2	U8,U9	HEF4051
1 Diode	1	D1	LED Green

34 Miscellaneous	1	B1	3V Battery
	1	LCD	LM044L
	1	X1	Crystal 4MHz
	1	Relay module	5VDC relay module
	1	Power supply	5VDC
	1	Power supply	12VDC
17 Connectors	2	J1, J3	SIL-100-03
	1	J2	SIL-156-03
	14	J4- J17	SIL-100-02

Table 20 Build of materials PCB components

CHAPTER 4: MECHANICAL TREATMENT OF LIQUIDS

To keep the price of the system as low as possible, the mechanicals parts of the system will be specifically designed to the porpoise of this project. All the part will be designed in Solid Works 2013 student version. Then the entire component will be 3D printed, using the open source slicing program Cura-BCN3D 0.1.2 and a modified version of the 3D printer BCN3D+.

The design of the peristaltic pump, the press valve and the enclosure of all the other equipment will be explained in this chapter.

4.1. Peristaltic pump

The first device to be designed is the peristaltic pump, which is based on a commercial peristaltic pump. This kind of pump is based on deforming a flexible tube in order to push forward the liquid from inside.

The pump has a rotor inside with a pair of bearing in each side. These bearings are the moving parts, which press the tube. In one side is allocated the geared motor with provide thrust to the rotor.

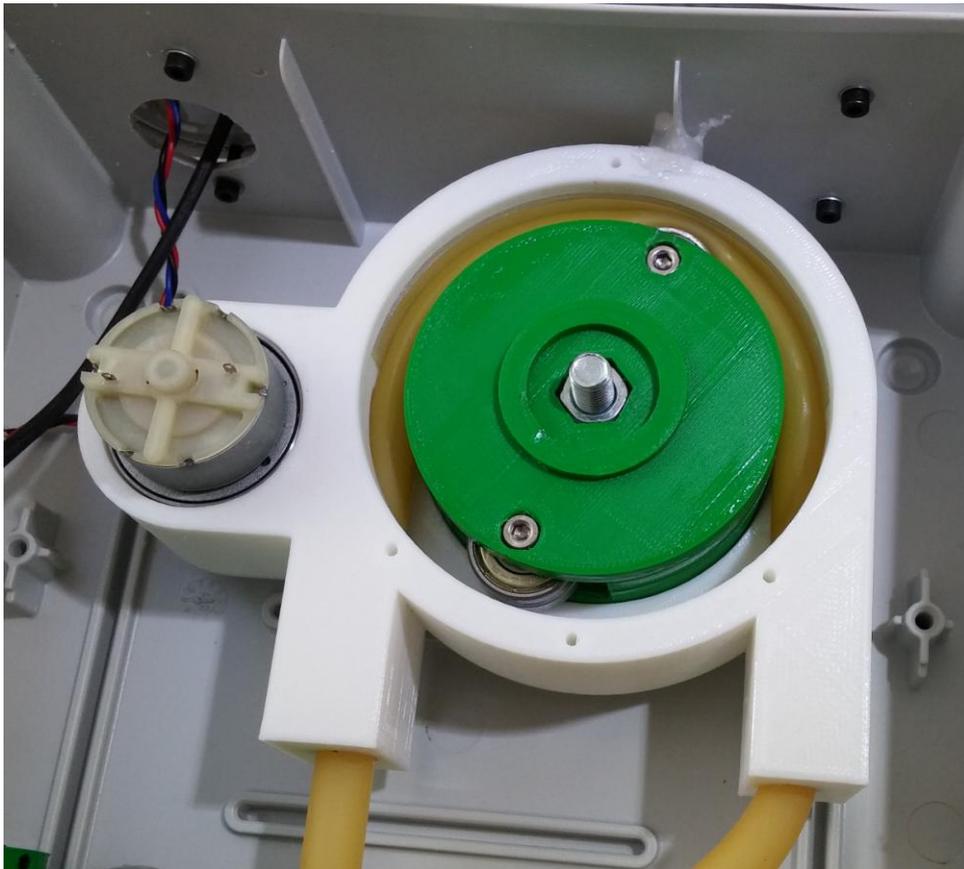


Figure 29 The peristaltic pump

For each half rotation the pump provide 4,5ml of suction in on side and push the same amount of liquid thought the other end of the tube.

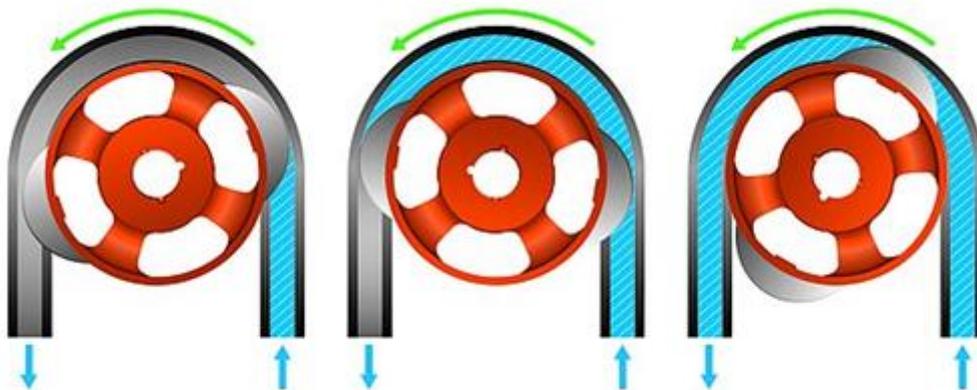


Figure 30 Scheme of operation of a peristaltic pump - Source: Verderflex.com

The pump is providing with an endstops to know when it have made a half rotation. Is not possible to stop in other place rather than the one with a half rotation.

The main reason to choose this pumps rather than other kind of pump is because the microcontroller can have a full control of the dosing system. Also due to the architecture of the pump the liquid inside never get contact with any mechanical part of the pump or the valve. The disadvantage is that is a really slow pump and it takes much more time that other pump to push the same amount of liquid.

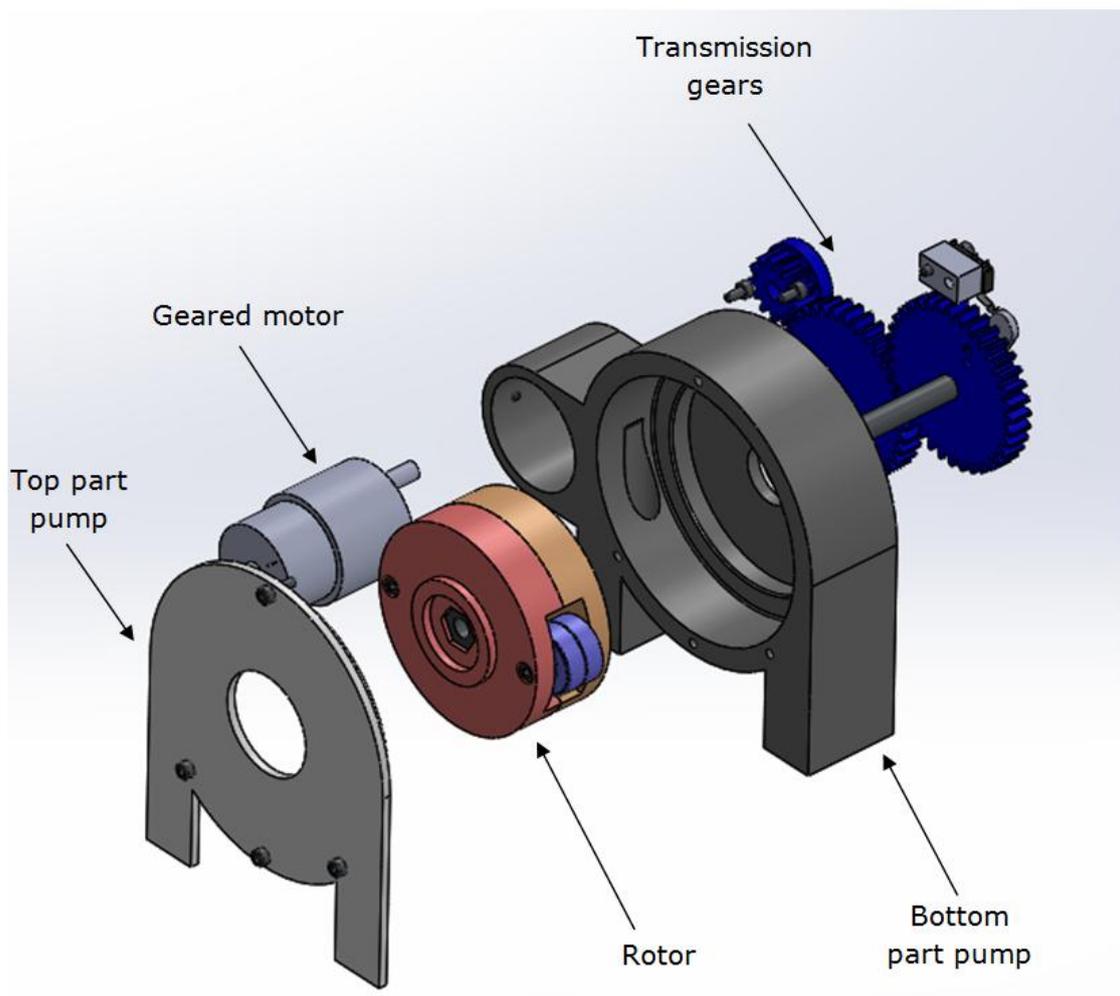


Figure 31 Exploded view of peristaltic pump

4.1.1. Pump case

The base of the peristaltic pump is this part, is where the rotor spin and where the tube is pressed towards the inside wall. It also holds the motor, gears and endstops in place.

From the bottom part the tube enters to the pump and do a U shape down to the other side. Once inside the tube is holding it in place by a bulge in the case.

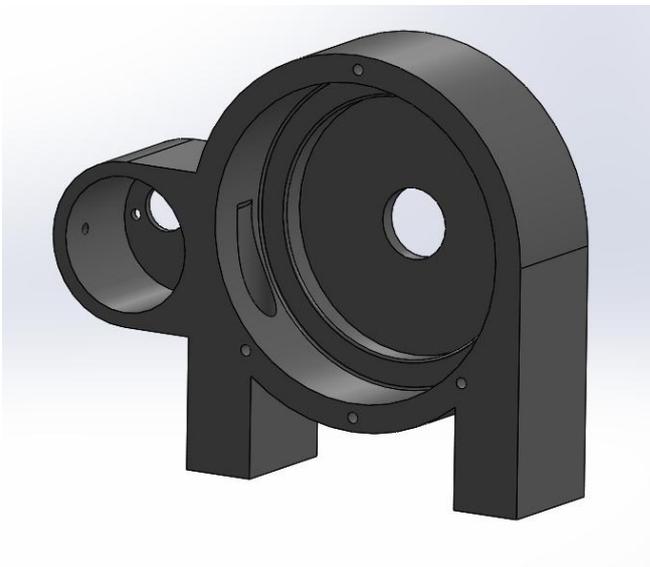


Figure 33 CAD Bottom part pump

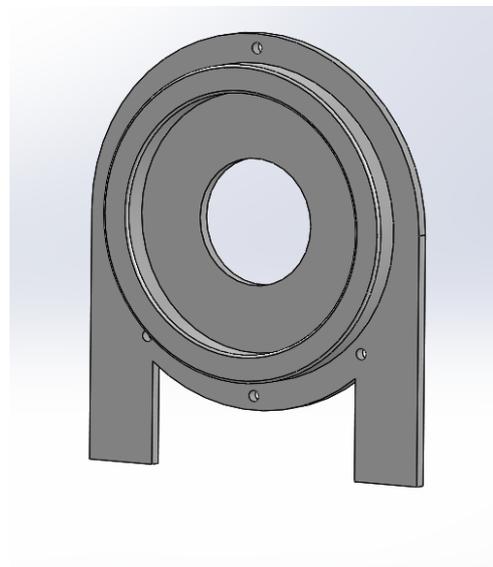


Figure 32 CAD Top part pump

The same bulge is on the other half of the pump case to keep the tube all the time centred inside the case

4.1.2. Rotor

This rotor is a sandwich between two parts, which trap together a pair of bearings in each side. To minimize the friction to the tube, the bearing rotate around a bussing (4-8-10) with also rotate in a M4x25 screw.

To keep both half of the rotor together a M8x40 press from both side together and also a main gear at the back.

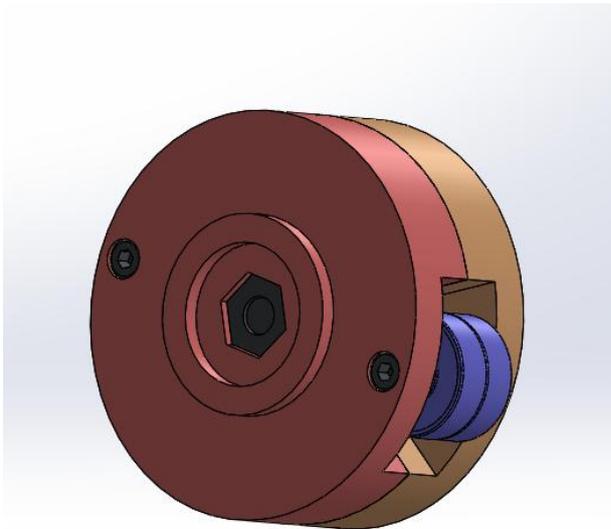


Figure 35 Front view CAD rotor assembled

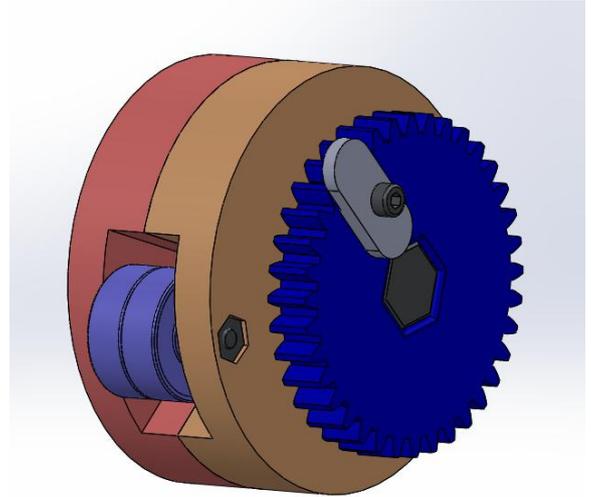


Figure 34 Rear view CAD rotor assembled

This gear also holds in place a lever to drive the endstops. This endstops send a signal to the microcontroller for every turn.

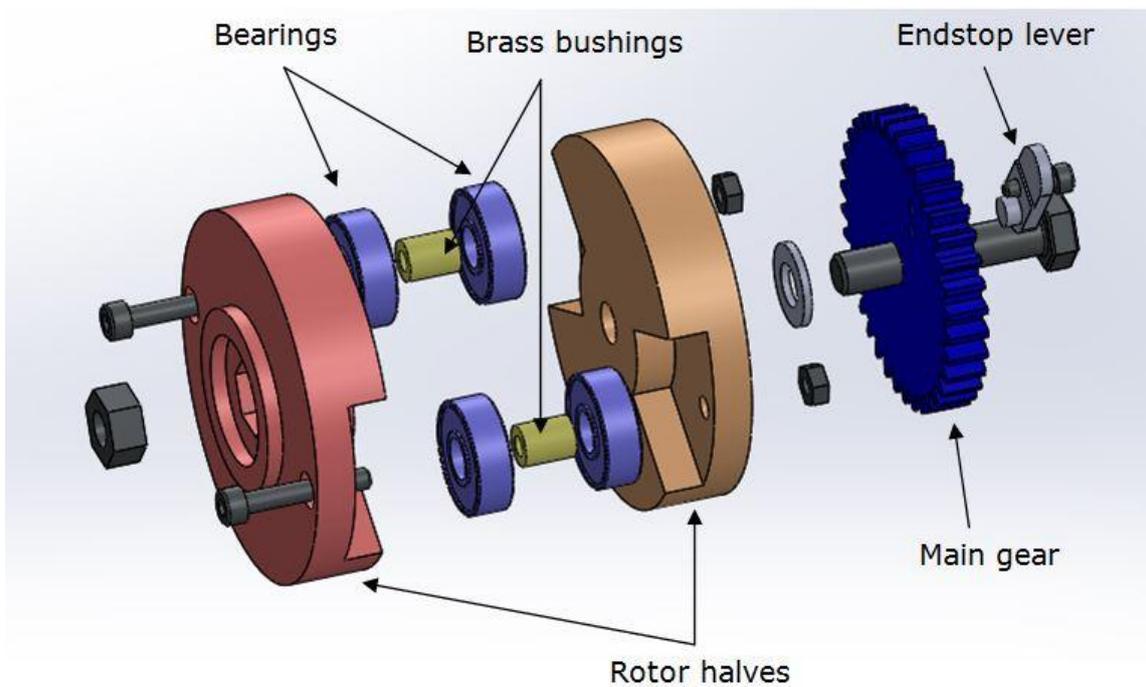


Figure 36 Exploded view rotor

4.1.3. Geared motor

The peristaltic pump uses a geared planetary motor from Mabushi Company. Is a 12 V power motor and the geared inside the metal case reduce the output speed to 15RPM and increase the torque. Right next to the geared motor a chain of two more geared reduce the speed even more.

