

# **Learning Robot Programming with Linkbot for the Absolute Beginner**

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# PREFACE

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Robotics can easily get students engaged and excited about learning science, technology, engineering, and math (STEM) concepts while having fun. However, most robotic systems are not suitable for formal math and science education because of their complexity. Working with the UC Davis Center for Integrated Computing and STEM Education (C-STEM) (<http://c-stem.ucdavis.edu>), Barobo, Inc. (<http://www.barobo.com>), a UC Davis spin-off educational robotics company, has developed innovative modular robots called Mobot and Linkbot. The modular robots Mobot and Linkbot can be programmed by a user-friendly C/C++ interpreter Ch in Professional Edition, Student Edition, or Standard Edition. Ch is available from SoftIntegration, Inc. (<http://www.softintegration.com>). RoboSim is a robot simulation environment, developed by the UC Davis C-STEM Center, for programming Barobo Mobots and Linkbots. RoboSim can be freely downloaded from the C-STEM web site at (<http://c-stem.ucdavis.edu>). Ch, Mobot, Linkbot, and RoboSim are specially designed for integrating computing, robotics, and engineering into K-14 math and science education in both formal and informal programs. They are especially suited for increasing student motivation and success in learning math and science with hands-on real-world problem solving and sparking their interest in STEM subjects leading to STEM related careers and post-secondary study.

This book is a gentle introduction to robot programming with Linkbot. It teaches the absolute beginners the underlying working principles of robotics and robot programming, with an emphasis on learning math, science, technology, and engineering (STEM) using robots. The book is a step-by-step guide on how to use Linkbot to solve applied problems. The programming technique for controlling Linkbot is the same as for controlling Mobot. The contents can be readily integrated into teaching various STEM subjects for personalized and collaborative learning in classroom, afterschool and out-of-school programs. The concepts and ideas are presented in such a manner that they can be adapted by instructors to meet the unique needs of their students.

## Prerequisites

The mathematical prerequisite for the book is basic math taught in elementary school. No prior computer programming and robotics experience is required.

## Organization of the Book

The topics in the manuscript are carefully selected and organized for the best information flow for beginners to learn how to use and program the Linkbot for solving practical and realistic problems while having fun. I believe that students who have mastered the topics and working principles presented in the book shall be able to embark on applying the robotics concepts to various STEM subjects and applications. The manuscript is organized as follows:

**Chapter 1** is an introduction to robotics, RoboPlay Competition (<http://www.roboplay.org>), and starting to use the Linkbot.

**Chapter 2** uses a user friendly graphical user interface called BaroboLink to control the Linkbot.

**Chapter 3** introduces the robot programming using a C/C++ interpreter Ch.

**Chapter 4** describes how to use RoboSim for robot simulation.

**Chapter 5** presents basic programming features about variables and input/output functions, and their applications in robot programming..

**Chapter 6** describes how to write programs to control a group of Linkbots to perform identical tasks such as dancing.

**Chapter 7** describes how to write programs to control a single Linkbot with different motion characteristics.

**Chapter 8** describes how to write advanced programs to control a single Linkbot.

**Chapter 9** describes how to control a Linkbot configured as a two-wheel robot. The two-wheel robot is particularly suitable for learning math and science concepts.

**Chapter 10** describes how to write programs to process the sensory information for Linkbots.

**Chapter 11** describes how to write programs to control multiple individual Linkbots.

**Chapter 12** describes how to write programs to control one or multiple group of Linkbots.

**Chapter 13** describes how to control multiple connected Linkbots.

**Appendix A** presents a few sample programs using programming features not covered in this book.

**Appendix B** describes features available only in RoboSim and their applications. Section B.1 can be introduced right after Chapter 5. Section B.6 can be introduced after Chapter 11.

**Appendix C** lists the color names and corresponding RGB values available for the Linkbot.

**Appendix D** contains quick references to Ch features used in the book.

**Appendix E** contains quick references to member functions of the Linkbot classes.

**Appendix F** lists common mistakes in writing Ch programs.

**Appendix G** lists deprecated features and new features in the new edition. It also gives examples on how to port existing code using the new features.

The subsection **Summary** at the end of each section summarizes what you should have learned in the section. The subsection **Terminology** summarizes all terminologies and topics presented in the section.

## Symbols and Notations Used in the Book

This book was typeset by the author using L<sup>A</sup>T<sub>E</sub>X. Programs in the book are displayed with the light blue background and syntax highlighting as shown in the following line of the code.

```
printf("Hello, world!\n");
```

The output from programs are displayed with the grey background as shown in the following output.

```
Hello, world!
```

The interactive execution of programs is displayed with the dark blue background as shown in the following interactive execution.

```
Enter the weight in ounces.  
4.5  
The ice cream costs $2.11
```

Special notes and important points are highlighted with the yellow background. Keywords such as **int** and **double** in C are in red color. Reserved words such as **sqrt** and **printf** are in pink color. The **definition** for a word is in green color.

Sections marked with the double dagger symbol ‘†’ use concepts beyond Algebra I or advanced robotics concepts. They can be skipped as they do not include prerequisite skills necessary for later chapters.

The exercise symbol  indicates the location to pause for students to solve problems in the exercise section.

The symbol  indicates the Linkbot-L is used in the section or exercise.

## Using this Book as a Textbook or Supplementary Textbook

This is a comprehensive book on robot programming for solving applied problems in engineering, math, and science. Below are some possible ways to use the book. The book can be used as a textbook for courses on **Robotics**, **Engineering**, **Computer Programming**, **Computer Technology**, etc. It can also be used as a supplementary textbook for **Math 7**, **Math 8**, **Pre-Algebra**, **Algebra I**, **Integrated Math I**, and **Physical Science**. In addition, the book can be used for afterschool programs as well as computing and robotics camps.

For teaching students in elementary schools or a few hour introductory robotics activities, only materials in Chapter 1, Chapter 2, and section 13.2 in Chapter 11 without programming may be covered.

## Available Teaching Resources

To use this manuscript for teaching, instructors can contact the author to obtain related teaching materials, including the source code for all programs presented in this manuscript, PowerPoint slides for classroom presentation, and solutions for exercises.

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The latest version of this documentation is available from (<http://c-stem.ucdavis.edu>).

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## Contacting the Author

I appreciate any criticisms, comments, identification of errors in the text or programs, and suggestions for improvement of this manuscript from both instructors and students. I can be reached over the Internet at

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Harry H. Cheng

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# CHAPTER 1

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## Introduction

### 1.1 Introduction

A **robot** is a re-programmable machine that is able to move, sense, and react to its environment. **Robotics** is a branch of technology that deals with the design, construction, operation and application of robots and the related computing systems for the control, sensing, and information processing. Robotics can be used to help learn science, technology, engineering, and math (STEM) concepts while having fun. The **Mobot**, as shown in Figure 1.1, is designed as a building block. However, a single Mobot module is a fully functional four-degrees-of-freedom modular robot. It has four motors inside a Mobot. This full mobility allows a Mobot to perform a multitude of novel robot locomotion, including inch-worming, rolling, arched rolling, turning, tumbling, and standing up. Multiple Mobot modules can be interconnected into various geometries for different applications, such as a space explorer, snake, gorilla, dog, humanoid, etc.

The **Linkbot** is a new version of low-cost modular robot. It can more conveniently interface with other devices and sensors. In comparison with the Mobot, the Linkbot has only two, instead of four, degrees-of-freedom. Namely, there are only two motors inside a Linkbot. There are two versions of Linkbot, called Linkbot-I and Linkbot-L. The shapes for both Linkbot-I and Linkbot-L are the same as shown in Figure 1.2. There are three locations for joints. For Linkbot-I, two joints are in the opposite of the housing in the I-shape. For Linkbot-L, two joints are adjacent in the L-shape. Other than the difference in the location of joints, the interface and programming for both Linkbot-I and Linkbot-L are the same. The term Linkbot in this manuscript refers to both Linkbot-I and Linkbot-L. Like Mobots,



Figure 1.1: A Mobot.

