



BUZZER Control Program

```
#include <12F675.h>
#fuses INTRC_IO,NOWDT,NOPROTECT,NOMCLR,BROWNOUT

#use delay(clock=4000000)
//#device ADC=10
#use rs232(baud=9600,xmit=PIN_A5,rcv=PIN_A3,parity=N,bits=8)
```

```
int Pi(int x)
{
    int cnt;
    cnt = x;
    while( cnt-- > 0 ){
        output_high(PIN_A5); // PIN 2
        delay_us(300);
        output_low(PIN_A5);
        delay_us(300);
    }
}
```

```
int Po(int x)
{
    int cnt;
    cnt = x;
    while( cnt-- > 0 ){
        output_high(PIN_A5); // PIN 2
        delay_us(900);
        output_low(PIN_A5);
        delay_us(900);
    }
}
```

```
int To(int x)
{
    Pi(70);
    delay_ms(70);
}

int Tu(int x) // Tu
{
    Pi(400);
    delay_ms(70);
}
```

```
int Osaki(int x)
{
    To(0);Tu(0);To(0);To(0);To(0);
    delay_ms(500);
    To(0);Tu(0);To(0);To(0);To(0);
    delay_ms(500);
    Tu(0);To(0);Tu(0);To(0);Tu(0);
    delay_ms(500);
    Tu(0);To(0);Tu(0);To(0);To(0);
    delay_ms(500);
}
```

```
int TuTuTu(intx) // TuTuTu
{
    Tu(0);
    Tu(0);
    Tu(0);
}
```

```
int ToToTo(intx) // ToToTo
{
    To(0);
    To(0);
    To(0);
}
```

```
int SOS(int x) // ToToTo TuTuTu ToToTo
{
    To(0);To(0);To(0);
    Tu(0);Tu(0);Tu(0);
    To(0);To(0);To(0);
    delay_ms(400);
}
```

```
int minu(int x) // minute
{
    while(x>0){
        int count=0;
        while (count<60){
            delay_ms(1000);
            if ( input(PIN_A4) == 0) { // PIN 3
                //ToTuTo(0);
            }
        }
    }
}
```

```
count += 1;
}
x += -1;
}
```

```
int Crescendo(int x) //
{
    int STEP = 100;
    int CNT = 0;

    while(CNT < 30){
        Pi(100);
        delay_ms(STEP);
        Pi(100);
        delay_ms(STEP);
        STEP += -3;
        CNT += 1;
    }
}
```

```
int Decrescendo(int x) //
{
    int STEP = 0;
    while(STEP<100){
        Pi(100);
        delay_ms(STEP);
        Pi(100);
        delay_ms(STEP);
        STEP += 3;
    }
}
```

```
int beeeep(int x)
{
    int COUNT=0;
    while(COUNT<20)
    {
        Pi(100);
        delay_ms(20);
        COUNT += 1;
    }
}
```

```
int Tantata(int x)
{
    int shibu=400;
    int nibu =80;

    Pi(100); // Tan
    delay_ms(shibu);
    Pi(100);
    delay_ms(shibu);
}
```

```
Pi(100); // ta
delay_ms(nibu);
Pi(100);
delay_ms(nibu);

Pi(100); // ta
delay_ms(nibu);
Pi(100);
delay_ms(nibu);
}
```

```
Pi(100); // Taa
delay_ms(shibu);
Pi(100);
delay_ms(shibu);
}
```

```
Pi(100); // Taa
delay_ms(shibu);

delay_ms(shibu); // Nnnnn
delay_ms(shibu); // Nnnnn
delay_ms(shibu); // Nnnnn
}
```

```
Pi(100); // Tan
delay_ms(shibu);
delay_ms(shibu);

Pi(100); // Tan
delay_ms(shibu);
delay_ms(1000+shibu);
}
```

```
void main(void)
{
    float data;
    int cnt;

    setup_adc_ports(AN3_ANALOG); //AN3 = PIN 3
    setup_adc(ADC_CLOCK_INTERNAL); //ADC clock is included OSC

    output_low(PIN_A5);
    delay_ms(1000);

    // Tantata(0);
    Osaki(0);

    Pi(100);
    Po(100);

    cnt = 0;
    minu(1); // 1 min
    while(cnt < 4){
        To(0);delay_ms(1000);
        ++cnt;
    }
    cnt = 0;
    minu(1); // 2 min
    while(cnt < 4){
        To(0);To(0);delay_ms(1000);
        ++cnt;
    }
    minu(1); // 3 min
    cnt = 0;
    while(cnt < 4){
        To(0);To(0);To(0);delay_ms(1000);
        ++cnt;
    }
    minu(1); // 4 min

    while(1)
    {
        Osaki(0);
        delay_ms(700);
        SOS(0);
        SOS(0);
        delay_ms(700);
        Crescendo(0);

        cnt = 5;
        while( cnt-- > 0)
        {
            Pi(100);
            Po(100);
        }
        delay_ms(500);
    }
}
```