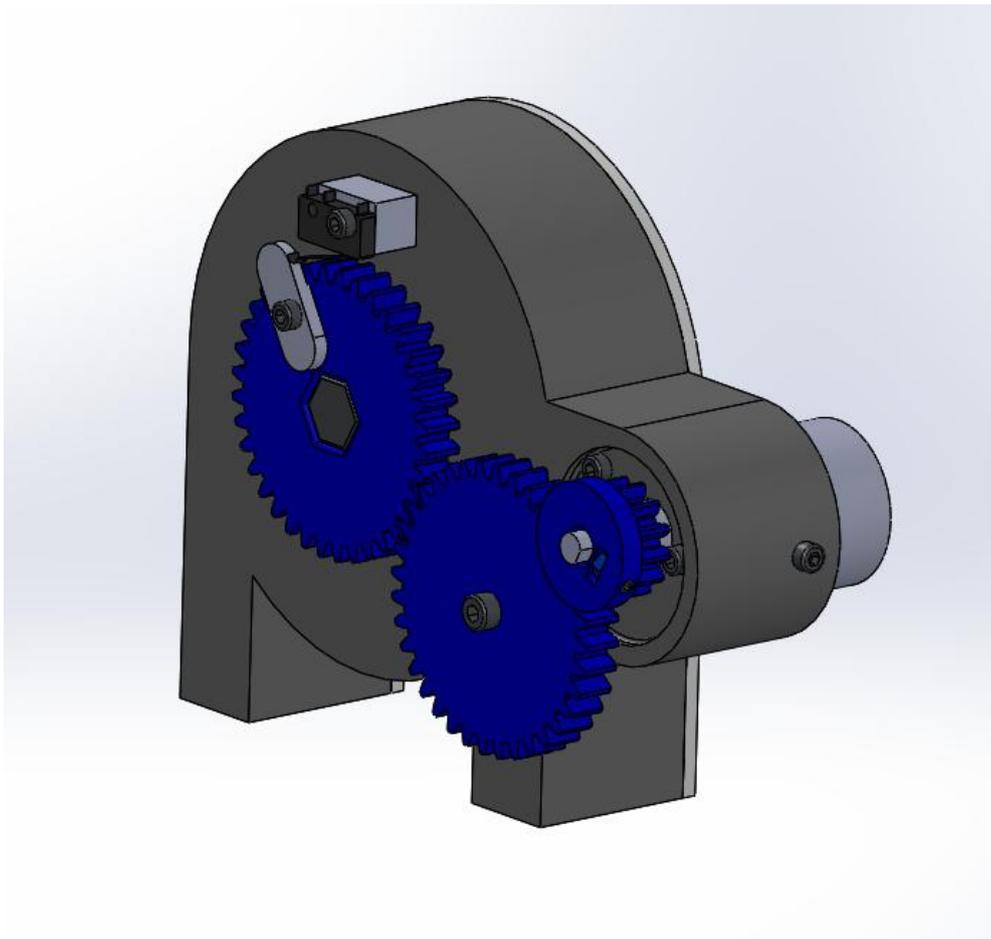


Figure 37 Rear view peristaltic pump, motor and gears

The small one attached to the motor (motor gear) have 13 teeth and is the drove one (N_B), the other two big gears (transmission gear and main gear) have 36 teeth each and are the driven ones (N_A).

$$R = \frac{N_B}{N_A} = \frac{13}{36} = 0.361$$

Equations 8 Gear ratio of the peristaltic pump

The gear ratio is equal to 0.361 and knowing the speed of the geared motor is possible to find the rotation speed of the rotor.

$$R = \frac{\omega_B}{\omega_A}; \omega_B = \omega_A \cdot R; \omega_B = 15 \cdot 0.361 = 5.416rpm$$

Equations 9 angular speed of the peristaltic pump

The actual speed of the rotor is equal to 5.416 rpm, so it takes 11 seconds to do a full rotation.

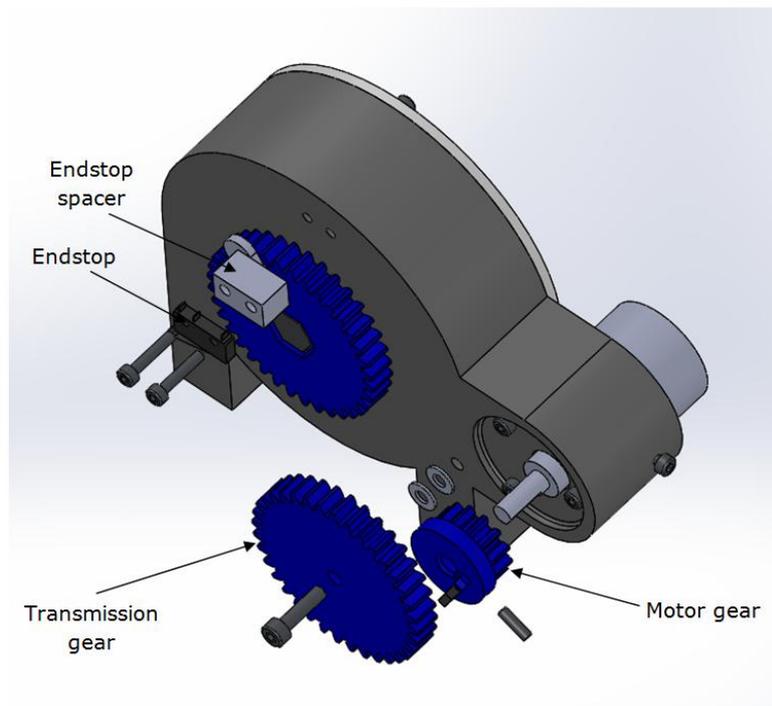


Figure 38 Exploded view gears and geared motor

4.2. Flexible tube

The tube or hose is the main part of the peristaltic pump, and also from the press valve.

The system need a special rubber tube, the specifications need to be like so:

Specifications tub	Max	Min	Units
Hardness	60	40	Shore scale
Outer diameter	11	10	mm
Inner diameter	7	6	mm
Corrosive resistance			Acid and bases

Table 21 Specification for the correct peristaltic tube

The tube that is being used in the system is a latex laboratory tube is not suitable for corrosive chemical like the acids and base that are used in this system. But it has been impossible to buy a peristaltic pump tube. A suitable option will be the Hypalom - CSM or the Vitron tube from the Spanish based company VerderFlex International B.V.



Figure 39 Picture of the tube Hypalom-CSM from VerderFlex to be used in this system - Source: verderflex.com

Verderflex is a company who used to sell for and industrial porpoise and it was really expensive to buy this tube for this small project.

4.3. Press valve

In order to choose between the different chemical, the microcontroller close all the valves and open only the one with the selected chemical. To do so this valve presses the tube to block the flow of liquid inside the tube.

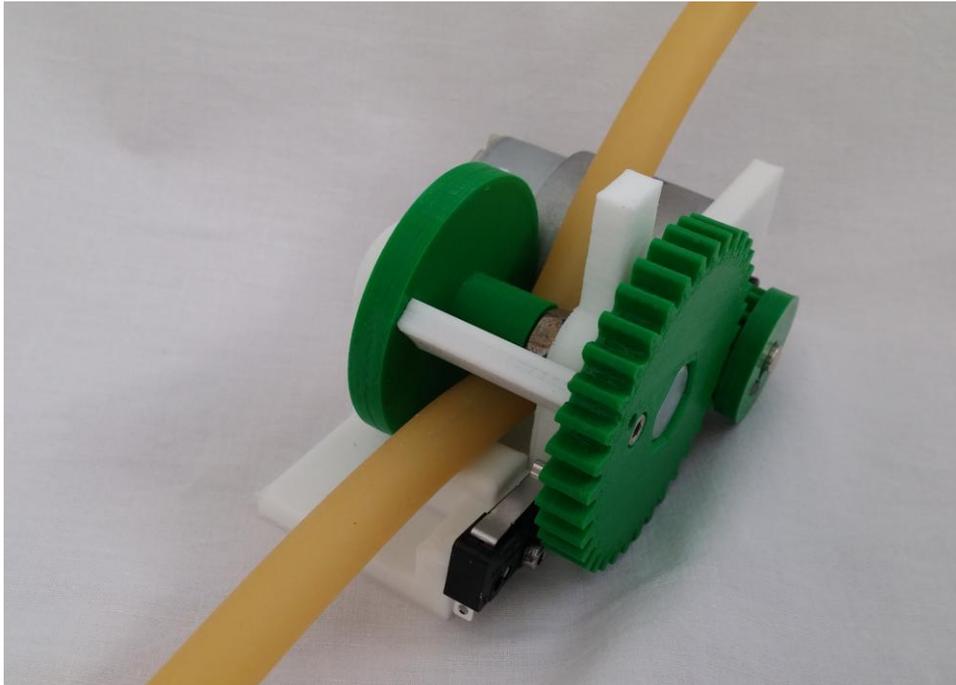


Figure 40 *The press valve*

When the tube is fully press the valve also activated the endstop to send a signal to the microcontroller to stop the motor. This process is the same when the microcontroller is opening the valve.

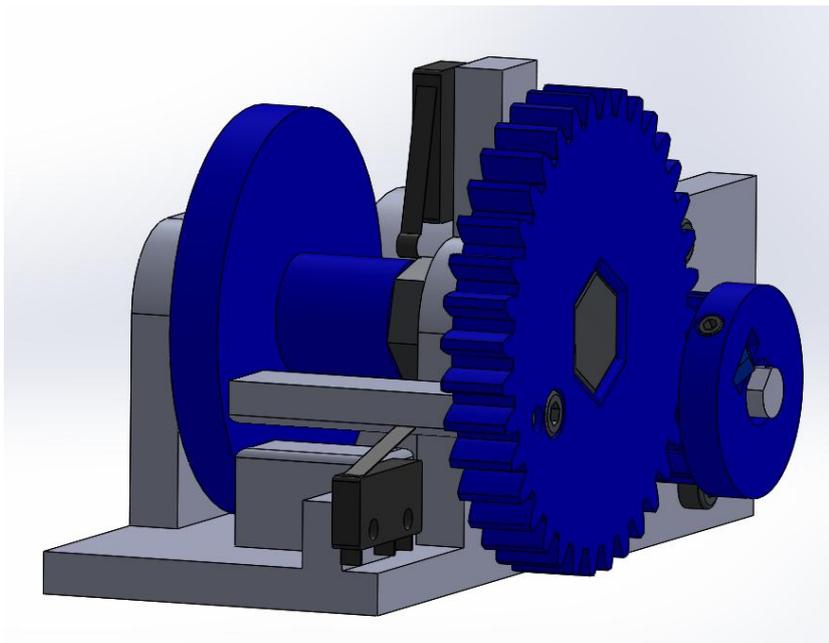


Figure 41 *CAD press valve, fully close*

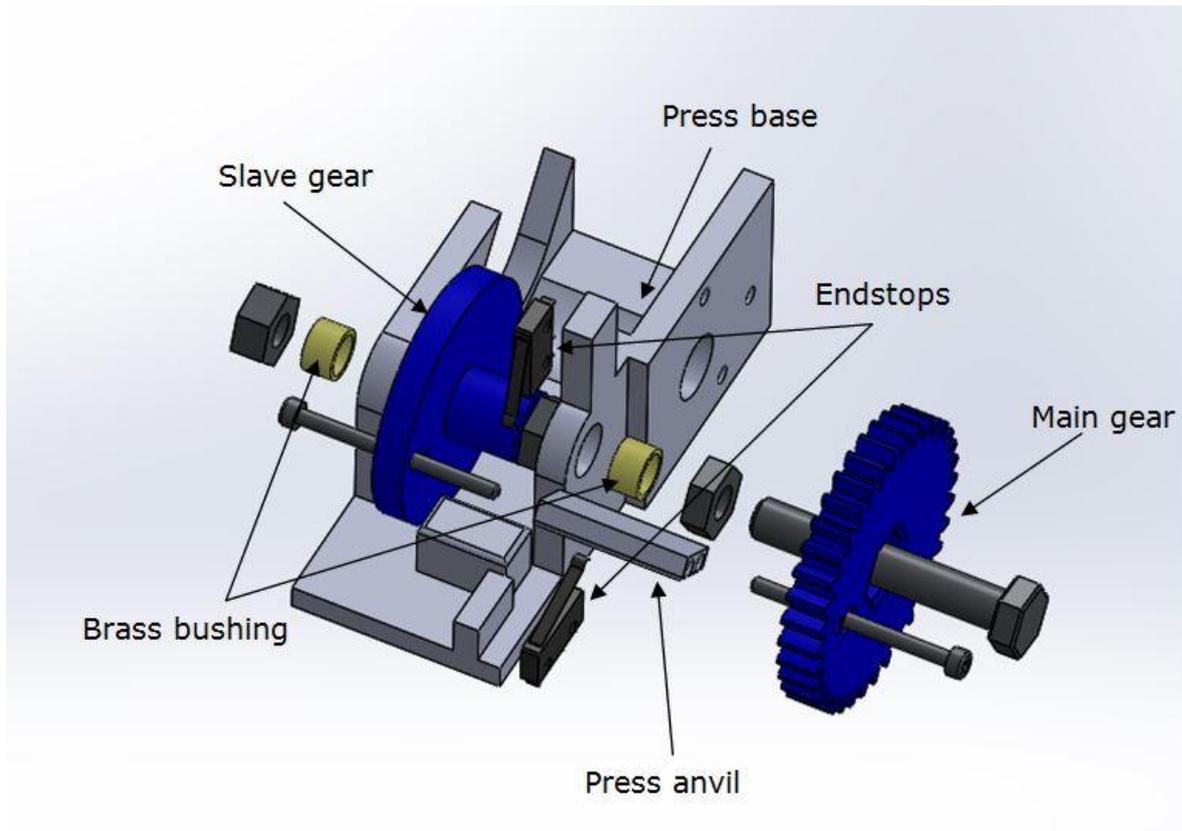


Figure 42 Exploded view press valve

4.3.1. Geared motor

The gears are the same size as in the peristaltic pump, but the geared motor is lower rpm motor because the operation must be under control. The actual output speed of the geared motor of the valve is 3,5 rpm rather than 15rpm of the peristaltic pump.

The small one attached to the motor (motor gear) have 13 teeth and is the drive one (N_B), the other big gear (main gear) have 36 teeth and is the driven one (N_A).

$$R = \frac{N_B}{N_A} = \frac{13}{36} = 0.361$$

Equations 10 Gear ratio of the press valve

The gear ratio is equal to 0.361 and knowing the speed of the geared motor it is possible to find the rotation speed of the rotor.

$$R = \frac{\omega_B}{\omega_A}; \omega_B = \omega_A \cdot R; \omega_B = 3.5 \cdot 0.361 = 1.263 \text{rpm}$$

Equations 11 angular speed of the press valve

The actual speed of the rotor is equal to 1.263 rpm, so it takes 47,487 seconds to do a full rotation. But in our case that to operate the valve is only necessary to do a quarter or a turn, the time to open and close will be 11,8 seconds.