## 1.1. Introduction

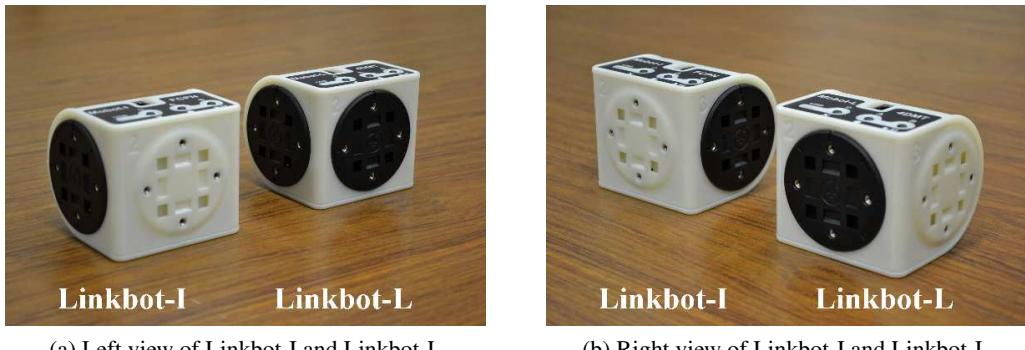


Figure 1.2: Linkbot-I and Linkbot-L.

multiple Linkbot modules can be interconnected into various geometries for different applications, such as a space explorer, snake, four-wheel drive, omnidrive, etc. as shown in Figure 1.3. Linkbots can also be connected with Mobots.

A robot can only perform tasks it has been programmed to do. When a robot does something smart, it is because a smart person has written a smart program to control the device. This introductory book teaches the absolute beginners without any prior computer programming and robotics experience the underlying working principles of robotics and robot programming. You will learn how to write your own programs so that a robot will do what you want it to do. You will also be able to write programs to control multiple Linkbots and Mobots.

 Do Exercises 1, 2, 3, 4, and 5 on page 3.

### 1.1.1 Summary

This section summarizes what you should have learned in this session.

1. A robot is a re-programmable machine that moves, senses, and reacts to its environment.
  - (a) Robots can only perform tasks they have been programmed to accomplish
  - (b) Robotics is a branch of technology that deals with design, construction, operation and application of robots and the related computing systems for the control, sensing, and information processing for robots.
2. A Mobot is a modular robot with 4 degrees of freedom.
3. A Linkbot is the new version of modular robot that interfaces with other devices and sensors. It has 2 degrees of freedom.
  - (a) Linkbot-I: two joints are in the opposite of the housing in the I-shape.
  - (b) Linkbot-L: two joints are adjacent in the L-shape.
  - (c) Programming the Linkbot-I and Linkbot-L is the same.

### 1.1.2 Terminology

Linkbot, Linkbot-I, Linkbot-L, Mbot, degrees of freedom, robot, robotics.

## 1.2. RoboPlay Competition

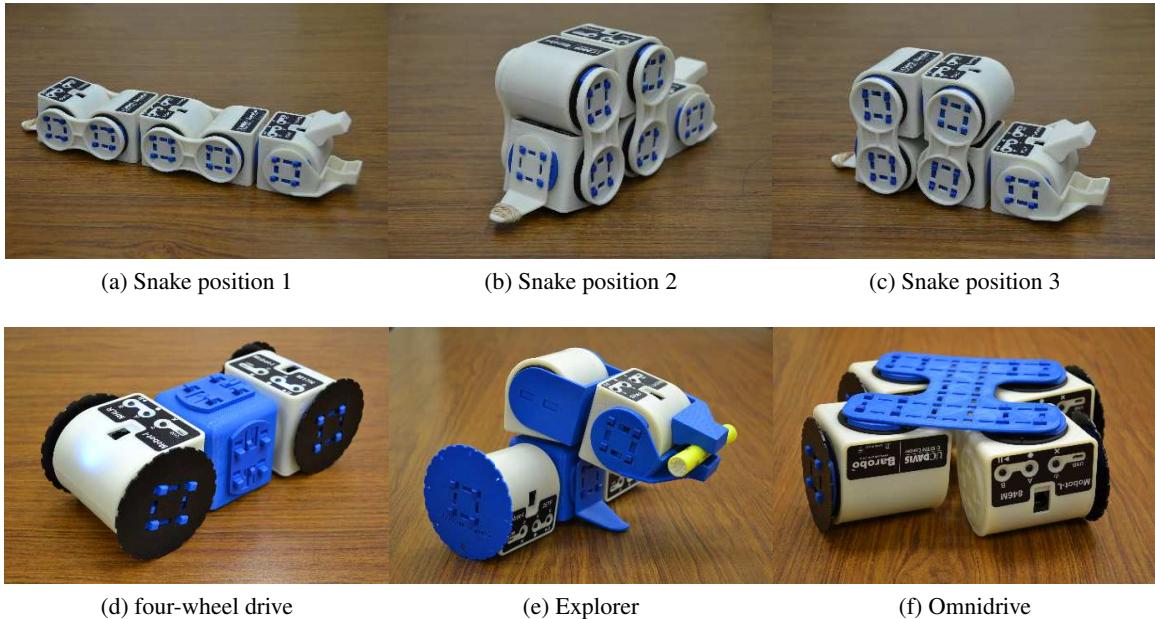


Figure 1.3: Robotic systems built with multiple Linkbots.

### 1.1.3 Exercises

1. What is a robot?
2. Where have you seen a robot?
3. What is robotics?
4. Explain what the differences are between the Linkbot-I, Linkbot-L, and Mobot?
5. List at least 3 combinations that the Linkbots can be put into for various applications.

## 1.2 RoboPlay Competition

After learning the topics in this book, students shall be able to participate in RoboPlay Competition with more detailed information available at <http://www.rooplay.org>. RoboPlay Competition consists of open-ended design challenges that integrate math and computer programming with music, choreography, and design for practical real-world problem solving. The goal of RoboPlay is to broaden student participation in computing, science, technology, engineering, and math (C-STEM) education with positive development for all students. The RoboPlay teamwork is intended to engage all students including those who might otherwise be inclined to pursue careers in the arts or humanities.

## 1.2. RoboPlay Competition



(a) RoboPlay Video Competition



(b) RoboPlay Challenge Competition

Figure 1.4: RoboPlay Competition.

There are two categories for RoboPlay Competition: RoboPlay Video Competition and RoboPlay Challenge Competition. Entries for the RoboPlay Video Competition are submitted as on-line videos. RoboPlay Video Competition is designed for students to play with robots while exploring their creativity in writing, art, music, choreography, design, video editing, and film production and at the same time seamlessly learn and apply computing and STEM concepts for solving practical problems. The handling of robot coordination between multiple modules and music requires not only teamwork in designing a well-organized visual performance, but also the math and programming skills to produce the desired actions for robots. The competitions will enable students working in different interest groups to explore the basic concepts of C-STEM in conjunction with their artistic and music talents.

The RoboPlay Challenge Competition is held on the C-STEM Day each spring near the end of the school year. The Challenge Competition is designed for students to showcase their real-world problem solving skills in a competitive environment. This competition simulates an unexpected problem occurring at a remote location such as a space station or planetary habitat, where a robotic solution must be quickly developed and deployed, using only existing resources.

Do Exercises 1 and 2 on page 4.

### 1.2.1 Summary

1. The RoboPlay Competition includes two categories: RoboPlay Video Competition and RoboPlay Challenge Competition.
2. C-STEM Day.

### 1.2.2 Terminology

RoboPlay Competition, C-STEM Day.

### 1.2.3 Exercises

1. What are RoboPlay Competitions? How many competitions do they consist of?
2. When is the RoboPlay Competition? When would you need to start preparing to compete in the RoboPlay Competition?

