Q1:

How to start it ?

A1:

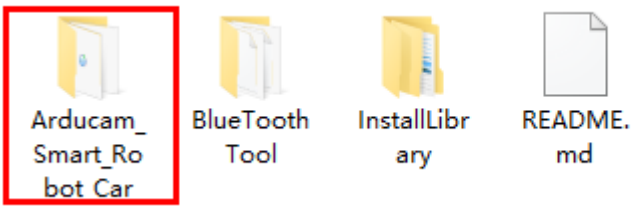
Step1:

Download the Smart-Robot-Car-Arduino package from

https://github.com/UCTRONICS/Smart-Robot-Car-Arduino.git

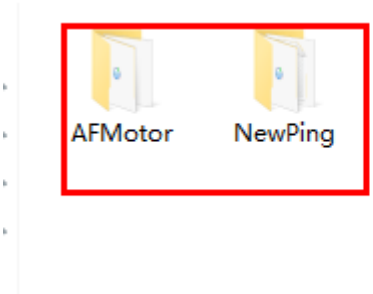
Step2:

Unzip the Smart-Robot-Car-Arduino package and copy the Arducam_Smart_Robot_Car to ..\Arduino\libraries path

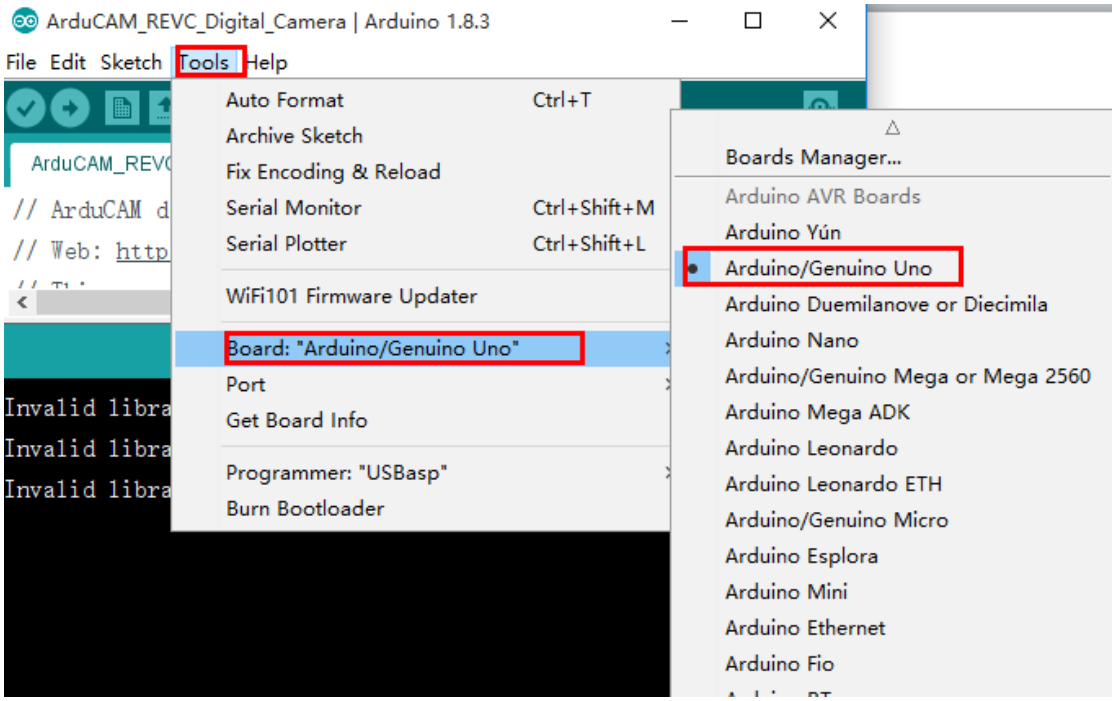


Step3：

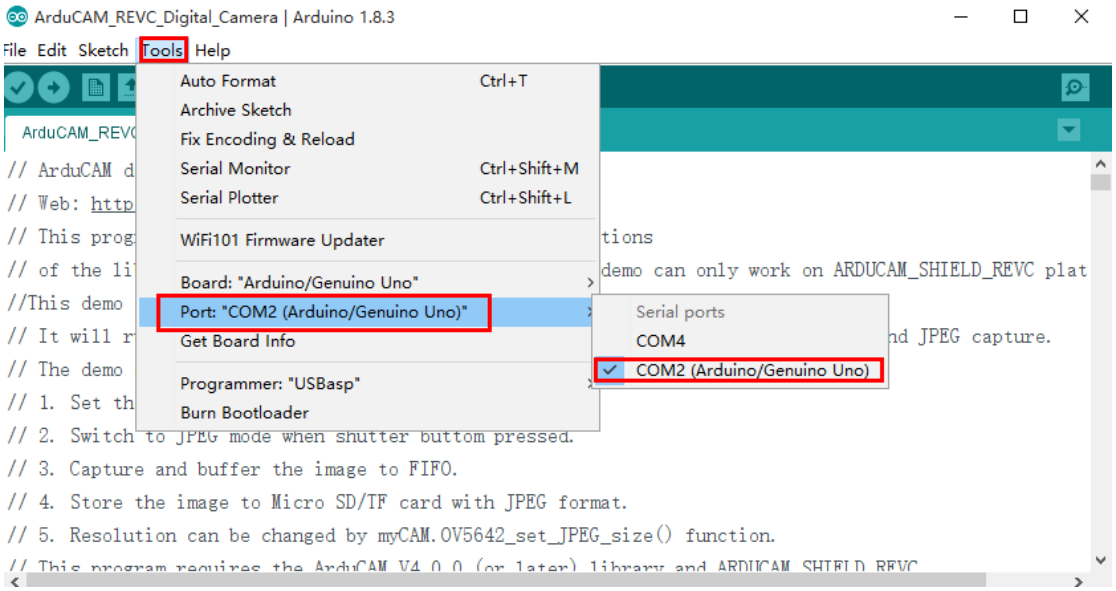
Open the InstallLibrary folder and copy AFMotor and NewPing libraries. to ..\Arduino\libraries path.