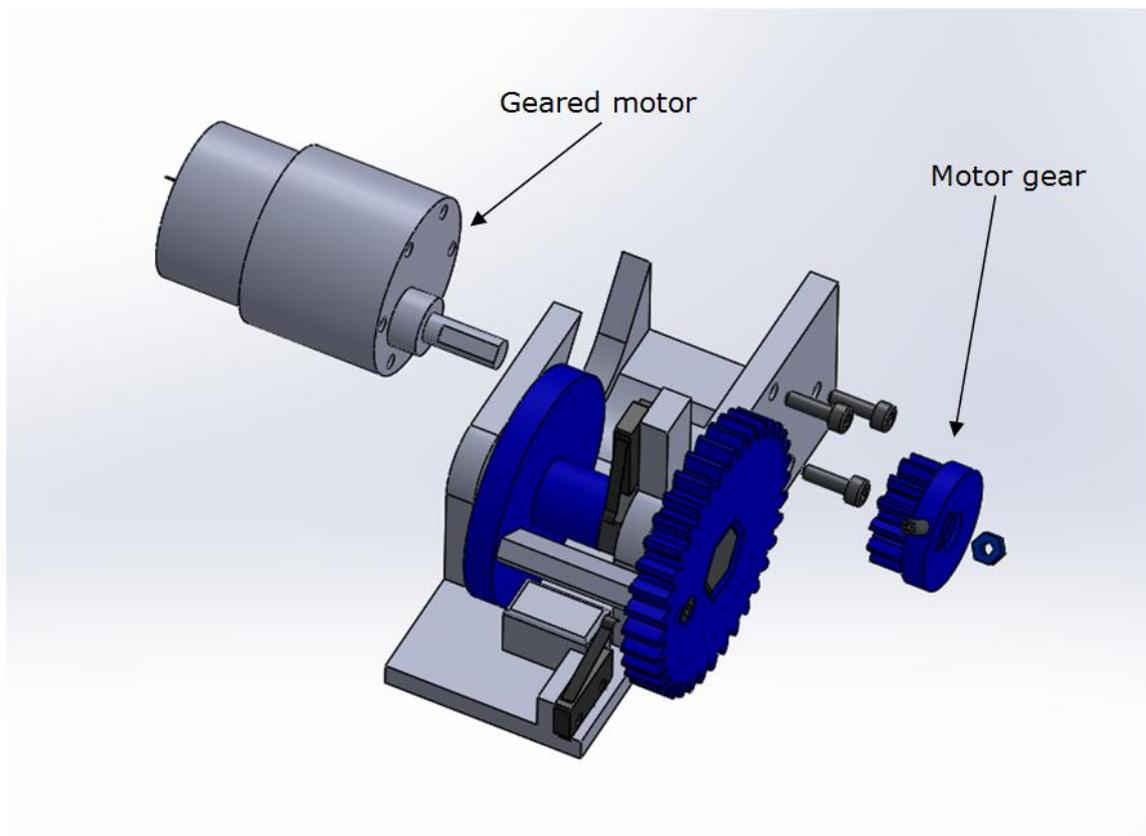


Figure 43 Exploded view geared motor press valve

4.4. Mechanical components (BOM)

From the CAD software is also possible to obtain a build of material for all the components used to build the complete system. The next table is for the commercial elements and the 3D printed parts

Family	Quantity	Reference	Value	
Electronics box	1	Main board		
	1	Waterproof socket	BASE IP44 IK07	
	1	Electronics covert	3D Printed	
	1	Power switch	2A 125V/250V Switch	
	3	Push buttons	0.5A 125V/250V Switch	
Mechanic box	4	T connexions	95HP 70KW	
	1	Flexible latex tube	20 meters	
Peristaltic pump	1	Bottom part pump	3D Printed	
	1	Rotor half 1	3D Printed	
	1	Rotor half 2	3D Printed	
	4	Bearings	Radial bearing 608ZZ	
	2	Bushing	Selfoil 4-8-12	
	1	Top part pump	3D Printed	
	1	Geared motor	Mabuchi 12VDC 15RPM	
	1	Motor gear	3D Printed	
	1	Transmission gear	3D Printed	
	1	Main gear	3D Printed	
	1	Endstop spacer	3D Printed	
	1	Endstop	0.5A 125V/250V Micro Switch	
	1	Endstop contact	3D Printed	
	Press valve	4	Valve base	3D Printed
		4	Motor gear	3D Printed
4		Geared motor	Mabuchi 12VDC 3.5RPM	

	4	Main gear	3D Printed
	4	Press gear slave	3D Printed
	4	Press anvil	3D Printed
	8	Bushings	Selfoil 8-10-6
	8	Endstops	0.5A 125V/250V Micro Switch
Enclosure	1	Electronics box	EX-231
	1	Mechanic box	EX-322

Table 22 BOM commercial and 3D printed parts

The next table is for the screws need to assemble de system:

Quantity	Reference
11	DIN912 M3x6
16	DIN912 M3x8
17	DIN912 M3x10
2	DIN912 M3x16
8	DIN912 M3x40
1	DIN912 M4x16
2	DIN912 M4x25
1	DIN912 M8x40
4	DIN912 M8x50
5	DIN913 M3x10
5	DIN934 M3
2	DIN934 M4
1	DIN125 M8
13	DIN936 M8

Table 23 BOM screws

CHAPTER 5:

SOFTWARE

Until now it has been a description of the circuits and the characteristics of the station, but this would not work alone as the microcontroller requires a program for its operation to carry out the tasks of the system. All parts of the program for the PIC18F4550 are described in this chapter.

The PIC program is made entirely in C language compiled by CCS software and is formed from a main program, various tasks and functions that are called from the main program. The main program functions are described below.

5.1. Main program

The program or main functions contains the main loop and initialization sequence and configuration of the records associated with control modules and microcontroller that runs only when start for the first time or a manual reset.

During the start up sequence, ports A, B, C, D and E, converter analog - digital, the USART and the external input RA0 / RA1 are configured.

The main program also does a first run wizard. When the system is plugged in the user must introduce some basic parameters about the pool that he

have. This parameter will be used later on the calculus of the amount of chemical product to correct the pH.

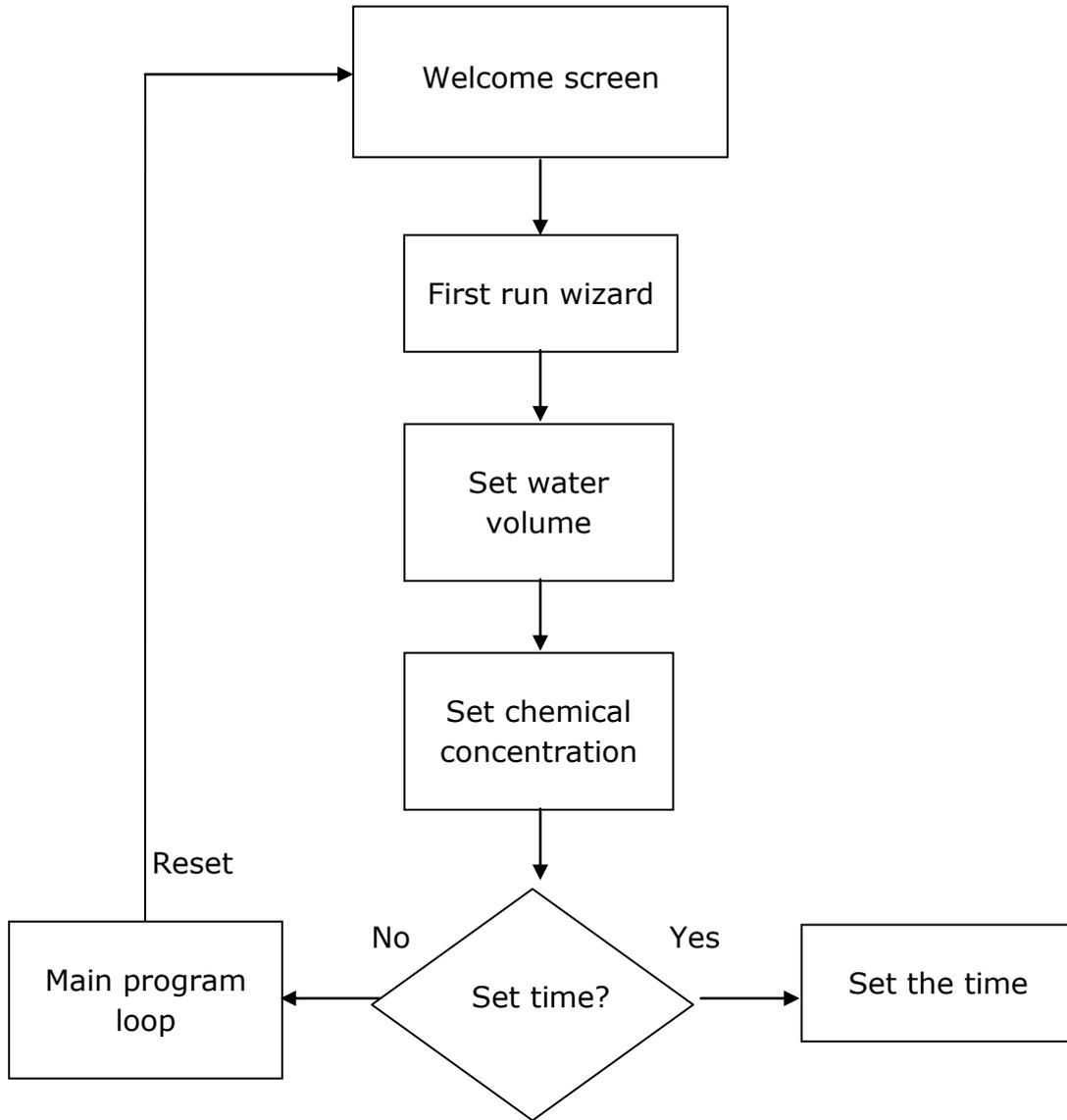


Figure 44 *First run wizard flowchart*

Once the user has chosen the correct parameter he won't be able to change it later on. In case that the user need to change some value he have to press the restart button to run the first run wizard.



Figure 45 Control menu displaying the insert data of water volume



Figure 46 Control menu displaying the insert data of chemical concentration

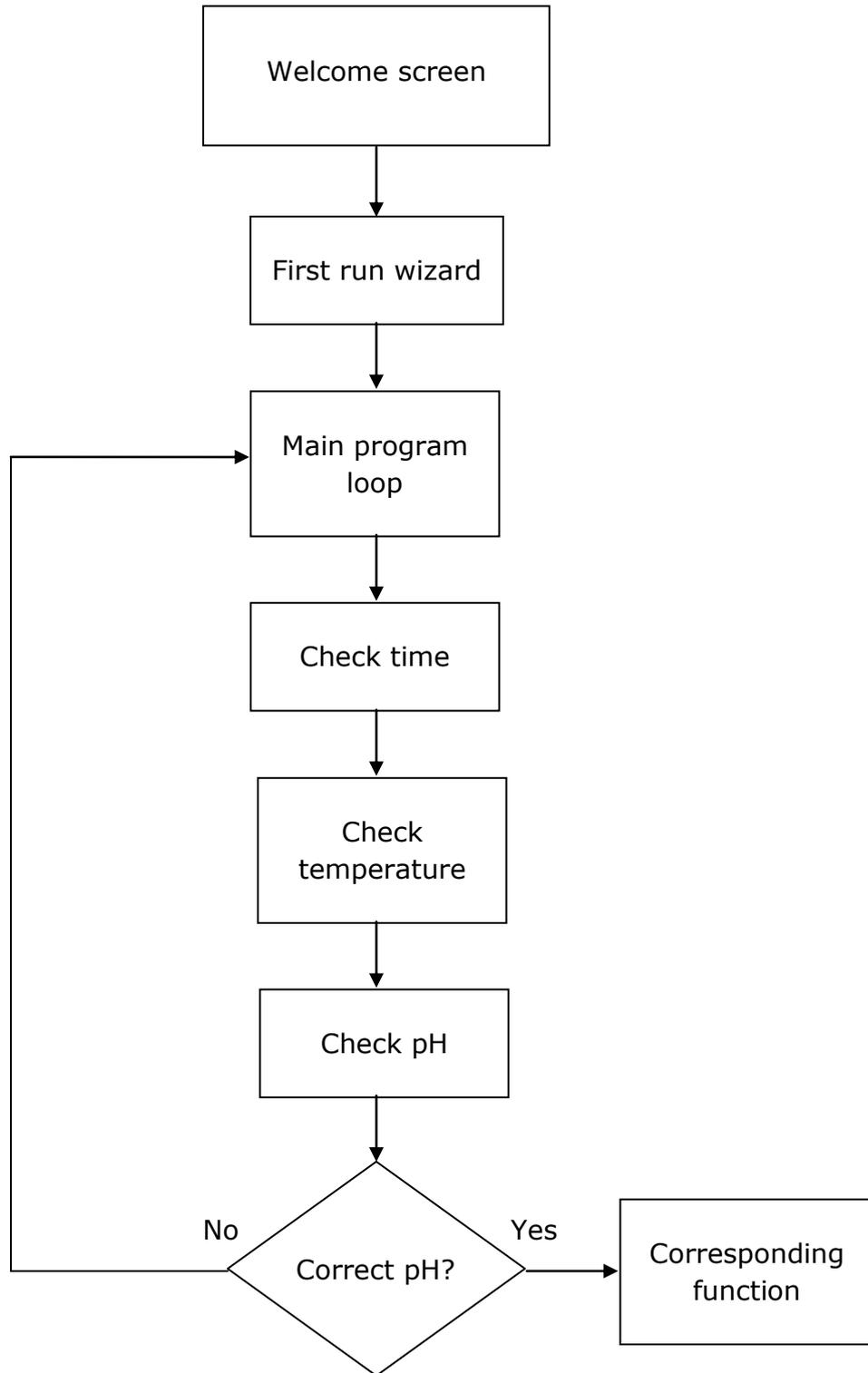


Figure 47 Main program loop flowchart

Right now we are able to know the pH, temperature and time. So the next step is to identify if is necessary to correct the pH. To do so we have to add some conditional to check if current pH is between the desire value and if is time to correct it.

```
// Condition based on pH level lower than 7 and specific time, Sunday 12 pm
if((dow==7) && (hours==12) && (currentpH<=7))
{
    [...]
    // Condition based on pH level higher than 8 and specific time, Sunday 12 pm
else if((dow==7) && (hours==12) && (currentpH>=8))
{    [...]
```

Table 25 Main conditionals to trigger the system

5.2. RTC and i2c communication

The function called "getTime" set the i2c communication between the RTC to obtain the value:

- DoW (day of the week), from 1(Monday) to 7(Sunday)
- hours (24h), from 00 to 23
- minutes, from 00 to 59
- seconds, from 00 to 59

First of all we have to define de i2c register explained in chapter 3.2.3:

```
// i2c Registers
#define SSPBUF   (unsigned char*)*0xFC9
#define SSPADD   (unsigned char*)*0xFC8
#define SSPSTAT  (unsigned char*)*0xFC7
#define SSPCON1  (unsigned char*)*0xFC6
#define SSPCON2  (unsigned char*)*0xFC5
```

Table 26 Definition of i2c registers

In this case we are defining that our system will be the Master to read or write in to the slave.

The slave is the RTC and to find it we have to send the correct address bits:

```
// I2C address definition
#define I2C_SLAVE_ADDRESS 0b1101000
```

Table 27 Definition i2c address

Once we have this entire configuration ready, we need to send the some specific bits to obtain the different parameters one by one:

```
switch(timeType) {
    case 0:                                // Case seconds
        timeReg = 0x00;                    // Bits for seconds
        break;
    case 1:                                // Case minutes
        timeReg = 0x01;                    // Bits for minutes
        break;
    [...]
}
```

Table 28 Bits switcher to obtain data from RTC

This switch / case script receive a number from 0 to 3 from another section of the function. Once the number arrives to the switch it change the value of the variable timeReg. When this variable have record this bits, it have to be send it to RTC by the next scrip:

```
// Begin communication
i2c_start ();

// Send slave address (with WRITE bit)
i2c_write ((I2C_SLAVE_ADDRESS<<1)&(0b11111110));

// Request slave internal memory address for analogue data
i2c_write (timeReg);

// Change to READ
// Send repeated start command to begin read cycle
i2c_start();

// Add 1 to the address to send a read bit
i2c_write ((I2C_SLAVE_ADDRESS<<1)|(0b00000001));

// Read analogue information from the slave
retVal = i2c_read(0);

// Terminate communication
i2c_stop ();

// Convert bcd to decimal
retVal = bcdToDec(retVal);
```

Table 29 Write and read from the slave RTC

This scrip sends the slave address plus a bit number to communicate with the RTC and change to write mode. Next step is to send the actual bit that we want to know.

After this it swaps to read mode sending the slave address plus a 1 and we record the receiving information in to the variable retVal.

This data is the number corresponding to what we claim in the write mode, but this number is codified en BCD (Binary code decimal) a class of binary encodings of decimal numbers where each decimal digit is represented by a fixed number of bits.

In order to convert this to decimal number we rend this data to a function to convert it. This process is explained in the chapter 3.3.

```
switch(m){
    case 0:
        seconds=retVal;                //Save the seconds value
        lcd_gotoxy(8,4);
        printf(lcd_putc,"::\b%2i",retVal);    // Refresh the screen time
        break;
    case 1:
        minutes=retVal;                //Save the minutes value
        lcd_gotoxy(5,4);
        printf(lcd_putc,"::\b%2i",retVal);    // Refresh the screen time
        break;
    [...]
}
```

Table 30 *Scrip to record data from RTC and shown on the LCD*

One by one the received data is record from the RTC to the corresponding variable. Also we show on the screen the values, it show the current time and day of the week.