## 1.3. Major Features of Linkbot

## 1.3 Major Features of Linkbot

A wide range of technologies have been integrated into the Linkbot. A CAD (computer-aided design) model along with its features for Linkbot is shown in Figure 1.5.

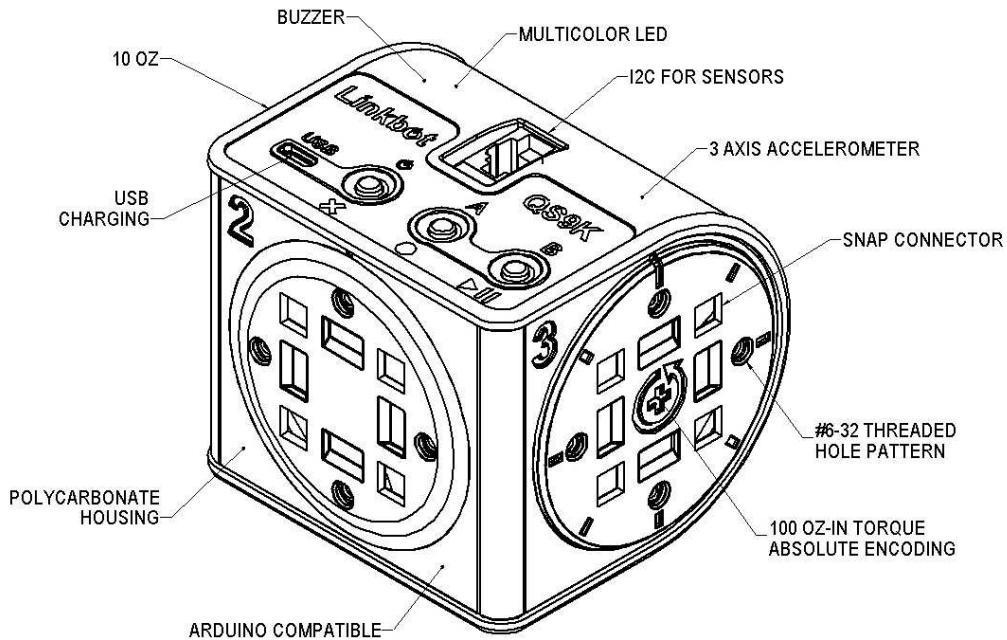


Figure 1.5: A CAD model of Linkbot.

The CPU (central processing unit) inside the Linkbot is the ATmega128RFA1 microcontroller by Atmel, running at 16 MHz. It integrates a ZigBee radio transceiver for wireless communication.

The Linkbot is powered by an internal, rechargeable lithium-ion battery that can drive motors for over 3 hours with typical use. Charging is done through the USB port with a cable and takes about 4 hours when connected to a computer. But, if it is plugged into a cell phone charger, the charging time drops to less than 2 hours. The user can use the Linkbot while it is plugged in for continual operation.

A multi-color LED can be used to personalize a Linkbot by selecting from a wide spectrum of colors. The Linkbot has a buzzer built-in to play a tune. The Linkbot also has a 3-axis accelerometer to detect free-falls, bumps, and tilted angles. Each Linkbot has three buttons for user interface.

The Linkbot weighs 10 oz. It has 100 oz-in (7.2 Kg-cm) of torque for each joint. Each hub has absolute encoding for precise control and measurement of speeds and angles accurate to  $\pm 0.5$  degree. By default, the maximum joint speed is 240 degrees per second for constant velocity control.

The Linkbot is expandable with SnapConnectors, which allow modules to be snapped together without needing tools. This allows the user to quickly try out new robot creations. The Linkbot also has standard #6-32 threaded holes available in its faceplate for custom-made accessories. The robot is made out of durable poly-carbonate plastic. A wide variety of accessories in CAD files are available for the Linkbot. The user can make accessories on their own using a 3D printer. Users can also customize these CAD files to their unique application and print using a 3D printer, laser cut, or even CNC (computer numerical control) machine depending on the part design.

Do Exercises 1 and 2 on page 6.

## 1.4. Run the On-Board Demo Program on the Linkbot

### 1.3.1 Summary

1. Linkbot is powered by a lithium-ion battery that lasts approximately 3 hours. It is charged through USB with a cable and takes approximately 4 hours.
2. The Linkbot has multi-color LED for personalization.
3. It has a 3-axis accelerometer to detect free-falls, bumps, and tilted angles.
4. The maximum joint speed is 240 degrees per second for velocity control.
5. SnapConnectors allow modules to attach to the Linkbot no tools needed. Customizable CAD files are available for customers to make accessories using a 3D printer or laser cutter.

### 1.3.2 Terminology

3-axis accelerometer, 3D printer CAD, CAD files, CNC machine, CPU, Laser cut, SnapConnectors, Torque, ZigBee.

### 1.3.3 Exercises

1. What does the Linkbot use for wireless communication?
2. How long does the battery last in a Linkbot? How long does it take to charge the Linkbot from a computer? How long using a cell phone charger?

## 1.4 Run the On-Board Demo Program on the Linkbot

The Linkbot comes with a demo program in the on-board embedded computer allowing it to work out-of-the box. The program is designed to show the motion and make sure everything is working properly. The demo program will move the Linkbot continuously until the Linkbot is shut off or the batteries die.

To run the demo program, turn on the Linkbot by pressing the power button on the Linkbot as shown in Figure 1.6. Then simply hold the button 'A' for three seconds. After three seconds have passed, the blue LED should blink three times quickly, and the demo motion will begin. You may want to run the demos for a Linkbot-I with two wheels attached, as shown in Figure 1.6b. You can turn off the demo program by pressing and holding the 'A' button for three seconds while the robot is moving.

For an old version of Linkbot, manufactured before March 2014, the demo program also serve as a secondary calibration. If a Linkbot joint gets sticky, running the demo program till you hear a beep will calibrate the robot properly.

## 1.5. Play with Multiple Linkbots

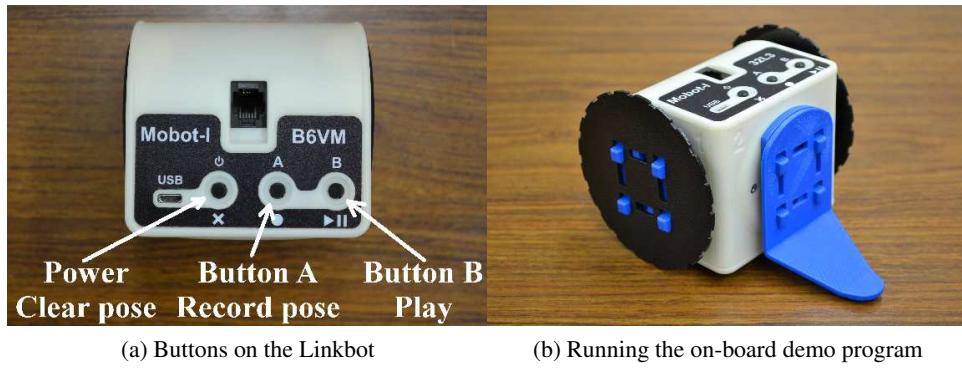


Figure 1.6: Running the on-board demo program on the Linkbot.

Do Exercises 1 and 2 on page 7.

### 1.4.1 Summary

1. The Linkbot comes with a demo program in the on-board embedded computer.
  - (a) The Demo Program shows the motion to make sure everything works properly.
  - (b) The Demo Program will continuously move Linkbot until it is shut off or batteries die.
2. To run demo program: turn on the Linkbot by pressing the power button. Then, hold the A button for three seconds. After three seconds, blue LED blinks three times and demo motion begins.

### 1.4.2 Terminology

On-board embedded computer, demo program.

### 1.4.3 Exercises

1. Run the demo program inside a Linkbot by pressing the power button on the Linkbot and hold the button 'A' for three seconds. You can stop the demo program by holding the button 'A' for three seconds.
2. What is the purpose of the Linkbot demo program?