Step4: Open your Arduino IDE and choose the Toos ->Board -> Arduino/Genuino UNO board

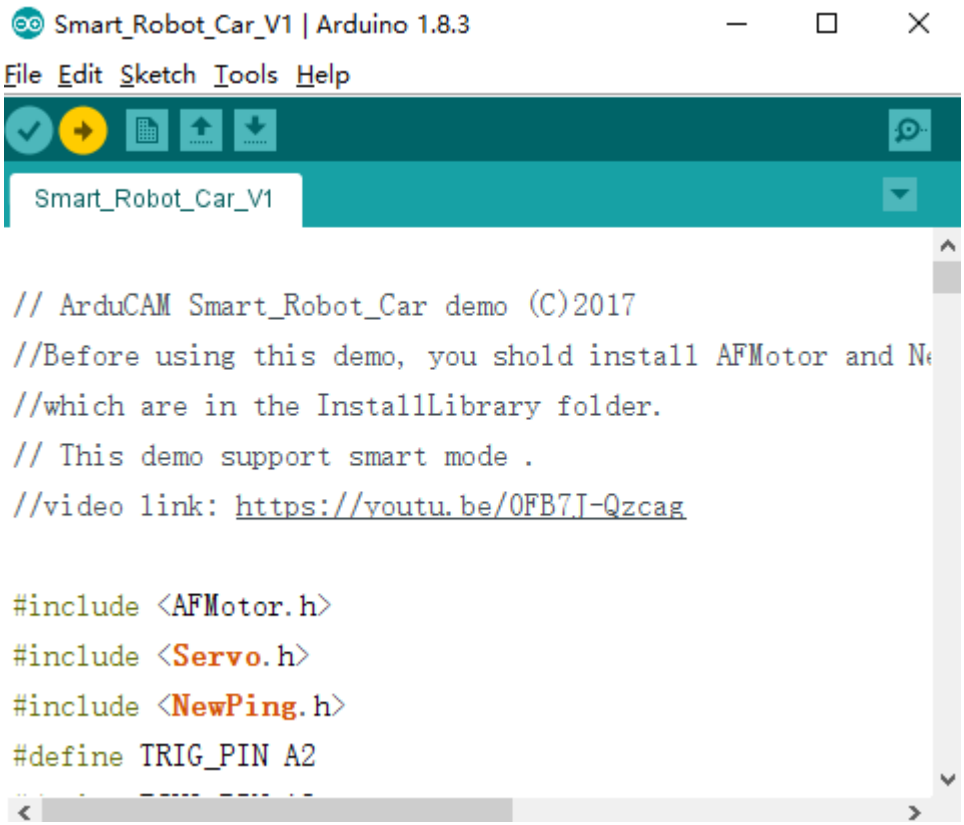


Step5: Choose the right serial poart:



Step6:

Upload the demo to Arduino UNO board:



Q2： When compiling, The following error occurred:

C:\Users\Home\Downloads\Smart-Robot-Car-Arduino-master\Smart-Robot-Car-Arduino-master\Arducam_Smart_Robot_Car\example\Smart_Robot_Car_V1\Smart_Robot_Car_V1.ino:5:22: fatal error: AFMotor.h: No such file or directory

```
 #include <AFMotor.h>
                      ^
compilation terminated.
exit status 1
Error compiling for board Arduino/Genuino Uno.
```

A2:

Before running this demo,you should install AFMotor and NewPing libraries.Just cope them to ..\Arduino\libraries path.

Q3: The Motor can not run?

A3:

Before running the whole project, we advice you test each module firstly.

The ultrasonic test code :

```
#include <NewPing.h>
#define TRIG_PIN A2
```

```
#define ECHO_PIN A3
#define MAX_DISTANCE_POSSIBLE 1000
NewPing sonar(TRIG_PIN, ECHO_PIN, MAX_DISTANCE_POSSIBLE);
void setup() {
  Serial.begin(115200);
}
void loop() {
delay(1000);
  unsigned int uS = sonar.ping();
  int cm = uS/US_ROUNDTRIP_CM;
  Serial.print("The cm is :");
  Serial.println(cm, DEC);
}
```

The servo test code :

```
#include <Servo.h>
Servo myservo;  // create servo object to control a servo
// twelve servo objects can be created on most boards
int pos = 0;    // variable to store the servo position

void setup() {
  myservo.attach(10);  // attaches the servo on pin 9 to the servo object
}
void loop() {
  for (pos = 0; pos <= 180; pos += 1) { // goes from 0 degrees to 180 degrees
    // in steps of 1 degree
    myservo.write(pos);              // tell servo to go to position in variable 'pos'
    delay(15);                       // waits 15ms for the servo to reach the position
  }
  for (pos = 180; pos >= 0; pos -= 1) { // goes from 180 degrees to 0 degrees
    myservo.write(pos);              // tell servo to go to position in variable 'pos'
    delay(15);                       // waits 15ms for the servo to reach the position
  }
}
```