5.3. pH and temperature signal

The functions "getpH" and "getT" are to obtain the ADC value from the sensors, it does a filtrate and average of the data and change the main variable of the program.

The scrip to obtain the temperature and pH are similar, just change the analog port (AN0 or AN1) and the conversion factor (pH is 3,5 and temperature is 100).

The next scrip is to compute the pH. We go to run the signal acquisition 12 times. First of all we set the ADC channel, in this case de AN0. Next is necessary to wait 20 microseconds in order to let the internal capacitor to be charge with the input analog signal.

After this we read the actual value, in this configuration we are able to read values from 0V to 5V and we have 1024 step in between (0-1023). So this configuration has a sensibility of 4.887mV.

```
for (i=0;i<=12;i++)
{
    // It select the analog channel to use
    set_adc_channel(0);

    // We wait to the capacitor to be charged
    delay_us(20);

    // It reads the analog channel
    A=read_adc();

    // It define the Step Size of our system from 0V to 5V using 10 bits
    SS1=((5-0)/(pow(2,10)-1));

    // Conversion factor from milivolts to ph value, factor x3.5
    pHs=(A*SS1*3.5);

    // It fill up the array with 12 pH samples
    PHaverage[i]=pHs;

    A=0;

    delay_ms (1);
}
```

Table 31 Scrip to obtain sample from analog inputs

To obtain the finally value is only necessary to multiply the sensibility, the number of bites from the ADC read and the value factor.

Once the 12 samples array is fill up, we need to filter them and do an average:

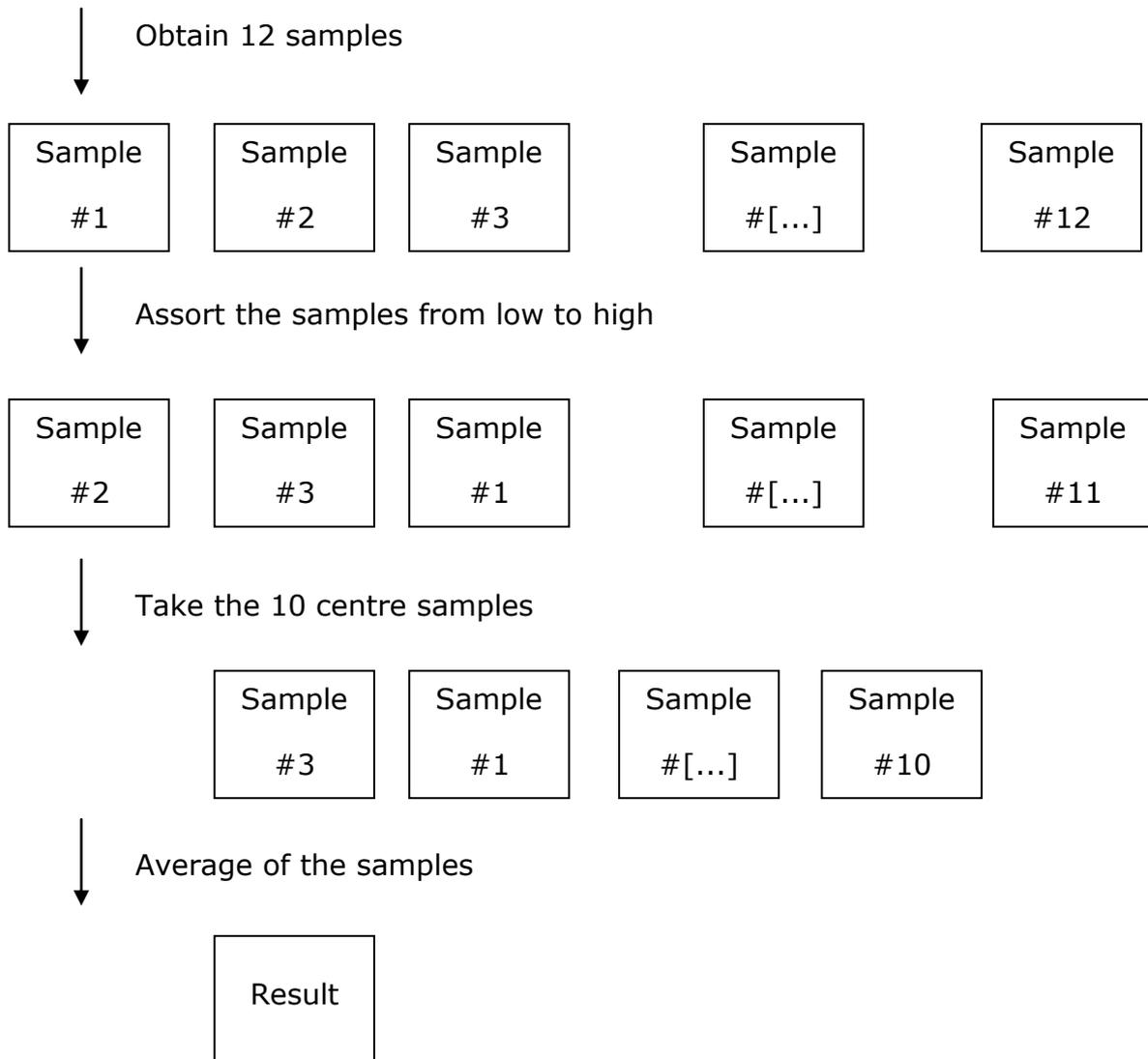


Figure 48 Flowchart to filter the sample from sensor

In this last scrip the 12 sample go for an assort system, from small to large. Then we delete the smaller one and the bigger one in order to just get the better one. In some cases the ADC fail and read a odd value.

The last step is to do an average of the 10 remaining value and record it in the global variable.



Figure 49 Control menu displaying the current time, temperature and pH

5.4. Motors, endstops and multiplexor control

For this part of the program, the system needs to open the press valves, operate the peristaltic pump and the external pool water pump. To know what is going on in this mechanical parts the program gets feedback from the endstops.

Due to the high number of endstops the system use two multiplexors of 8 channels each.

This system start with a conversion of the volume of the liquid that the system need, previous calculation in another function.

```
spins=0;
spins=(qtyliquid/dosexspin);
if (qtyliquid>(dosexspin*spins))
{
spins=spins+1;
}
```

Table 32 Scrip to convert liquid volume to turn for the pump

This scrip just converts the volume of liquid into number of turn of the peristaltic pump of the system. Each turn is equal to 4,5ml of liquid. Is also necessary to add a condition to avoid a drastic differences when the division is not an exact number, for example when the amount of liquid is 8,9ml it will be compute into 1 turn (4,5ml) when 2 turn are more close to the actual value.

After this process the system is ready to operate the valve and the pumps.

The procedure is like follows:

1. Turn on the external water pump
2. Check/Close all valves
3. Open only the desire valve (previously set on the variable "selecliquid")
4. Pump the amount of liquid from the open valve (amount of liquid is preset in to "spins" variable)
5. Check/Close all valves
6. Open the valve of the clean water
7. Pump a preset amount of water to push the liquid to the pool
8. Check/Close all valves
9. Wait some seconds to let the external pump to distribute the chemical into the actual pool
10. Switch off the external water pump.

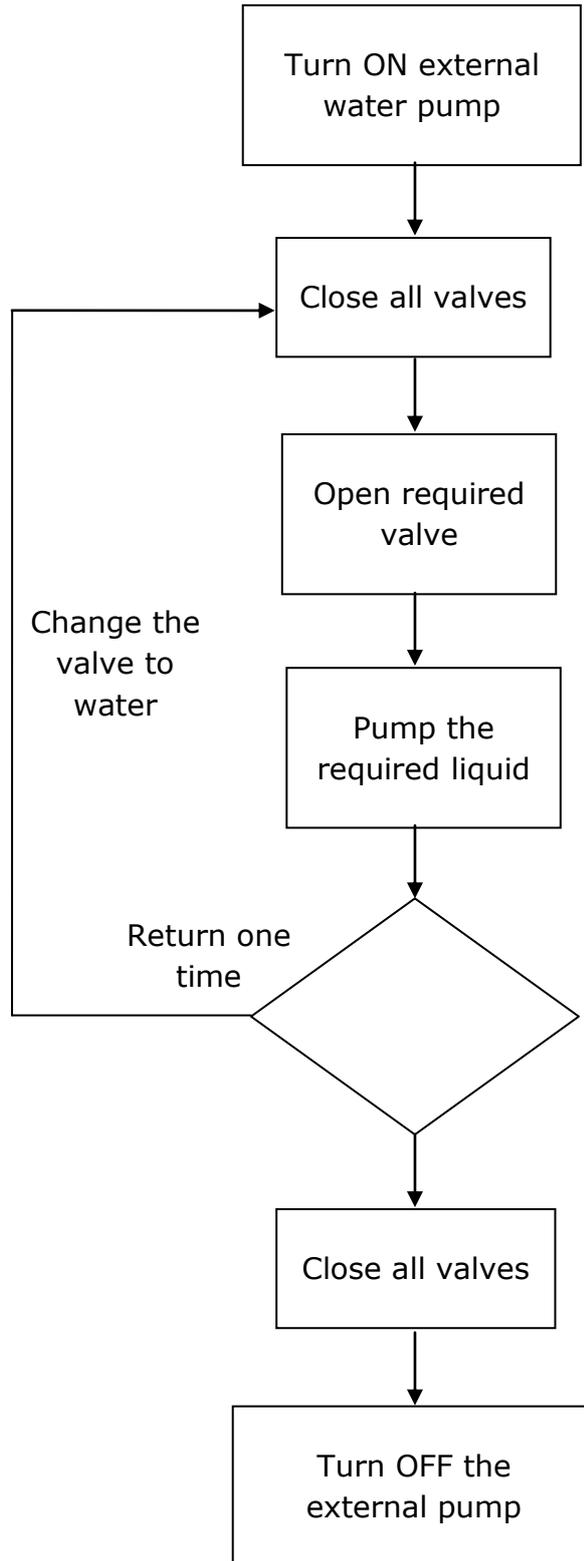


Figure 50 Flowchart to add chemical to the pool

This procedure to close a valve is based on sending 2 bits for the spin direction and 1 bit for enable. Is also necessary 3 bits to set the multiplexors in order to get signal from the endstops. This step is mandatory to know if the valve is fully open or close.

1. Send 3 bits on the outputs PIN_E0,1,2 to set the multiplexors (both use the same bits)
2. Send 1 bits high to enable the corresponding motor valve to move
3. Send 2 bits to the corresponding motor valve to select the spin direction
4. Wait till the multiplexor output PIN_A5 receive a high bits from the corresponding endstop
5. Set the enable and spin direction to low in order to stop the valve for over closing.

case 1:

```
output_low(PIN_E0);           // Multiplexors bit 0
output_low(PIN_E1);           // Multiplexors bit 1
output_high(PIN_E2);          // Multiplexors bit 2
delay_ms(25);
while (input(PIN_A5)==0)      // While endstop is low do:
{
    output_high(PIN_B3);       // Enable motor valve
    output_high(PIN_A2);       // Bit 0 spin direction
    output_low(PIN_A3);        // Bit 1 spin direction
}
output_low(PIN_B3);           // Stop the motor valve
output_low(PIN_A2);
output_low(PIN_A3);
break;
```

Table 33 *Scrip to operate a motor of a press valve*

The scrip to open the valve is pretty much the same. Is only necessary to change the spin direction to the opposite one and instep of reading the output multiplexor PIN_A5 swap to the PIN_A4 to read the other multiplexor. The 3 bits to select the corresponding input of the multiplexor remain the same.

Once we are able to open and close the valve, is necessary to operate the peristaltic pump. The system receive the number of turns with have been pre set in to the variable "spins".

After set up the multiplexor and the spin direction for the motor pump, The system use the endstops to count the spins, 1 spin equal to one dose of 4,5ml.

The rotor moves really slowly, to avoid any counting problem with the endstops. The program only adds 1 to the counter when the endstops is pressed and then released.

```
realspins=0;
  while (realspins<spins)
  {
    if (input(PIN_A4)==1)
    {
      realspins++;
      lcd_gotoxy(8,4);
      printf(lcd_putc, "\b%2i", (spins-realspins));
      while (input(PIN_A4)==1)
      {
        delay_ms(25);
      }
    }
  }
  output_low(PIN_B2);
  output_low(PIN_A2);
  output_low(PIN_A3);
```

Table 34 *Scrip to calculate the number of turn of the pump*



Figure 51 control menu displaying the current operation to correct pH

CHAPTER 6:

SIMULATION

To make sure that all the devices work together and to test the software before trying it in the real system, I draw a circuit with all the electrical and mechanical devices to test everything. The system has been made in Proteus 7.8 Labcenter Electronics ISIS.

6.1. Circuit simulation

Most of the electronic devices was in the library of the software used to run the simulation, but the pH sensor and the relay module wasn't in this library. In order to incorporate them in the circuit to be simulated some modification was needed:

- The pH meter (Ph sensor + amplification driver) are represent with a batteries. Because basically the pH meter is sending a DC voltage to the analog port of the microcontroller and the battery represent that.
- The relay module, which have, and optocoupler is represented with a LED, the real relay in the system works with a 5V signal from the microcontroller and the LED also.
- All the endstop from the peristaltic pump and the press valves are represented with a push buttons. In the real system this endstop are activated by the motors of the pump are valves.
- The system received the power from a 12V battery and from a voltage regulator from 12V to 5V in the real system 2 independent power supplies provide these 2 different voltages.

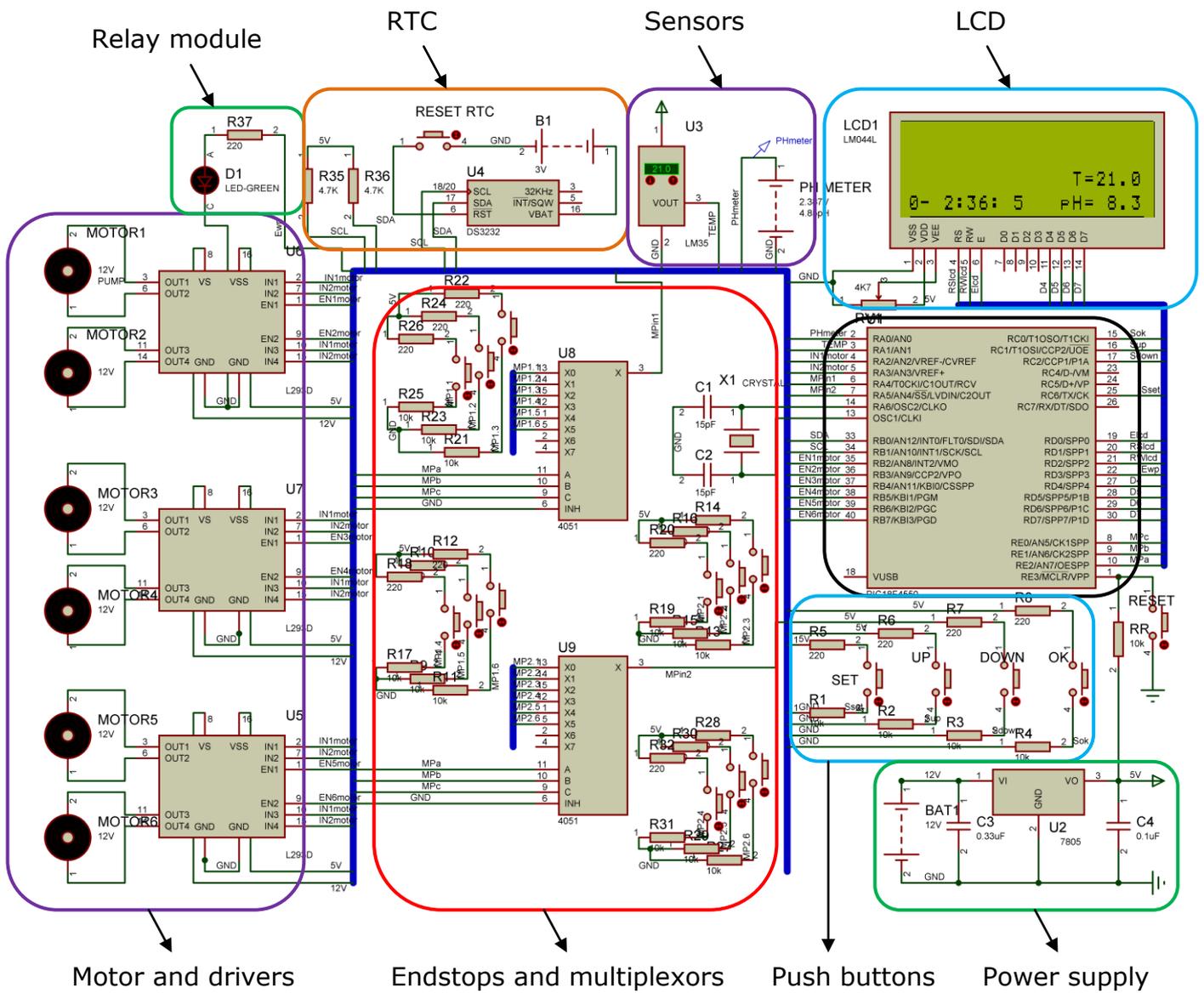


Figure 52 Scheme of all the system for simulation

In this capture of the simulation program all the different devices are represented. For the integrated chips, only the important connexions are visible.