## 1.5 Play with Multiple Linkbots

A Linkbot can be used to control one or multiple other Linkbots. Multiple Linkbots can also be controlled using PoseTeaching. In such applications, the multiple Linkbot modules must be paired together using a process called BumpConnect. The process can also be used to add additional follower robots to an existing group. All BumpConnected groups of Linkbots contain a single leader robot which can control one or more follower robots.

#### BumpConnect two unpaired Linkbots:

1. Press and hold the 'B' button on the Linkbot you want to be the leader.

## 1.5. Play with Multiple Linkbots

2. Press and hold the 'B' button on a second Linkbot.
3. Gently bump the two modules together.
4. Release the 'B' buttons.
5. After a second or so, the LED colors on both robots should change. The leader robot will blink, cycling between Blue and a randomly chosen group color. The follower should display the randomly chosen group color.
6. If nothing happens after 5 seconds, try again starting from step 1.

### BumpConnect a paired Linkbot with an unpaired Linkbot:

1. Press and hold the 'B' button on the leader robot and the unpaired robot.
2. While holding the 'B' buttons, gently bump the two robots together.
3. The unpaired robot should take on the color of the paired robot. If this does not happen after 5 seconds, try the process again starting from step 1.
4. At this point, the robots are in PoseTeaching mode, you may press the 'B' button on the leader robot to switch into TiltDrive mode. The PoseTeaching and TiltDrive modes are described in next sections.

#### 1.5.1 PoseTeaching Mode

After robots have been paired with each other to form a group, they enter the default “PoseTeaching” mode. Initially, there are zero recorded poses. In this mode, the buttons have the following functions:

- The Power or 'X' button: If the robots are not playing poses, this button deletes all recorded poses.
- The 'A' button: If the robots are not playing poses, this button records a new pose.
- The 'B' button: If there are no recorded poses, the 'B' button makes the robot switch into “TiltDrive” mode. If there are recorded poses, the 'B' button begins playing the poses. If the robot is currently playing poses, the 'B' button stops playing poses.

#### 1.5.2 TiltDrive Mode

While the group is in TiltDrive mode, the leader robot will flash its LED colors between green and the group color. In TiltDrive mode, the leader module can be tilted forward, backward, and side-to-side to drive the follower modules. In this mode, the buttons have the following functions:

- The 'B' button: Changes the current mode from “TiltDrive” mode to “CopyCat” mode.

#### 1.5.3 CopyCat Mode

While the group is in CopyCat mode, the leader robot will flash its LED colors between light-blue and the group color. In CopyCat mode, all of the follower modules will move their joints to match the position of the joints on the leader module. If there are intermixed -I and -L Linkbot modules, joint 2 will match the angle on the leader's joint 3, and vice versa. In this mode, the buttons have the following functions:

- The 'B' button: Changes the current mode from “CopyCat” mode to “PoseTeaching” mode.

## 1.5. Play with Multiple Linkbots

### 1.5.4 Unpair the Connected Linkbots

You can either press and hold the 'A' button on the leader module to unpair all modules at once, or press and hold the 'A' button on a follower module to just unpair that one follower.

 Do Exercises 1 and 2 on page 9.

### 1.5.5 Summary

1. Use BumpConnect to pair Linkbots by pushing the B buttons on both Linkbots and bumping them together.
2. You can control paired robots using PoseTeaching by pushing the A button and recording new poses that can then be saved as a ch program.
3. You can control paired robots using TiltDrive by pushing the B button directly after pairing them. The TiltDrive allows the user to control the follower module by tilting the leader module to drive the follower module.
4. CopyCat.mode allows the user to manipulate the leader module and have the follower module match that motion. You can control paired robots using CopyCat mode by pushing the B button while in TiltDrive.

### 1.5.6 Terminology

BumpConnect, CopyCat, PoseTeaching, and TiltDrive.

### 1.5.7 Exercises

1. BumpConnect two Linkbots into a group. Play with two Linkbots with PoseTeaching, TiltDrive, and CopyCat modes.
2. BumpConnect three Linkbots into a group. Play with three Linkbots with PoseTeaching, TiltDrive, and CopyCat modes.

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## CHAPTER 2

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# Controlling a Linkbot Using the Motion Control Panel

A Linkbot can be conveniently controlled without writing a computer program. This chapter presents detailed steps to control a Linkbot through a user friendly graphical user interface called BaroboLink. BaroboLink can be used to control both Linkbots and Mobots.

## 2.1 The Zero Positions of the Linkbot

### 2.1.1 The Schematic Diagram of the Linkbot

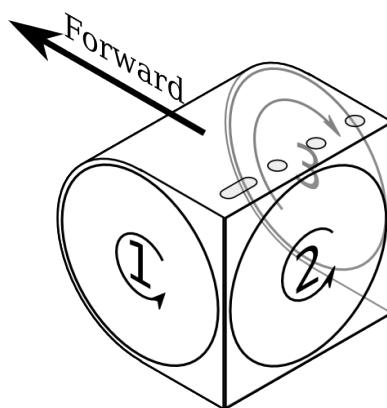


Figure 2.1: A schematic diagram of a Linkbot module.

## 2.1. The Zero Positions of the Linkbot

Figure 2.1 shows a schematic diagram of the Linkbot displaying the locations and positive directions of three joints of a Linkbot. For Linkbot-I, only joints 1 and 3 are fully rotational. The joint 2 for Linkbot-I cannot move. For Linkbot-L, only joints 1 and 2 are fully rotational. The joint 3 for Linkbot-L cannot move.

The direction of motion for each joint follows the right hand rule shown in Figure 2.2. Figure 2.1 also shows the forward direction for a Linkbot-I.

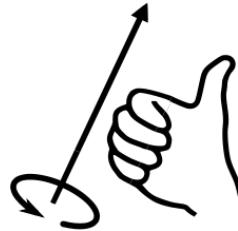


Figure 2.2: The right hand rule for the direction of motion for a joint of Linkbot.

### 2.1.2 The Zero Position for a Joint of the Linkbot

There are tiny notches on the top of the housing and disk for each joint. When these two notches for a joint are aligned as shown in Figure 2.3, the joint is in its zero position. For an illustrative purpose, these two notches for a joint are displayed with different colors as zero position marks in Figure 2.3.

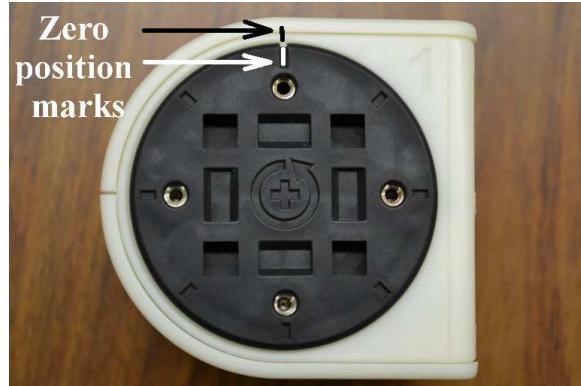


Figure 2.3: The zero position of the Linkbot.

### 2.1.3 Testing the Zero Positions and Relaxing Motors of a Linkbot

Buttons 'A' and 'B' pressed together may be used to toggle the Linkbot between holding its zero position or relaxing all of its joints. If the robot is currently relaxed, it will move to zero position and hold its position. If the 'A' and 'B' buttons are pressed again, the robot will relax its motors, allowing the user to reposition the robot.

This feature is typically used to check the robot's zero position to make sure it is properly calibrated. The button may also be used to relax a robot that is currently holding any of its joints at a position.

The feature can also be used to reset the robot to the zero position before a program controlling it is run. We will learn how to write a robot program in the next chapter.

## 2.2. Connect Linkbots from a Computer

### 2.1.4 Recalibrating the Zero Positions of the Linkbot

When the Linkbot is used for a long period of time, its zero positions for joints may be off. A user may recalibrate the robot's zero positions if necessary. To recalibrate the robot, perform the following steps:

- Position each joint of the Linkbot into its zero position. If the robot is currently actuating any of its joints, or if any joints feel “stiff”, you may power the robot off and on again, or you may press both the 'A' and 'B' buttons to relax the joints.
- While the robot is powered on, press and hold both the 'A' and 'B' buttons simultaneously. After three seconds, the LED should flash quickly three times. At this point, the robot has been recalibrated and you may release the buttons.
- Test the zero position as described in section 2.1.3.

 Do Exercises 1 and 2 on page 12.

### 2.1.5 Summary

This section summarizes what you should have learned in this session.

1. Reset the two joint angles of a Linkbot to the zero position by pressing the A and B buttons simultaneously.
2. The direction of a joint motion follows the right hand rule.
3. For Linkbot-I, only joints 1 and 3 are fully rotational joint 2 cannot move.
4. For Linkbot-L, only joints 1 and 2 are fully rotational joint 3 cannot move.
5. Recalibrate the Linkbot if used for a long period of time because the joints zero positions may be off. Put the joints in the zero position, and then push the A and B buttons simultaneously for three seconds until the LED flashes quickly three times.

### 2.1.6 Terminology

Right hand rule, zero position.

### 2.1.7 Exercises

1. Recalibrate the zero positions of a Linkbot and test the zero postions.
2. Explain how the right hand rule works and what it tells you about the direction of motion for a joint of the Linkbot.

## 2.2 Connect Linkbots from a Computer

Linkbot modules should be configured the first time they are used with a new computer. The process informs the computer to which Linkbots are allowed to connect. The configuration is performed through the BaroboLink program. This section contains step-by-step instructions on how to configure Linkbots.

## 2.2. Connect Linkbots from a Computer

### 2.2.1 Installing the Linkbot Device Driver

The BaroboLink in a computer can control one or multiple Linkbots. One Linkbot needs to be connected to the computer through the USB cable. For controlling multiple Linkbots, the Linkbot connected to the computer through the USB cable will serve as a dongle for the BaroboLink to connect and control other Linkbots through the ZigBee wireless communication, as shown in Figure 2.4. The other Linkbots in the network can be located as far as 100 meters.



Figure 2.4: The configuration for the BaroboLink to control multiple Linkbots, with one Linkbot connected to a computer through a USB cable.

For the BaroboLink to control a Linkbot, a device driver for the Linkbot needs to be installed. A **device driver** is a computer program that operates or controls a particular type of device that is attached to a computer. The BaroboLink invokes a Linkbot device driver which communicates with the Linkbot through the USB cable.

If you use the BaroboLink in a computer lab, it is very likely that your instructor or system administrator has already installed the Linkbot device driver in your computer. In case you are using the Linkbot in a computer for the first time, you can use one of the two methods described below to install the Linkbot device driver.

#### Installing the Linkbot Device Driver

After the BaroboLink is installed, you can then install the Linkbot device driver. You can connect one end of the USB cable to a Linkbot and the other end to a USB connector in the computer. Then, launch the BaroboLink as described in section 2.2.2. Click the command **File->Install Linkbot Driver**. Follow the displayed instruction to complete the installation of the Linkbot device driver.

### 2.2.2 Adding ZigBee Serial Numbers of Linkbots in BaroboLink

First, start the BaroboLink application program. In Windows, start the BaroboLink by clicking on the icon labeled “BaroboLink” on your desktop, as shown in Figure 2.5. On Mac OS X systems, the BaroboLink application is located inside the “Applications” folder in Finder. The control dialog as shown in Figure 2.6 should pop up.

## 2.2. Connect Linkbots from a Computer

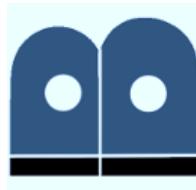


Figure 2.5: The icon for the BaroboLink.

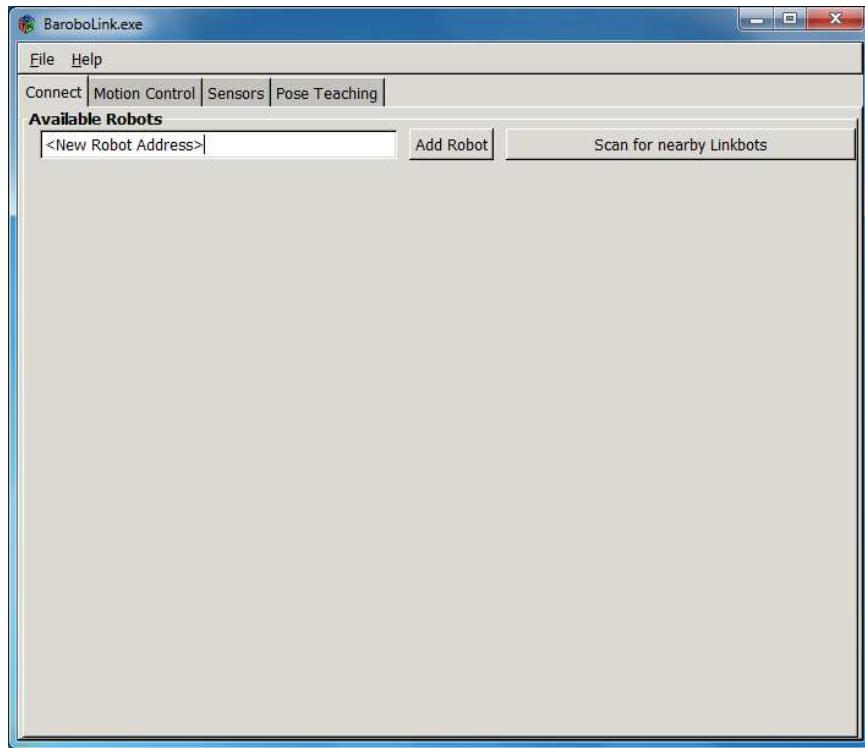


Figure 2.6: The opening screen for the BaroboLink.

The BaroboLink application, as seen in Figure 2.6, is organized into several different panels, each denoted by a tab. Upon startup the default tab is the “Connect” tab. This Connection Panel allows you to manage, connect to, and disconnect from Linkbots.

First, add your Linkbot serial number into the BaroboLink by typing in the serial number in the box marked “<New Robot Address>” and clicking on the “Add Robot” button. The dialog should appear as shown in Figure 2.7. Alternatively, you can click the “Scan for nearby Linkbots” button to display the serial numbers of all Linkbots within the range for ZigBee communication. Figure 2.8 shows serial numbers of two Linkbots. You can then click “Add Robot(s)” to add Linkbots to the BaroboLink.

## 2.2. Connect Linkbots from a Computer

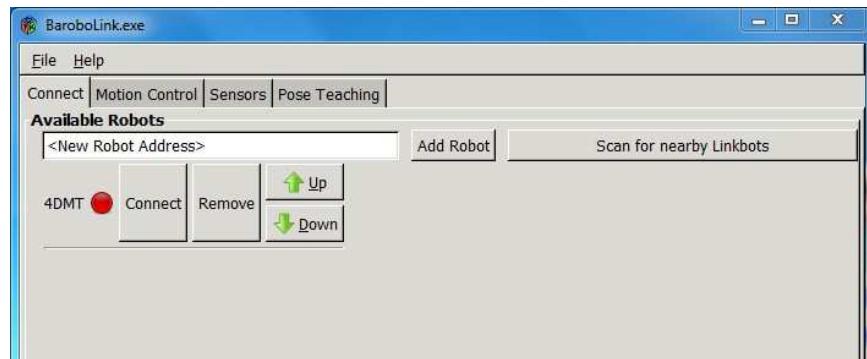


Figure 2.7: Configuring the robot ZigBee connection.