The connexions between the integrated chips, passive components and motor are simplified using a wire bus. This bus represents a group of all the wires. This bus is represented with a wide blue line.

When the simulation is running all the integrated chip works as in the real live, the DC motor have an active picture to show that are spinning the endstops can be activated by clicking on it and the temperature sensor is

showing the temperature displayed on the actual device. Also the LED symbol change from black to green when is activated.

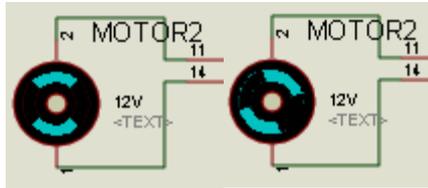


Figure 53 Animation of the motor in the simulation

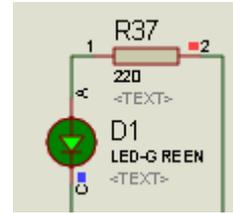


Figure 54 Animation of the LED in the simulation

This simulated was a huge help in order to test the software and the connexions of the devices before soldering on the PCB.

CHAPTER 7: SET UP OF THE HARDWARE

The station is designed to be located outdoors. So the different systems of the station are contained inside a structure to give rigidity to the station, for easy transport, storage and to protect from inclement weather and weather.

The station is contained in two plastic boxes, which keep all the systems inside. The first one contains all the sensing, power and electronic systems required for the functioning of the station.

The second one contains all the mechanical parts, pump and valves. Both boxes are connected through a rigid tube.

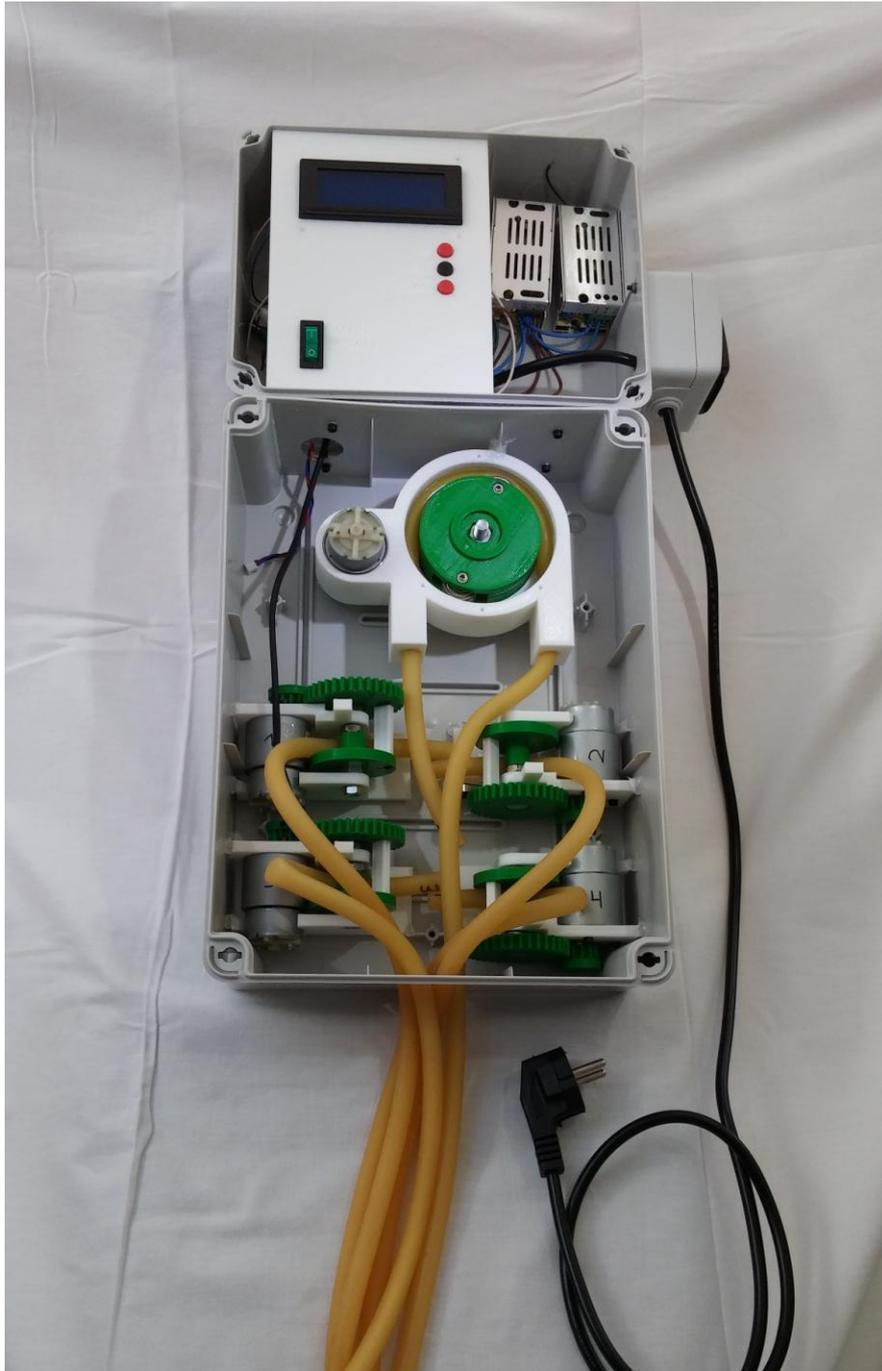


Figure 55 *The complete system*

These plastic boxes protect the systems from humidity, direct sunlight and low temperatures.

7.1. Enclose of the mechanics parts

In order to insulate the mechanical part from the electronics, all the valves and the pump have been place in an independent waterproof box.

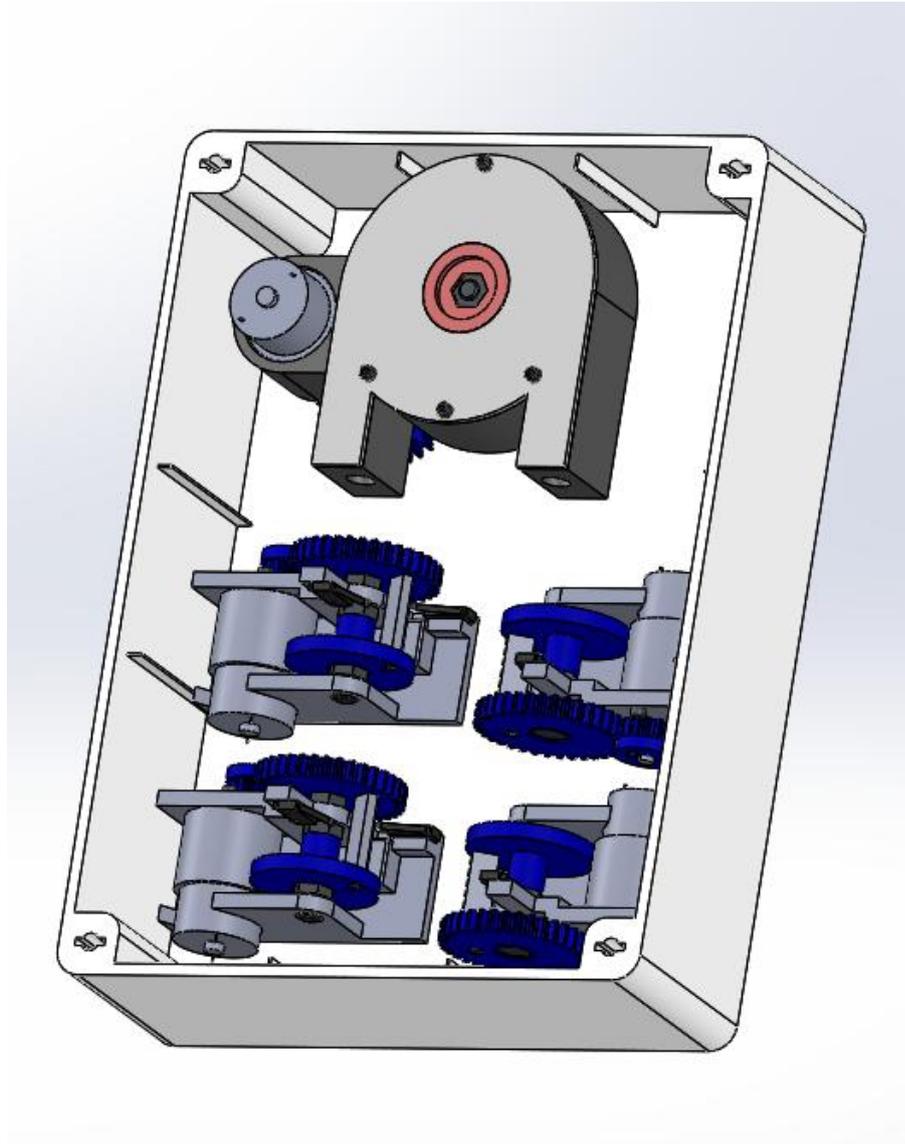


Figure 56 CAD enclosure mechanical parts

The box has the entire connexion for the endstops and the motor with go direct to the top part of the box, and through a hole communicates with the electronics box.

The box is suitable to allocated in it interior, 1 peristaltic pump and 4 valves.

The electronic board is suitable to run up to 7 valves. This extra valve will be placed on top of the other ones.

The flexible tubes go in and out through an opening at the bottom part. To preserve the waterproof seal, no hole have been made in the case.

The case is EX-322 342x253x129 with a IP65 waterproof and dustproof level.

7.2. Enclosure of the electronics

The box of the electronics contains: the main board, power supplies and the relay. Also carry on the outside the socket for the external water pump.

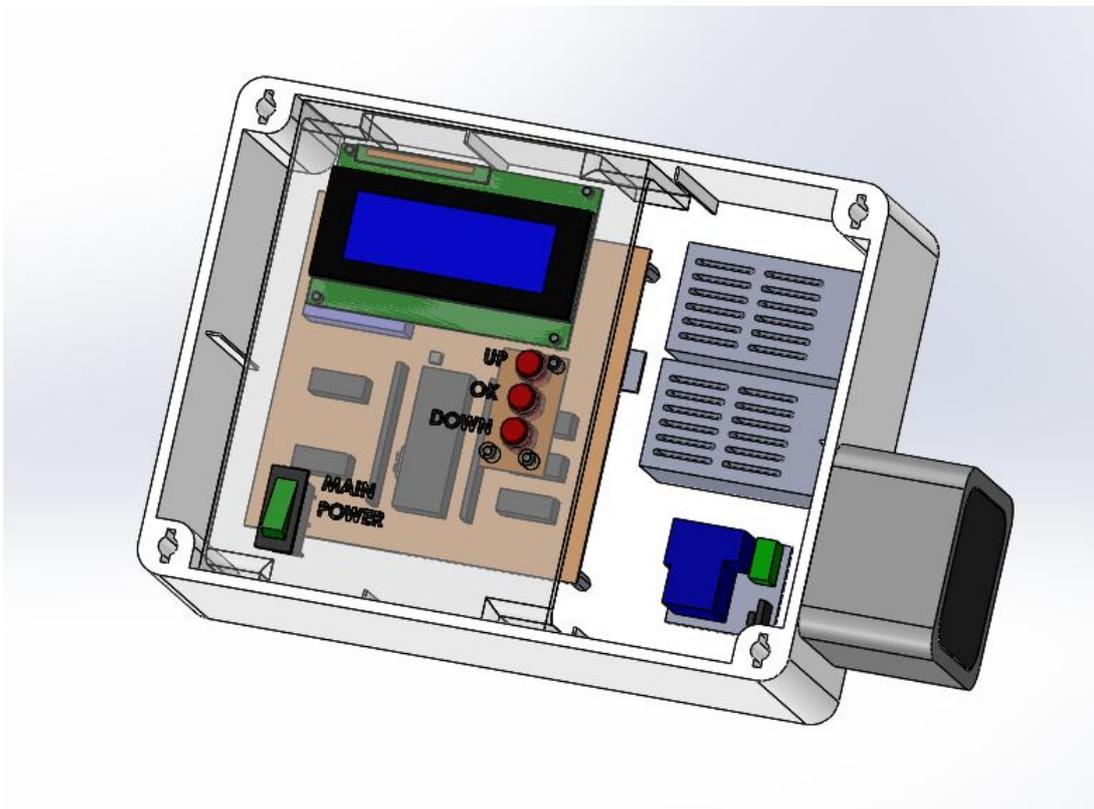


Figure 57 CAD enclosure electronics components

The box contains the 2 power supply for the electronics and the DC motors, the main board and the relay to switch the external water pump.

The relay is next to the wall box, which holds the waterproof socket, allocated outside of the box. Here is where the user must plug his existing water pump for the pool.

The power supply use air to refrigerate itself, when the system is running in automatic mode, it won't be any heavy load so a huge heat is not expected. For that reason there is no ventilation holes.

No moisture can enter in this box because the mechanical, part which carry liquid inside, is in and independents box and no hole have been made in this electronics box.



Figure 58 *the electronics cover*

When the user run for first time the system is necessary to open the box to have access to the control panel. This plastic part holds the screen and the control buttons and covers the main board.

The case is EX-231 255x194x95 with an IP65 waterproof and dustproof level.

7.3. Connexions of the system

The system needs a inter connexion between the different devices. The connexion on the PCB are already been explained in chapter 3.7, it remains detailed the electric connexion outside of the PCB and also the pipes connexion.

7.3.1. Electric circuit

The system has to be plugged in to a 220V/115V AC power in order to start working. This wire goes to the electronic box at the top of the circuit. Once inside the AC tension must jump a master switch with a fuse and then goes to the 12VDC power supply, 5VDC power supply and the output socket for the external water pump (switched by the relay)

Also the electronics box have cable to go to the mechanic box, to power the DC motor of the press valve and the peristaltic pump. Also these devices need an extra cable for their corresponding endstops.

Avery short cable connects the main board to the electronics covert, which hold the push button and the LCD, to provide and received feedback from the user.

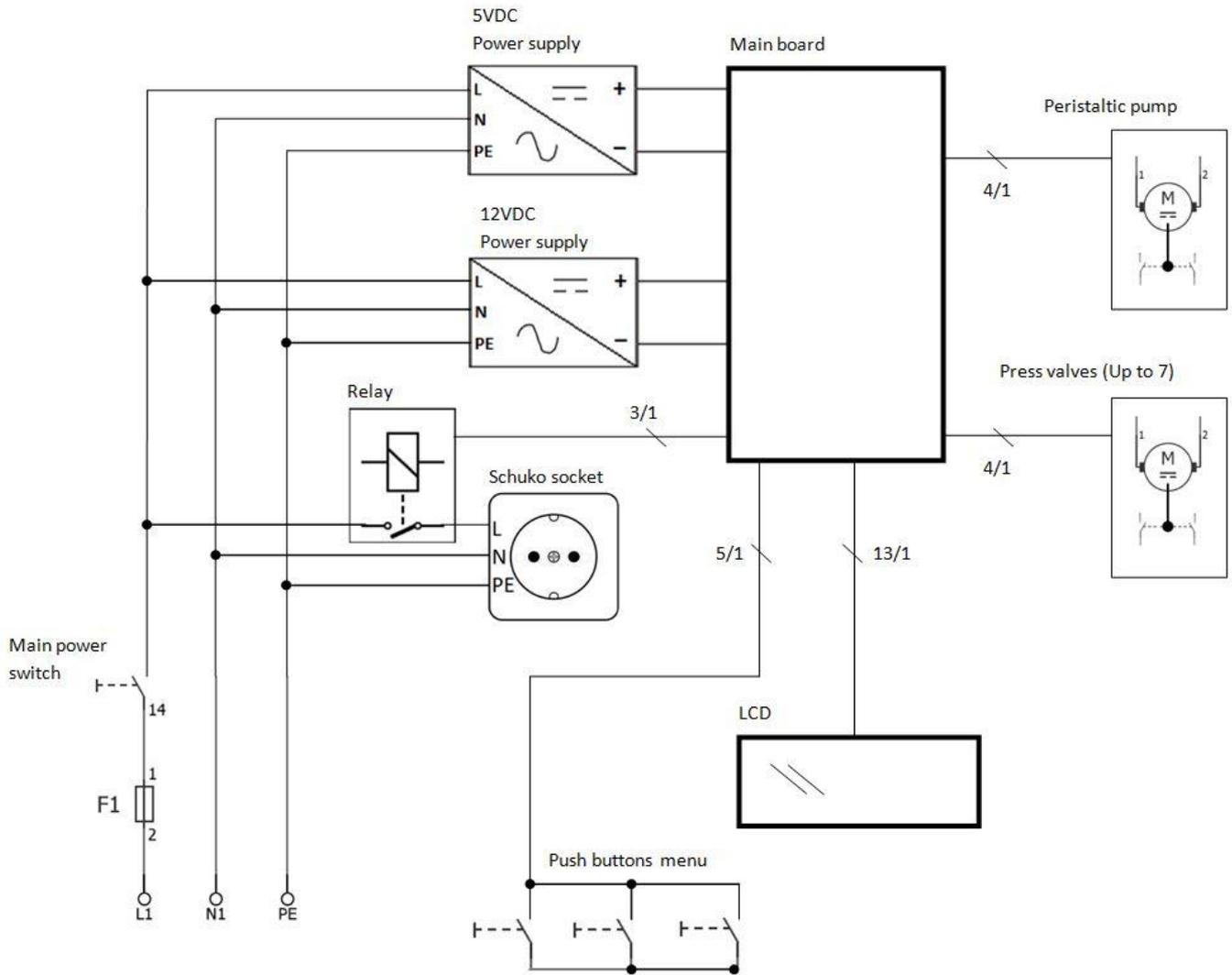


Figure 59 Electric scheme of the system

7.3.2. Pipes connexion

In this particular system is also necessary some pipes to connect the different devices which carry liquids.