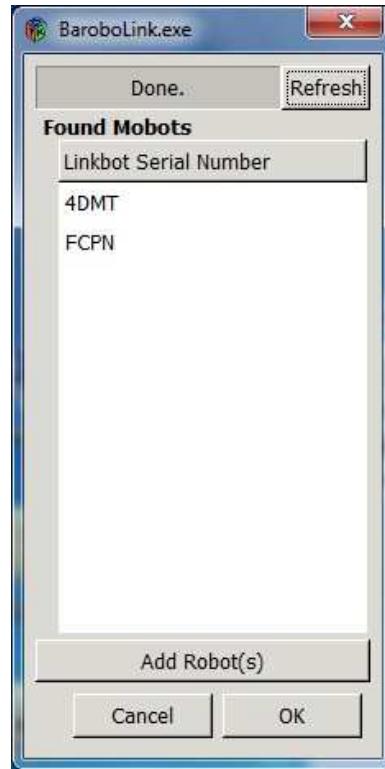


Figure 2.8: Displaying the serial number of Linkbots.

Only one Linkbot needs to be connected to the computer using the USB cable. Additional Linkbots can be connected to the computer through the ZigBee wireless communication, as shown in Figure 2.4. Each additional Linkbot added occupies its own row in the dialog. After the addition of another robot, the dialog appears as shown in Figure 2.9.

## 2.2. Connect Linkbots from a Computer

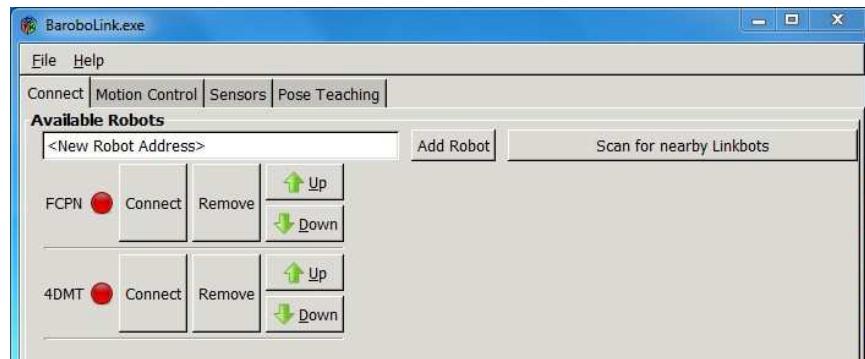


Figure 2.9: The Connection Panel with two Linkbot entries.

Once new serial numbers are added, the BaroboLink will remember the serial numbers in the future.

### 2.2.3 Making a Connection of Linkbots from a Computer

The dot next to the added serial number on the Connection Panel indicates the current connection status of the robot. A red dot indicates that the Linkbot is not currently connected, and a green dot indicates that the Linkbot is properly connected. To connect to a robot, make sure the robot is on by pressing the power button on the Linkbot, and click on the button labeled “Connect” inside the BaroboLink.

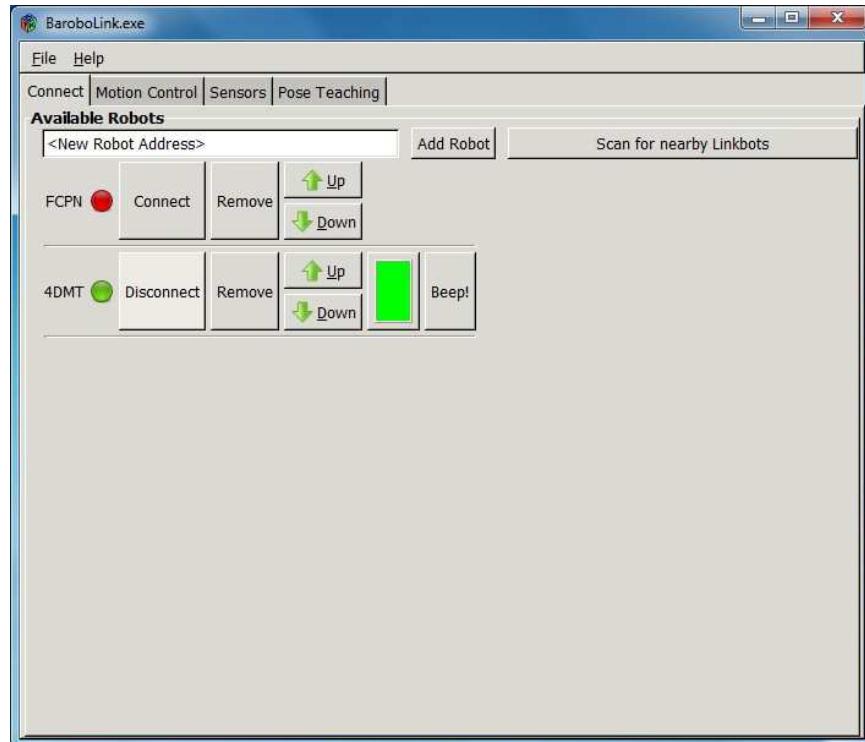


Figure 2.10: The Connection Panel showing a connected Linkbot.

## 2.2. Connect Linkbots from a Computer

If the connection succeeds, the red dot should turn green to indicate that a connection has been established, as shown in Figure 2.10. Note that in Figure 2.10, the second Linkbot had been added to the list of known Linkbots to illustrate how the Connection Panel displays as more Linkbots are added. Each additional Linkbot appears in its own row on the panel.

### Trouble Shooting the Connection of the Linkbot from a Computer

Should the connection from a computer to the Linkbot fail, you may check the following options to fix the connection problem and try again.

1. The ZigBee serial number has been entered correctly.
2. The Linkbot is turned on.
3. The device driver for the Linkbot has been installed as described in section 2.2.1.
4. Turn the Linkbot off and on again.
5. Restart the BaroboLink.
6. Plug the USB cable firmly.
7. Try a different USB cable.

Once the connection succeeds, the “Connect” button for that Linkbot turns into a “Disconnect” button. Clicking on the “Disconnect” button disconnects the Linkbot. For a connected Linkbot, you can click “Remove” button to remove a Linkbot from the BaroboLink.

You can click the “Beep!” button to hear a beep from the Linkbot.

Please note that there is no limit on the number of Linkbot that can be connected to the BaroboLink.

### Connecting Your Linkbot

Once a Linkbot is connected to the BaroboLink in a computer, a BaroboLink in other computers will not be able to find it by clicking the “Scan for nearby Linkbots” button. In case the BaroboLink in other student’s computer is connected to your Linkbot, you will not be able to make a connection to it from your computer. In this case, you can turn off the power of the Linkbot to disconnect it from the other computer first. Then, turn it on and connect it from the BaroboLink in your computer.

 Do Exercises 1, 2, and 3 on page 18.

#### 2.2.4 Summary

1. Connect to a Linkbot from a computer using the BaroboLink.
2. BaroboLink can control one or multiple Linkbots.
3. To add your Linkbot, type the Linkbot serial number into the BaroboLink box marked <New Robot Address> and click “Add Robot”.
4. If robot is added correctly: green = connected; red = not connected.
5. Once a Linkbot is connected to BaroboLink, other computers will not be able to detect the Linkbot or try to connect to it.

#### 2.2.5 Terminology

BaroboLink, device driver, Zigbee communication.

## 2.3. The Sensors Panel

**2.2.6 Exercises**

1. Connect the computer to your Linkbot by typing in the address and adding the robot and then clicking connect. Click “Beep” to make your Linkbot beep.
2. Remove the address for your Linkbot and then click “scan for nearby Linkbots.” Search for your Linkbot and connect it. Click “Beep” to make your Linkbot beep.
3. What can you do if your Linkbot is connected to another student’s computer and you want to connect it to your computer?

## 2.3 The Sensors Panel

By default, when a Linkbot is turned on, its LED displays the blue color. Once it is connected, the color will be changed to the green. You can click the color button for a connected Linkbot on the Connection Panel, or the “Sensors” tab, the Sensors Panel will appear as shown in Figure 2.11. The LED color, its RGB (Red, Green, Blue) values and HSV (Hue, Saturation, and Value) values, and color name will be displayed. The RGB and HSV are color models. The color of the LED can be changed through the color dial, RGB, or HSV values. The Sensors Panel also displays the X, Y, and Z components as well as the magnitude of the accelerometer data.