Once the desired press valve is opened and the rest are close, the peristaltic pump sucks the liquid from the chemical deposit. Once the chemical has been sucking it, the system pushes it with water to the actual pipe system of the user pool. The microcontroller turn on the external water pump from the users pool in order to spread this chemical

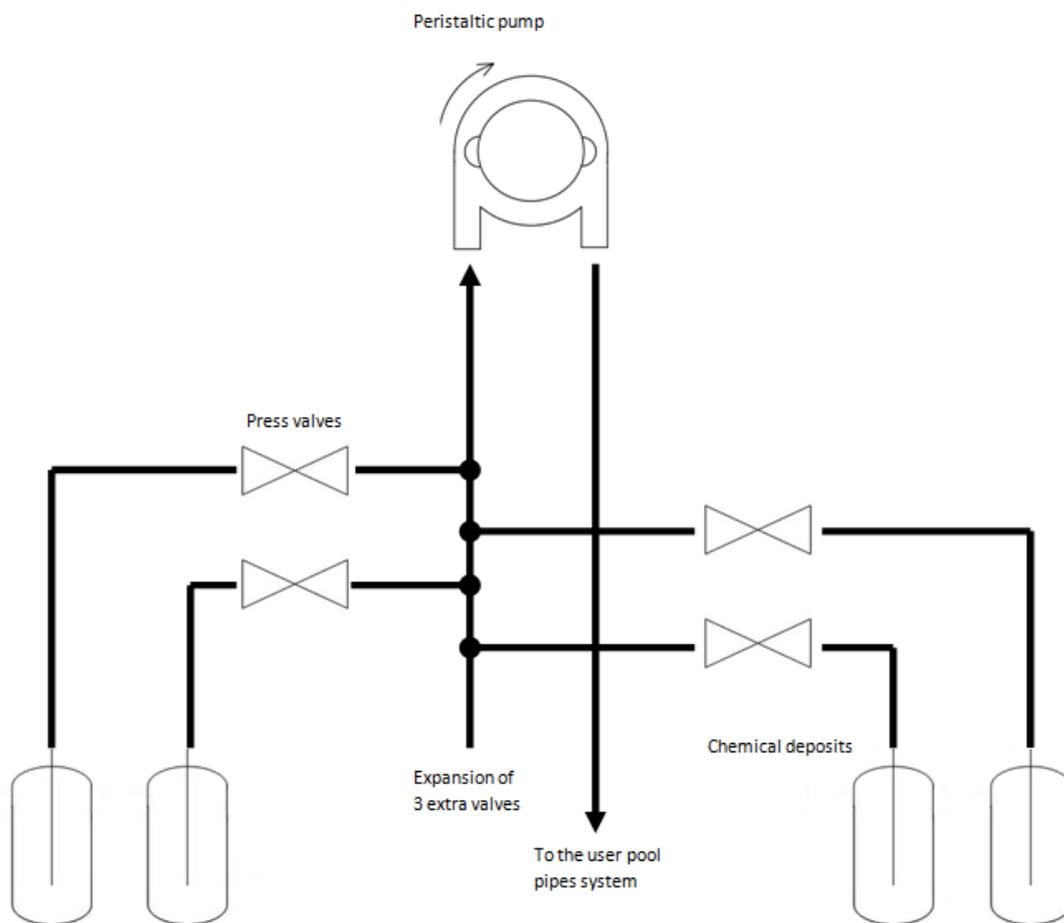


Figure 60 Pipes scheme of the system

All the pipes of the system are made from the flexible tube described in chapter 4.2.

Some T pieces bond together all the pipes in the system; the flexible pipes are hold in place using zip tires.



Figure 61 T connector for the pipes - Source: RS Componentes

The user must not add extra length to the tube with connect the system to the pool. Because if this tube is longer the chemical won't reach the pool will be necessary more water to push the chemical to the pool

CHAPTER 8: NORMATIVES AND LEGISLATION

In this chapter the main normative applied to the system are explained and detailed. Some of this normative need to do some test in some specific laboratories, any of this test have been made but in case of someone want to successfully pass this test, it will be helpfully to follow this recommendations.

- **European directive 2003/95/EC, Directive RoHS** Restriction of use of certain hazardous substances.

In the system no lead or cadmium is found.

- **UNE-EN 123000/A2:1996:** Generic specification: Printed Circuit Boards.

The PCB has been design as the regulation of this normative

- **UNE-EN ISO 12100:2012** Machine safety. General values to evaluate the risks

The risk have been identifies and the press valve and peristaltic pump have risk of trapping a finger of the user. This risk cannot be neutralizes because is the basic function of the device. So this risk must be identified with some signs.

- **UNE-EN ISO 7010:2012** Graphic symbols. Colours and safety signs registered

To aware the user of the risk of finger getting trapped, is necessary to use a sign like the one on figure 61.



Figure 62 Risk of finger get tramped - Source: Aenor.es

- **UNE-EN 60950-1** Equipment of information technology. Security. Part 1: General requirements (IEC 60950-1: 2005 modified)
- **UNE-EN 55022:2010** Equipment of information technology. Radio disturbance characteristics. Limits and methods of measurement.
- **UNE-EN 55024:2010** Equipment of information technology. Immunity characteristics. Limits and methods of measurement.

This 3 last normative focus on the Electromagnetic compatibility CEM, with ensure that the device don't emit radiation to the ambient or the electric system. Also ensure that the interference from the exterior dons cause any malfunction.

In order to successfully pass this test the system maybe requires a ferrite to the cable of the DC motor.



Figure 63 Ferrite for the electromagnetic compatibility - Source: RScomponentes

This ferrite mitigates the electromagnetic interference generated when power is send it to the motor.

Also the PCB board could be a problem, the clock pulse to run the microcontroller may interfere with the test, so is possible to change the design of the lay out around the clock. The crystal oscillator and the 2 capacitors must be isolated from the rest of the track unless a single small point to reduce the electromagnetic waves.

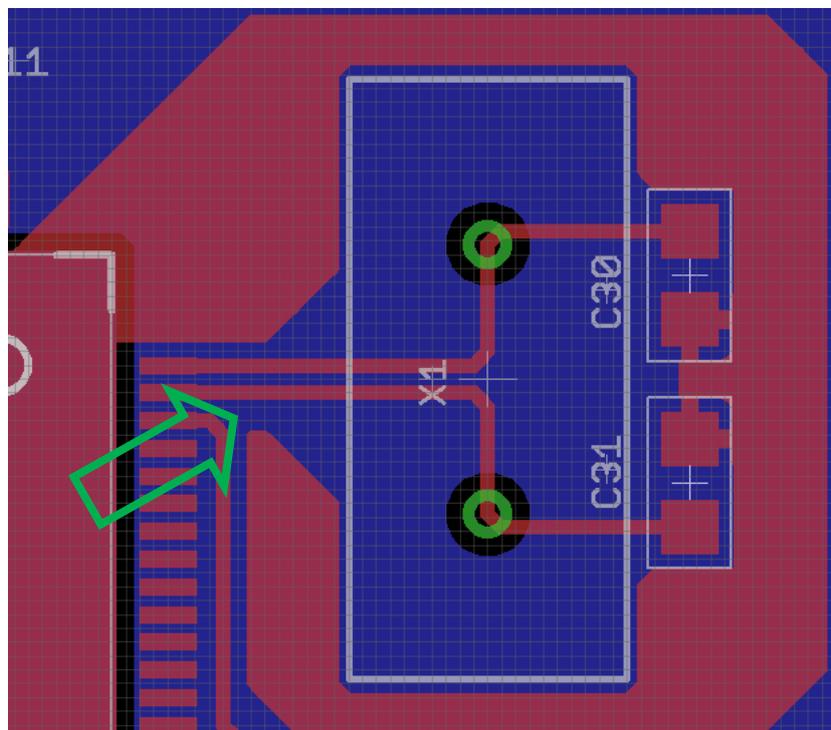


Figure 64 Example of insulation of the crystal oscillator

As is show in the figure 63, the crystal and the capacitor are bounded by a ground track excepted for a small gap (green arrow). The idea is to keep as must as possible interferences trapped inside of this area

Another option is to cover all the cable and boxes with a metal shield, like an aluminium tape.

Another CEM test is the one called induced waves. With basically is to electrocute the system with 4KV in to the metal parts and 8kV in the plastic ones. Due to the plastic insulation of the 2 boxes, any spark will damage the system inside.

- **UNE-EN 60947-3:2009** Low-voltage switchgear. Part 3: Switches, disconnectors, switch-disconnectors and fuse combination.

To operate the system the user can use a switch, which interrupted the main power from the system. Also the system has a fuse that automatic cut the power supplies if any high pick of power happen. This switch and fuse have been designed like these normative stables.

CHAPTER 9: PLANNING OF THE WORK

In this chapter all the major step to make this project are detailed.

The horizontal axis represent days of work up to 120 days with is about 4 months. Every day around 6h was used to work in this project:

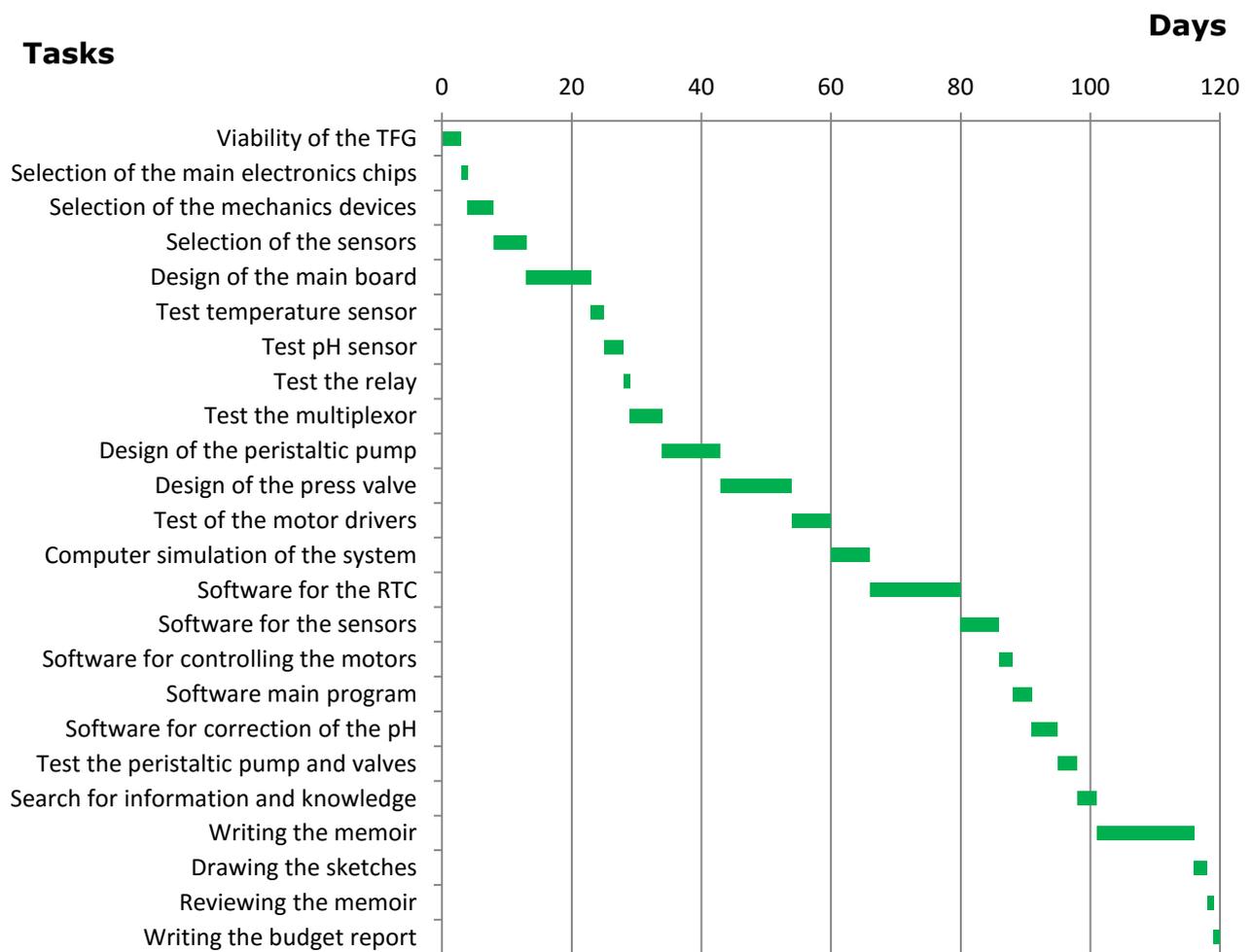


Figure 65 Gantt diagram of this project

CHAPTER 10: CONCLUSIONS

In this final project for my degree, I was able to use most of knowledge that I learn on the University. Also I gained a lot of knowledge of C language and communication.

The i2c communication was the most complex part of the project but is a key factor for this system, because the RTC (Real time clock) is necessary to know the time to run the system and the communication between the microcontroller and this chip is trough i2c port.

The pH sensor is also a basic device, the sensor used in system is not the perfect choice due to it crystal sensor. This sensor is not suitable to stay under water for long periods of time. But it was costly and more complex to set up the correct one.

For this particular project it was necessary to design some devices with moving part and due to my research and my college from other engineering disciplines I was able to successfully design the peristaltic pump and the press valve. This new knowledge will help me to find a good job in the near future.



Figure 66 System fully assembled

The 3D printer that I own it have been a huge help to improve the professionally on the system, making this work perfectly.

In order to improve the performance of the system some upgrades like a chlorine sensor can be added. Also a better human interface system to control the filtration pump could be a good option.



Figure 67 Actual human interface of the system

In conclusion, I believe that this project have given me a professional experience in the field of industrial electronics engineering useful to complete all the knowledge acquired during the degree. I am sure this experience will help me in the future especially to choose the field I want to specialize.