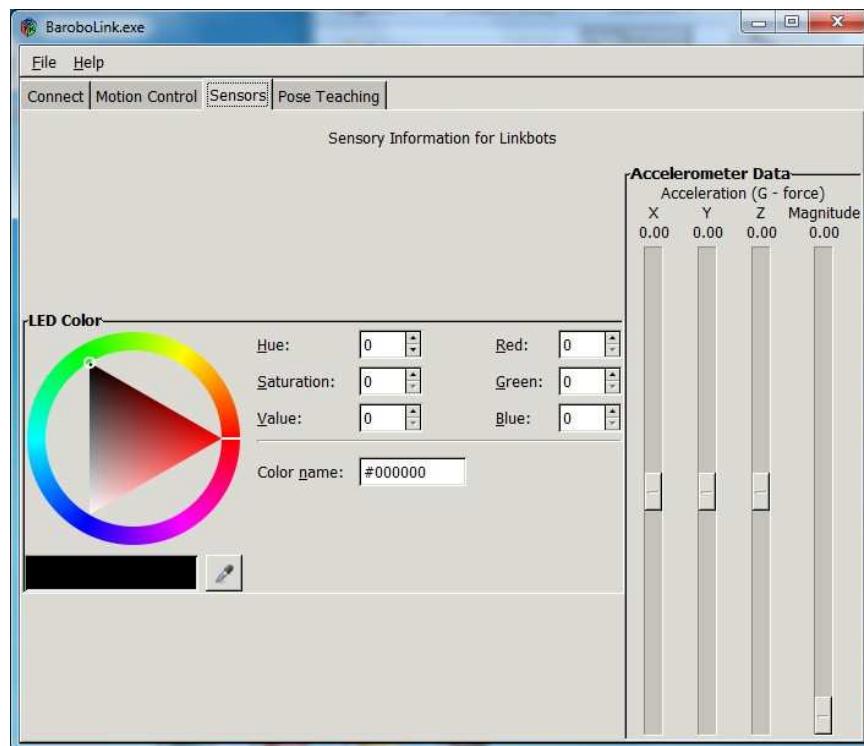


Figure 2.11: The Sensors Panel showing the color of the LED and accelerometer data.

Do Exercises 1 and 2 on page 19.

## 2.3. The Sensors Panel

### 2.3.1 Summary

1. The default LED color is blue to show that the robot is turned on.
2. The LED color turns green when the robot is connected.
3. Click on the “Sensors” tab. The color of the LED can be changed through the color dial, RGB, or HSV values.
4. The Sensors Panel also displays the X, Y, and Z components and the magnitude of the accelerometer data.

### 2.3.2 Terminology

LED color, Sensors Panel.

### 2.3.3 Exercises

1. Click on the “Sensors” tab and click on the LED Color wheel to choose the color you like.
2. While your linkbot is connected, rotate and move the robot around and observe how the sliders under “Accelerometer Data” move. Can you cause only two sliders to move while the third remains roughly still?

## 2.4. Control a Linkbot Using the Motion Control Panel

## 2.4 Control a Linkbot Using the Motion Control Panel

### 2.4.1 The Motion Control Panel

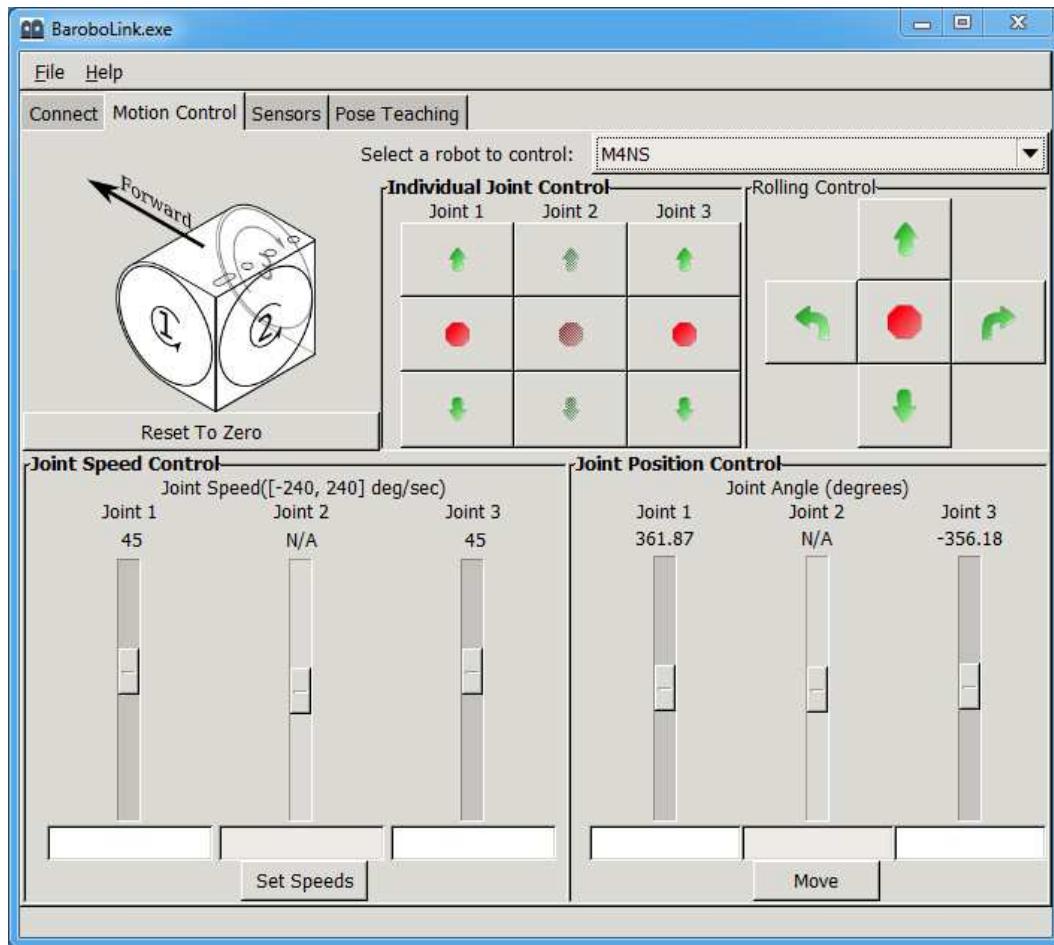


Figure 2.12: The Motion Control Panel of the BaroboLink with a Linkbot-I connected.