CHAPTER 11:

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ANNEX 1 SOURCE CODE

12.1. Main program, firm v9.4

```
//MAIN PROGRAM //////////////////////////////////////
```

```
#include <Firm v2.h>
```

```
#include <Flex_LCD420_adaptat.c>
```

```
#include <math.h>
```

```
#include <Variables.h>
```

```
#include <getpH.c>
```

```
#include <getT.c>
```

```
#include <getTime.c>
```

```
#include <pHacid.c>
```

```
#include <pHbasic.c>
```

```
#include <closevalves.c>
```

```
#include <openvalves.c>
```

```
#include <pumping.c>
```

```
#include <pumpLiquid.c>
```

```
void main()
{
    // Set up of the ADC chanel
    setup_adc_ports(AN0_TO_AN1);
    setup_adc(ADC_CLOCK_DIV_16);
    // Inicializate the LCD screen
    lcd_init();

    #include <Ini_ports_variables.h>

    //FIRST RUN WIZARD (Run ones) //////////////////////////////////////

    delay_ms(200);
    lcd_gotoxy(1,1);
        // Intro for the first run wizard
    printf(lcd_putc, "FIRST RUN WIZARD\n\b" );

    lcd_gotoxy(14,4);
    printf(lcd_putc, "v 9.4\n\b" );

    delay_ms(1000);

    printf(lcd_putc, " \f ");

    // FIRST RUN WIZARD -> Water volume
```

```
lcd_gotoxy(1,1);

// Ask to the user the real amount of water
printf(lcd_putc, "Enter water volume\b" );

// While the user don't press the button OK (PIN_C0) the program keep
changing the value
while((input(PIN_C0)==0))
{
// Condition to avoid over flow, range from 0 to 440000
if (watervolume>44000)
{
    watervolume=44000;
}

lcd_gotoxy(1,4);

// Constanly showing the actual water volume
printf(lcd_putc, " \b%lu liters ",watervolume);

// If the user press the button UP (PIN_C1) the system increas 500
liter the water volume
if((input(PIN_C1)==1))
{

    watervolume=watervolume+500;

    delay_ms(250);

}

// If the user press the button DOWN (PIN_C2) the system decreas
500 liter the water volume
else if((input(PIN_C2)==1))
{
```

```
    watervolume=watervolume-500;
    delay_ms(250);
}
}

// FIRST RUN WIZARD -> Chemical concentration

delay_ms(250);
printf(lcd_putc, " \f ");
lcd_gotoxy(1,1);
    // Ask to the user the real amount of chemical concentration
printf(lcd_putc, "Enter chemicals \b" );
    lcd_gotoxy(1,2);
printf(lcd_putc, "concentration \b" );
    // While the user don't press the button OK (PIN_C0) the program
    keep changing the value
while((input(PIN_C0)==0))
{
    // Condition to avoid over flow, range from 0 to 100
    if (chemicalscon>100)
    {
        chemicalscon=100;
    }

    lcd_gotoxy(1,4);
    printf(lcd_putc, " \b%lu %% ",chemicalscon);
    //
    Constanly showing the actual chemical concentration
```

```
// If the user press the button UP (PIN_C1) the system increas 5% the
concentration value
if((input(PIN_C1)==1))
{

    chemicalscon=chemicalscon+5;
    delay_ms(250);

}

// If the user press the button DOWN (PIN_C2) the system decreas
5% the concentration value
else if((input(PIN_C2)==1))
{

    chemicalscon=chemicalscon-5;
    delay_ms(250);

}
}

printf(lcd_putc, " \f ");
lcd_gotoxy(1,1);
// End first run wizard
printf(lcd_putc, "Completed\n\b" );
delay_ms(500);
lcd_gotoxy(4,3);
printf(lcd_putc, "Automatic mode\n\b" );
delay_ms(1000);
```

```
printf(lcd_putc, " \f ");

// MAIN PROGRAM (Infinite loop) //////////////////////////////////////

while(TRUE)
{
    // Call the function to read and show on the screen the current time
    getTime();

    // Call the function to read and show on the screen the current
    temperature
    getT();

    lcd_gotoxy(15,3);

    // The degree symbol "°" is write it by sendind the cade 1101 1111 b
    -> \223 d

    printf(lcd_putc, "T= \b%2.1f\223 ",currentT);

    // Call the function to read and show on the screen the current pH
    getpH();

    lcd_gotoxy(14,4);

    printf(lcd_putc, "pH= \b%2.1f",currentpH);

// Condition based on pH level lower than 7 and specific time, Sunday 12
pm    if((dow==7)&&(hours==12)&&(currentpH<=7))
{
    printf(lcd_putc, " \f ");

    lcd_gotoxy(1,1);

    printf(lcd_putc, "Current pH acid\b");

    // Call the fuction to calculate the amount of chemical needed to
    correct the sistem

    pHacid();
```

```
        lcd_gotoxy(1,2);
        printf(lcd_putc,"add \b%3.3f mL NaOH",lNaOH);
// Set the quantiti of liquid  to be pumped
        qtyliquid=9;
        // Change the variable to select the valve with the liquid base
        selecliquid=2;
// Call the fuction to pump the liquid
        pumpLiquid();

        printf(lcd_putc, " \f ");
    }
// Condition based on pH level higher than 8 and specific time, Sunday
12 pm
else if((dow==7)&&(hours==12)&&(currentpH>=8))
{

        printf(lcd_putc, " \f ");
        lcd_gotoxy(1,1);
        printf(lcd_putc, "Current pH basic\b");
        // Call the function to calculate the amount of chemical needed to
correct the system
        pHbasic();

        lcd_gotoxy(1,2);
        printf(lcd_putc,"add \b%3.3f mL HCl",lHCl);
        // Set the quantiti of liquid  to be pumped
        qtyliquid=lHCl;
```

```
        // Change the variable to select the valve with the liquid base
        selecliquid=1;

        // Call the function to pump the liquid
        pumpLiquid();

        printf(lcd_putc, " \f ");
    }
}
}
```

12.2. ini_ports_variables

```
// Inicialization of the ports / Set default parameters
```

```
set_tris_A(0b110011);
set_tris_B(0b000000);
set_tris_C(0b11110111);
set_tris_E(0b0000);

output_low(PIN_A2);
output_low(PIN_A3);

output_low(PIN_B2);
output_low(PIN_B3);
output_low(PIN_B4);
output_low(PIN_B5);
```

```
output_low(PIN_B6);
```

```
output_low(PIN_B7);
```

```
output_low(PIN_E0);
```

```
output_low(PIN_E1);
```

```
output_low(PIN_E2);
```

```
i=0;
```

```
j=0;
```

```
k=0;
```

```
l=0;
```

```
M1=0;
```

```
M2=0;
```

```
SG=0;
```

```
currentpH =0;
```

```
    // Default water volume, common value 11.000 liters
```

```
watervolume=11000;
```

```
    // Default chemical concentration, common value 40%
```

```
chemicalscon=40;
```

```
    // Every spin of the water pump it will absord 4,5ml
```

```
dosexspin=4.5;
```

```
defspins=10;
```

```
    // Number of spins lo push the chemical dose to the pool
```

```
numvalves=4;
```

```
// Definition of all variables of the program
```

```
int8
i,j,k,l,m,n,o,M1,M2,SG,seconds,minutes,hours,dow,spins,realspins,numvalv
es,selecliquid;

int16 A,B,watervolume,chemicalscon;

float32 qtyliquid,dosexspin,defspins;

float32 sum,temp,SS1,SS2;

float32 pHs,currentpH;

float32 pOH,molOH,pOHO,molOHO,difmol1,molNaOH,gNaOH,INaOH;

float32 molH,molHO,difmol2,molHCl,gHCl,IHCl;

float32 Ts,currentT;

float32 PHaverage[12],Taverage[12];
```

12.3. Function, getpH

//Function to obtain the ADC value of pH from the sensor, it does a filtrate and average of the data and change the main variable of the program

```
void getpH()
{

    for (i=0;i<=12;i++)
    {
        // It select the analog channel to use
        set_adc_channel(0);

        // We wait to the capacitor to charge
        delay_us(20);

        // It reads the analog channel
        A=read_adc();
```

```
// It define the Step Size of our sistem from 0V to 5V using 10 bits
SS1=((5-0)/(pow(2,10)-1));
// Conversion factor from milivolts to ph value, factor x3.5
pHs=(A*SS1*3.5);
// It fill up the array with 12 pH samples
PHaverage[i]=pHs;

A=0;

delay_ms (1);
}

// Sort the samples from small to large
for(i=0;i<=12;i++)
{
for(int j=i+1;j<12;j++)
{
if(PHaverage[i]>PHaverage[j])
{
temp=PHaverage[i];
PHaverage[i]=PHaverage[j];
PHaverage[j]=temp;
}
}
}

// Take the average value of 10 centre sample
for (i=1;i<11;i++)
{
sum=PHaverage[i]+sum;
```

```
}  
  
currentpH=sum/10;  
  
sum=0;  
temp=0;  
  
}
```

12.4. Function, getT

//Function to obtain the ADC value of temperature from the sensor, it does a filtrate and average of the data and change the main variable of the program

```
void getT()  
{  
  
    for (i=0;i<=12;i++)  
    {  
        // It select the analog channel to use  
        set_adc_channel(1);  
        // We wait to the capacitor to charge  
        delay_us(20);  
        // It reads the analog channel  
        B=read_adc();  
        // It define the Step Size of our sistem from 0V to 5V using 10 bits
```

```
SS2=((5-0)/(pow(2,10)-1));
    // Conversion factor from milivolts to ph value, factor x100
Ts=(B*SS2*100);
    // It fill up the array with 12 pH samples
Taverage[i]=Ts;

B=0;

}

    // Sort the samples from small to large
for(i=0;i<=12;i++)
{
    for(int j=i+1;j<12;j++)
    {
        if(Taverage[i]>Taverage[j])
        {
            temp=Taverage[i];
            Taverage[i]=Taverage[j];
            Taverage[j]=temp;
        }
    }
}

    // Take the average value of 10 centre sample
for (i=1;i<11;i++)
{
    sum=Taverage[i]+sum;
}
}
```

```
currentT=sum/10;

sum=0;
temp=0;
}
```

12.5. Function, getTime

//Function which set the i2c communication between the RTC to obtain the value of dow (day of the week), hours, minuts and second

```
int8 bcdToDec(int8 val);
int8 decToBcd(int8 val);
int8 readRTCValue(int8 timeType);

void getTime()
{
    int8 retVal = 0;
        // Request the data for the 4 parameters
    for(m=0;m<=3;m++)
    {
        // For every colectet parameter save it temporary in this variable
        retVal = readRTCValue(m);

        switch(m)
        {
            case 0:
                // Save the secoinds from the RTC and show it on the screen
```

```
seconds=retVal;  
lcd_gotoxy(8,4);  
printf(lcd_putc, "::\b%2i ",retVal);  
break;
```

case 1:

```
// Save the minutes from the RTC and show it on the screen
```

```
minutes=retVal;  
lcd_gotoxy(5,4);  
printf(lcd_putc, "::\b%2i",retVal);  
break;
```

case 2:

```
// Save the hours from the RTC and show it on the screen
```

```
hours=retVal;  
lcd_gotoxy(2,4);  
printf(lcd_putc, "--\b%2i",retVal);  
break;
```

case 3:

```
// Save the dow from the RTC and show it on the screen
```

```
dow=retVal;  
lcd_gotoxy(1,4);  
printf(lcd_putc, " \b%1i",retVal);  
break;
```

default:

```
        break;
    }
}
m=0;
n=0;
}

int8 readRTCValue(int8 timeType)
{
    int8 retVal = 0;
    int8 timeReg = 0;

    // Time type selection
    switch(timeType)
    {
        case 0:
            timeReg = 0x00;                // Bits for reading the seconds
            break;

        case 1:
            timeReg = 0x01;                // Bits for reading the minutes
            break;

        case 2:
            timeReg = 0x02;                // Bits for reading the hours
            break;

        case 3:
```

```
        timeReg = 0x03;                                // Bits for reading the dow
        break;

    default:
        return 0;
        break;
}

i2c_start ();                                        // Begin communication
    // Send slave address (with WRITE bit)
i2c_write ((I2C_SLAVE_ADDRESS<<1)&(0b11111110));
    // Request slave internal memory address for analogue data
i2c_write (timeReg);
    // Send repeated start command to begin read cycle
i2c_start();
    // Add 1 to the address to send a read bit
i2c_write ((I2C_SLAVE_ADDRESS<<1)|(0b00000001));
    // Read analogue information from the slave
retVal = i2c_read(0);
    // Terminate communication
i2c_stop ();
    // Convert bcd to decimal
retVal = bcdToDec(retVal);

return retVal;
}

// Function to convert from bcd to decimal
int8 bcdToDec(int8 val)
```

```
{  
    return ( (val/16*10) + (val%16) );  
}
```

```
int8 decToBcd(int8 val)
```

```
    // Function to convert from decimal to bcd
```

```
{  
    return ( (val/10*16) + (val%10) );  
}
```

12.6. Function, pHacid

//Function to calculate the amount of base to add to the sistem based in the water volume, current pH, temperature and chemical concentration explained in annex chapter 14.1

```
void pHacid()
```

```
{
```

```
    pOH=(14-7.4);
```

```
    molOH=(pow(10,-pOH));
```

```
    pOHO=(14-currentpH);
```

```
    molOHO=(pow(10,-pOHO));
```

```
    difmol1=(molOH-molOHO);
```

```
molNaOH=(difmol1*watervolume);  
  
gNaOH=(molNaOH*40);  
  
lNaOH=((gNaOH*100)/chemicalscon);  
  
}
```

12.7. Function, pHbasic

//Function to calculate the amount of acid to add to the sistem based in the water volume, current pH, temperature and chemical concentration, explained in annex chapter 14.2

```
void pHbasic()  
{  
  
molH=(pow(10,-currentpH));  
  
molHO=(pow(10,-7.4));  
  
difmol2=(molH-molHO);  
  
molHCl=(difmol2*watervolume);  
  
gHCl=(molHCl*36.46);
```

```
IHCl=((gHCl*100)/chemicalscon);
```

```
}
```

12.8. Function, pumpLiquid

```
// Main function to pump liquids into the pool. The system pump the desired  
liquid and the water to push it into the pool
```

```
void pumpLiquid()
```

```
{
```

```
    spins=0;
```

```
        // Convert the volum of liquid into turns of the pump
```

```
    spins=(qtyliquid/dosexspin);
```

```
        // Condition to do a extra turn if the value is close to another turn
```

```
    if (qtyliquid>(dosexspin*spins))
```

```
    {
```

```
        spins=spins+1;
```

```
    }
```

```
        // Turn ON the external pool water pump
```

```
    output_high(PIN_D3);
```

```
        // 1 - Make sure all the valves are close
```

```
    closevalves();
```

```
// 2 - Open only the desired valves, know from the variable
(selecliquid)

openvalves();

// 3 - Pump the desired amount of liquid from the opened valve,
variable(spins)

pumping();

// 4 - Close all the valves

closevalves();

// Amount of water to push the chemical to the pool
spins=defspins;

// Select the water to push the liquid to the pool
selecliquid=4;

// 5 - Open the water valve

openvalves();

// 6 - Pump water to push the previos liquid to the pool

pumping();

// 7- Close all valves

closevalves();
```

```
    delay_ms(5000);  
    // Turn OFF the external pool water pump  
    output_low(PIN_D3);  
  
}
```

12.9. Function, closevalves

// Function to check and close all valve based on the signal from the endstops through the multiplexors

```
void closevalves()  
{  
  
    lcd_gotoxy(1,4);  
    printf(lcd_putc, "Closing all valves \b" );  
  
    o=1;  
    // Check that all the valves are close  
    while (o<(numvalves+1))  
    {  
        switch(o)  
        {  
            case 1:  
                output_low(PIN_E0);           // Multiplexors bit 0  
                output_low(PIN_E1);           // Multiplexors bit 1  
                output_high(PIN_E2);          // Multiplexors bit 2
```

```
delay_ms(25);
    // While endstop is not activated do:
while (input(PIN_A5)==0)
{
    // Enable motor valve to rotate
output_high(PIN_B3);

output_high(PIN_A2);           // Bit 0 spin direction
    // Bit 1 spin direction, the valve is being closed
output_low(PIN_A3);
}

output_low(PIN_B3);           // Stop the motor valve

output_low(PIN_A2);
output_low(PIN_A3);

break;

case 2:
output_low(PIN_E0);
output_high(PIN_E1);
output_low(PIN_E2);
delay_ms(25);

while (input(PIN_A5)==0)
{
output_high(PIN_B4);
```

```
    output_high(PIN_A2);  
    output_low(PIN_A3);  
}
```

```
output_low(PIN_B4);
```

```
output_low(PIN_A2);  
output_low(PIN_A3);  
break;
```

```
case 3:
```

```
    output_low(PIN_E0);  
    output_high(PIN_E1);  
    output_high(PIN_E2);  
    delay_ms(25);
```

```
while (input(PIN_A5)==0)
```

```
{  
    output_high(PIN_B5);  
  
    output_high(PIN_A2);  
    output_low(PIN_A3);  
}
```

```
output_low(PIN_B5);
```

```
output_low(PIN_A2);
```

```
output_low(PIN_A3);  
break;
```

case 4:

```
output_high(PIN_E0);  
output_low(PIN_E1);  
output_low(PIN_E2);  
delay_ms(25);
```

```
while (input(PIN_A5)==0)  
{  
    output_high(PIN_B6);  
  
    output_high(PIN_A2);  
    output_low(PIN_A3);  
}
```

```
output_low(PIN_B6);
```

```
output_low(PIN_A2);  
output_low(PIN_A3);  
break;
```

case 5:

```
output_high(PIN_E0);  
output_low(PIN_E1);  
output_high(PIN_E2);  
delay_ms(25);
```

```
while (input(PIN_A5)==0)
{
    output_high(PIN_B7);

    output_high(PIN_A2);
    output_low(PIN_A3);
}

output_low(PIN_B7);

output_low(PIN_A2);
output_low(PIN_A3);
break;

default:

    break;
}
o++;
}
}
```

12.10. Function, openvalves

// Function to open the desired valve to obtain liquid from the deposit. Open the valve based on the signal from the endstop through the multiplexor

```
void openvalves()
{

lcd_gotoxy(1,4);

    printf(lcd_putc, "Opening valve \b%2i    ",selecliquid);
    // Open only the corresponding valve
switch(selecliquid)
{
case 1:

    output_low(PIN_E0);                // Multiplexors bit 0
    output_low(PIN_E1);                // Multiplexors bit 1
    output_high(PIN_E2);               // Multiplexors bit 2
    delay_ms(25);

        // While endstop is not activated do:
while (input(PIN_A4)==0)
{

        // Enable motor valve to rotate
    output_high(PIN_B3);



    output_low(PIN_A2);                // Bit 0 spin direction
        // Bit 1 spin direction, the valve is being opened
    output_high(PIN_A3);
}

    output_low(PIN_B3);                // Stop the motor valve

    output_low(PIN_A2);
    output_low(PIN_A3);
```

```
break;
```

```
case 2:
```

```
output_low(PIN_E0);
```

```
output_high(PIN_E1);
```

```
output_low(PIN_E2);
```

```
delay_ms(25);
```

```
while (input(PIN_A4)==0)
```

```
{
```

```
output_high(PIN_B4);
```

```
output_low(PIN_A2);
```

```
output_high(PIN_A3);
```

```
}
```

```
output_low(PIN_B4);
```

```
output_low(PIN_A2);
```

```
output_low(PIN_A3);
```

```
break;
```

```
case 3:
```

```
output_low(PIN_E0);
```

```
output_high(PIN_E1);
```

```
output_high(PIN_E2);
```

```
delay_ms(25);
```

```
while (input(PIN_A4)==0)
{
    output_high(PIN_B5);

    output_low(PIN_A2);
    output_high(PIN_A3);
}
```

```
output_low(PIN_B5);
```

```
output_low(PIN_A2);
output_low(PIN_A3);
break;
```

case 4:

```
output_high(PIN_E0);
output_low(PIN_E1);
output_low(PIN_E2);
delay_ms(25);
```

```
while (input(PIN_A4)==0)
{
    output_high(PIN_B6);

    output_low(PIN_A2);
    output_high(PIN_A3);
}
```

```
output_low(PIN_B6);
```

```
output_low(PIN_A2);
```

```
output_low(PIN_A3);
```

```
break;
```

```
case 5:
```

```
output_high(PIN_E0);
```

```
output_low(PIN_E1);
```

```
output_high(PIN_E2);
```

```
delay_ms(25);
```

```
while (input(PIN_A4)==0)
```

```
{
```

```
output_high(PIN_B7);
```

```
output_low(PIN_A2);
```

```
output_high(PIN_A3);
```

```
}
```

```
output_low(PIN_B7);
```

```
output_low(PIN_A2);
```

```
output_low(PIN_A3);
```

```
break;
```

```
default:
```

```
        break;

    }

}
```

12.11. Function, pumping

// Function to operate the peristaltip pump, based on the variable and the signal from the endstop through the multiplexors

```
void pumping()
{
    lcd_gotoxy(1,4);
    printf(lcd_putc, "Pumping      \b" );

    realspins=0;

    output_low(PIN_E0);           // Multiplexors bit 0
    output_low(PIN_E1);           // Multiplexors bit 1
    output_low(PIN_E2);           // Multiplexors bit 2
    delay_ms(25);

        // Enable motor pump to rotate
    output_high(PIN_B2);

        // Bit 0 spin direction
    output_low(PIN_A2);

        // Bit 1 spin direction, the valve is rotating
```

```
output_high(PIN_A3);

    // Check the number of rotations
while (realspins<spins)
{
    // When the enstops is preset but not realease do:
    if (input(PIN_A4)==1)
    {
        // Add 1 rotation to the counter
        realspins++;
        lcd_gotoxy(8,4);
        // Show the remain rotations
        printf(lcd_putc, "\b%2i", (spins-realspins));
        // In ordeter to not reenter in this operation till the enstop is
        // realease,
        while (input(PIN_A4)==1)
        {
            // the program is traped here until the enstop goes low.
            delay_ms(25);
        }
    }
}

output_low(PIN_B2); // Stop the pump
output_low(PIN_A2);
output_low(PIN_A3);
}
```

ANNEX 2 MAINTAINING POOL WATER

13.1. Filter system

The filter system is the main cleaning system in a pool. Without this process the next step of chemical cleaning process wont succeeded.

The filtering system is always based on a water pump and some sort of filter. The different necessities of how clean the user want to have the pool and how much water there are in the pool, determine the kind of filter and the specs of the water pump.

13.1.1. Filter options

- Cartridge filters - Filter choice for most spas, and many smaller above ground pools. The cartridge filter element, an aquatic version of the pleated air filter in a car, traps dirt and particles of 25 - 100 microns in size. The cartridge is removed from the tank and cleaned with high pressure water thoroughly, top to bottom, but too much pressure may damage the cartridge. Each time the cartridge filter element is cleaned, some of its filtering ability is reduced. The cartridge should be replaced every 3 - 5 yrs.

- Diatomaceous filter (DE) - The D.E. filter is the most efficient type of pool filter on the market. It can trap particles down to 3 - 5 microns; well below what the naked eye can see. DE filters need an annual breakdown of the filter is necessary to thoroughly clean D.E. filter grids. This kind of filtering system is expensive and also need some extra maintenance comparing to the other systems.
- Sand filters - The sand in a pool sand filter is specially graded to trap particles in the 20 - 100 micron range. Sand filters are known to be the lowest maintenance of the three types of pool filters. You may only need to open up the tank every 7 years or so. Sand filters are the easiest to operate and maintain.

To use in our system the user can choose any of these 3 different filter systems. Sand and cartridge filter are commonly use in small and medium pools. And the DE filter is more expensive and sophisticates but the unique extra requirement is to have a great pH levels and we can regulate this in Chapter 5.3.

13.2. pH levels

pH is a basic measure of acidity or basicity in the water pool, and it's one of the most important factors in balancing your pool. On a scale of 0 to 14, ideally, the level of pH in the pool should be between 7 and 8, where 7.4 is ideal because this is the pH of human tears. The eyes are the most delicate organs than the water pool can interact which.

A pH that is too high will irritate the swimmer's skin. Conversely, if it's too low, the pool equipment can be damaged.

Low pH levels in a pool can be caused by rainwater and other foreign particles getting into pool and changing the chemical of the water. And a high pH is caused by the effect of chloride or other cleaning chemist.

13.2.1. Measuring pH

The user can use different methods to measure de pH:

- Using litmus papers / pH strips - Both are a piece of paper with contain a series of indicator bars that will all change colour after exposure to a solution. The strength of the acids and bases on each bar change, the colour pattern of the bars can be matched to the examples that come with the kit.
- Using a pH meter - A simple and speedy device to measure the acidity and alkalinity of the water. A pH meter acts as a voltmeter that measures the electrical potential difference between a pH electrode and a reference electrode and displays the result in terms of the pH value of the solution in which they are immersed. Typically the enclosure of this electrode is made of glass.

In our system we going use a pH meter kit with allow us to read the ph measurement and send it to the microcontroller. This pH meter is described in chapter 2.1.2

13.3. Chlorine

Chlorine is the chemical most often used to keep swimming pools and Jacuzzis free of bacteria that can be hazardous to humans.

Chlorine kills bacteria though a fairly simple chemical reaction. The chlorine solution you pour into the water breaks down into many different chemicals, including hypochlorous acid (HOCl) and hypochlorite ion (OCl⁻). Both kill microorganisms and bacteria by attacking the lipids in the cell, walls and destroying the enzymes and structures inside the cell, rendering them oxidized and harmless.

The difference between hypochlorous acid and hypochlorite ion is the speed at which they oxidize. Hypochlorous acid is able to oxidize the organisms in several seconds, while the hypochlorite ion may take up to 30 minutes.

The levels of HOCl and OCl⁻ vary with the pool's pH level. If the pH is too high, not enough HOCl is present and pool cleaning can take much longer than normal.

13.3.1. Chlorine levels

While the bacteria-killing properties of chlorine are very useful, chlorine also has some side effects that can be annoying to humans if we don't control the level.

Chlorine level should always be between 1 and 4 ppm for proper sanitation and to prevent bacteria.

Chlorine has a very distinctive smell that most find unpleasant, and some find overwhelming. There is also the "itch factor" chlorine can cause certain skin types to become itchy and irritated. The hypochlorite ion causes many fabrics to fade quickly when not rinsed off immediately after exiting the pool. This is why your swimsuit looks faded and worn so early in the summer.

Some companies have developed alternatives to chlorine, including other chemicals and ion generators. Some of these are good alternatives, but they don't achieve the cleanliness, oxidation levels or low price that chlorine provides.

13.3.2. Chlorine options

- Basic Chlorinating Tabs - Slow-dissolving chlorinating tablets, found in 200g and 10g sizes, keep your water clear. Most chlorinating tablets have a built-in stabilizer to protect your chlorine from sunlight burn-off. Chlorinating tablets can be used in your floating dispenser, skimmer or automatic chlorinator.
- Complete Chlorinating Tabs - Many varieties of chlorine sanitizers offer a multifunctional approach to pool care. There are a variety of chlorinating tabs available to sanitize your pool and keep it in great shape for swimming, while shocking your pool to remove contaminants. Other varieties kill bacteria and control algae, while softening your water and protect pool equipment.
- Chlorinating Granules - Multifunctional granular chlorine products can help you perform several tasks at once by chlorinating, shocking and killing algae with a single, daily application.
- Liquid Chlorine - Liquid chlorine is similar to the bleach you use in your household, but is two or three times stronger when formulated for pools. Liquid chlorine is easy to apply and an effective sanitizer, but it has a short shelf life compared to other chlorine products.

To use in our system the chlorine must be in liquid format. The user has the option to use pre-dissolved liquid chlorine or dissolve granules o tabs chlorine into water.

13.4. Algaecide

Millions of microscopic plants in the form of algae can grow into your pool by rain, wind and fill water. Leave it unchecked and your water will quickly become unusable due to clogged filters, low water circulation and reduced effectiveness of pool chemicals. Algaecides prevent algae from taking over the pool, and they treat algae growth.

Prevention is the key to an algae-free pool. In the case of an algae outbreak, algaecides can quickly and efficiently eliminate the problem and restore your pool to clear water.

ANNEX 3 pH LEVEL CORRECTION

pH is a basic measure of acidity or basicity in the water pool, and it's one of the most important factors in balancing your pool. On a scale of 0 to 14, ideally, the level of pH in the pool should be between 7 and 8, where 7.4 is ideal because this is the pH of human tears. The eyes are the most delicate organs than the water pool can interact with.

In this annex chapter we go to describe all the steps to calculate the amount of liquid acid or liquid base to properly adjust the pH level to the most suitable for a swimming pool.

Water quality	pH
Poor chlorine disinfection	>7.8
Eye irritation	
Skin irritation	
Most ideal for eye/skin comfort and disinfection	7.8 ~ 7.2
Eye irritation	< 7.2
Skin irritation	
Corrodes pipes	

Table 35 Pool pH level chart

In order to have the water of the pool between 8 and 7 we need to know the current pH level, the amount of water and the concentration of the acid and bases.

The current pH is obtained from chapter 2.1.2 / 5.3 , the amount of water of the pool and the concentration is obtained in the first run wizard of the system.

Pool parameters	Value obtained from	Value range
Current pH and temperature	Sensor microcontroller	and >8 OR <7
Amount of water	First run wizard	10.000L ~ 40.000L
Concentration	First run wizard	40% ~ 100%

Table 36 Needed pool parameter to correct the pH level

What the system have to do is add sodium hydroxide when the current pH is lower than 7. In the other hand the system have to add hydrochloric acid to lower the pH when is higher than 8.

In both scenarios the calculus are different, the software evaluate with is the actual case and if is necessary to correct it. Just in case that the ph is far away from the 7 ~ 8 pH level.

14.1. Acid current pH level

In the case of the water of the pool is acid, the system have to add a liquid base to raise the pH level. The base use is sodium hydroxide dissolved in 40% of warm water.

Initial parameter:

$$pH_0 = 4$$

$$pH_f = 7.4$$

$$V_t = 11.000L$$

T= 18°C

M(NaOH) = 40g/ml (dissolved in 40% concentration)

Converter pH to pOH:

$$pH = -\log[H^+] ; pH + pOH = 14 ; pOH = 14 - pH$$

$$pOH = -\log[OH^-] ; [OH^-] = 10^{-pOH}$$

$$pOH_f = 14 - pH_f ; pOH_f = 14 - 7.4 = 6.6$$

Number of moles necessary to correct pH:

$$[OH^-]_f = 10^{-pOH_f} = 10^{-6.6} = 2.512 \cdot 10^{-7} \frac{\text{molOH}^-}{L}$$

Initial number of moles current pH:

$$[OH^-]_0 = 14 - pH_0 = 14 - 4 = 10 ; [OH^-] = 10^{-pOH_0} = 1 \cdot 10^{-10} \frac{\text{molOH}^-}{L}$$

Amount of OH⁻ moles needed:

$$\Delta[OH] = 2.512 \cdot 10^{-7} - 1 \cdot 10^{-10} = 2.511 \cdot 10^{-7} \frac{\text{molOH}^-}{L}$$

Number of NaOH moles needed:

$$2.511 \cdot 10^{-7} \frac{\text{molOH}^-}{L} \cdot \frac{1\text{molNaOH}}{1\text{molOH}^-} \cdot 11000L = 2.7621 \cdot 10^{-3} \text{mol NaOH}$$

Convert NaOH moles to NaOH grams:

$$2.7621 \cdot 10^{-3} \text{mol NaOH} \cdot \frac{40g}{1\text{molNaOH}} = 0.110480 g NaOH$$

Compensate concentration of NaOH dissolution:

$$0.110480 g NaOH \cdot \frac{1\text{mLNaOH}}{0.4g NaOH} = 0.2762\text{mL NaOH}$$

Equations 12 Group of equations to calculate the pH correction for acid case

14.2. Basic current pH level

In this case of the water of the pool is basic, the system have to add a liquid acid to lower the pH level. The acid use is hydrochloric acid dissolved in 40% of water.

Initial parameter:

$$pH_0 = 10$$

$$pH_f = 7.4$$

$$V_t = 11.000L$$

$$T = 18^\circ C$$

$$M(HCl) = 36.46g/ml \text{ (dissolved in 40\% concentration)}$$

Converter ph:

$$pH = -\log[H^+] ; [H^+] = 10^{-pH}$$

Initial number of moles current pH:

$$pH_0 = 10 ; [H^+]_0 = 10^{-10} = 1 \cdot 10^{-10} \frac{molH^+}{L}$$

Number of moles final pH:

$$pH_f = 7.4 ; [H^+]_f = 10^{-7.4} = 3.98 \cdot 10^{-8} \frac{molH^+}{L}$$

Amount of H^+ moles needed:

$$\Delta[H^+] = 3.98 \cdot 10^{-8} - 1 \cdot 10^{-10} = 3.97 \cdot 10^{-8} \frac{molH^+}{L}$$

Number of HCl moles needed:

$$3.97 \cdot 10^{-8} \frac{\text{molH}^+}{\text{L}} \cdot \frac{1\text{molHCl}}{1\text{molH}^+} \cdot 11000\text{L} = 4.367 \cdot 10^{-4} \text{mol HCl}$$

Convert HCl moles to HCl grams:

$$4.367 \cdot 10^{-4} \text{mol HCl} \cdot \frac{36.46\text{g HCl}}{1\text{molHCl}} = 0.02 \text{g HCl}$$

Compensate concentration of HCl dissolution:

$$0.02 \text{g HCl} \cdot \frac{1\text{HCl}}{0.4\text{g HCl}} = 0.05\text{L HCl}$$

Equations 13 Group of equations to calculate the pH correction for base case

As it can see above the final result is an amount of liquid of an specific chemical and the water pump will absolved this amount of liquid from the chemical tanks and then introduced to the pool by pushing it with water.