## 2.4. Control a Linkbot Using the Motion Control Panel

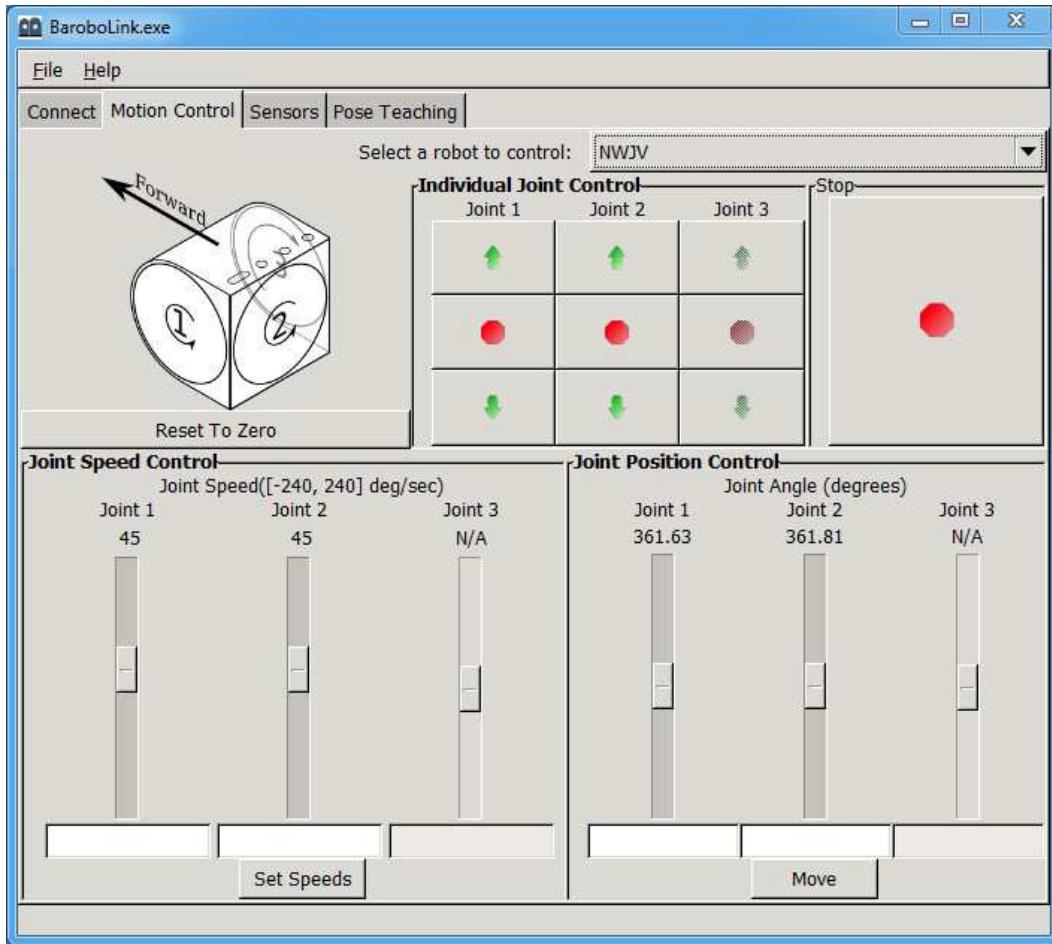


Figure 2.13: The Motion Control Panel of the BaroboLink with a Linkbot-L connected.

Once a robot is connected to the BaroboLink, the joint angles and speeds of the robot are displayed on the Motion Control Panel as shown in Figure 2.12 for a Linkbot-I. Figure 2.13 shows the Motion Control Panel for a Linkbot-L. This panel is located under the second tab of the BaroboLink, labeled “Motion Control”. The Motion Control Panel can be used to display information about the Linkbot’s joint positions, and also control the speeds and positions of the Linkbot’s joints. The panel is divided into five sections; three on the top half of the panel, and two on the bottom half. The functions of these five sections will be discussed in the next section.

### 2.4.2 The “Reset To Zero” Button

The first section of the GUI located on the top left of the panel displays a schematic diagram of the Linkbot as shown in Figure 2.14. Underneath the schematic diagram, there is a button with the text “Reset To Zero”. When clicked, this button will command the connected Linkbot to rotate each joint to the zero angle position.

## 2.4. Control a Linkbot Using the Motion Control Panel

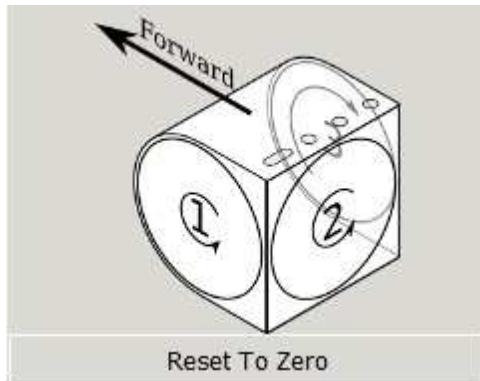


Figure 2.14: The button to reset to zero.

You can also move all joints of a Linkbot into zero positions by pressing both A and B buttons of the Linkbot.

### 2.4.3 Individual Joint Control

The second section, located at the top-middle section of the panel, is the “Individual Joint Control” section, as shown in Figure 2.15. These buttons command the Linkbot to move individual joints. When the up or down arrows are clicked, the Linkbot begins to move the corresponding joint in either the positive, or negative direction. The joint will continue to move until the stop button, located between the up and down arrows, is clicked.

Figure 2.15a shows the “Individual Joint Control” section for Linkbot-I. Since joint 2 is not movable for Linkbot-I, joint 2 is not clickable with the fainted background. Figure 2.15b shows the “Individual Joint Control” section for Linkbot-L. Since joint 3 is not movable, joint 3 is not clickable with the fainted background.

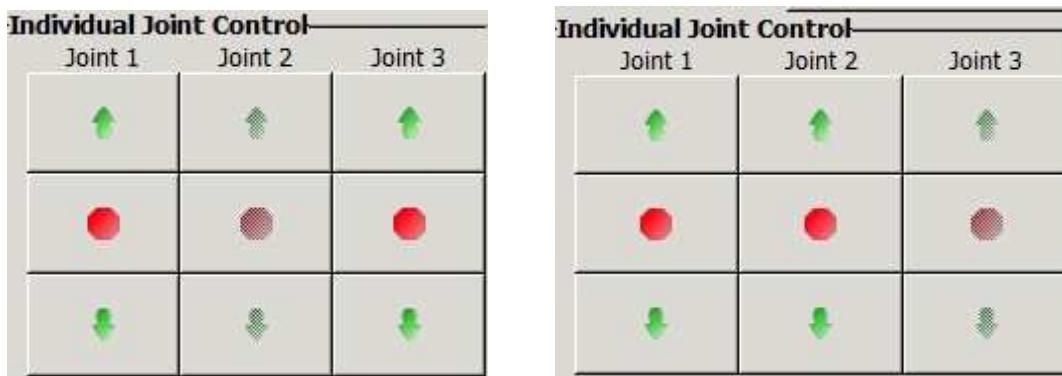


Figure 2.15: The individual joint control.

If the joint encounters any obstacle that prevents it from moving, the joint will automatically disengage power to the joint. This may happen, for example, if it collides with the other object.

Do Exercise 1 on page 26.

## 2.4. Control a Linkbot Using the Motion Control Panel

### 2.4.4 Rolling Control for Linkbot-I

The Rolling Control section contains buttons for controlling a Linkbot-I as a two-wheel robot as shown in Figure 2.16. The up and down buttons cause the Linkbot to roll forward or backward, as shown in Figure 2.16. The left and right buttons cause the Linkbot to turn to the left, or to the right. The stop button in the middle causes the Linkbot to stop where it is.

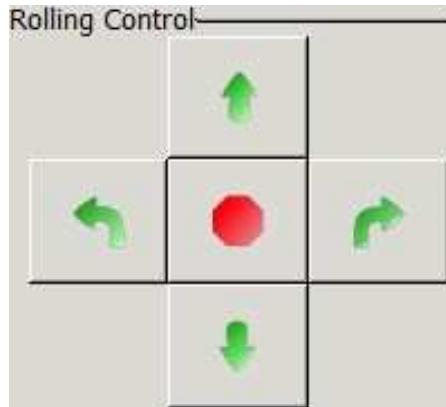


Figure 2.16: The rolling control for a Linkbot-I.

Do Exercise 2 on page 26.

### 2.4.5 Joint Speed Control

The Joint Speed Control section is located at the bottom left of the panel, as shown in Figure 2.17. It displays and controls the current joint speeds of the Linkbot. The joint speeds are in units of degrees per second. To set a specific desired joint speed for a particular joint, you can move the slider to change the joint speed. The joint speed may also be typed directly into the edit boxes below the sliders, and the “Set Speeds” button should be clicked.

Like individual joint control, Figure 2.17a shows the “Joint Speed Control” section for Linkbot-I. Since joint 2 is not movable for Linkbot-I, joint 2 is not clickable with the fainted background. Figure 2.17b shows the “Joint Speed Control” section for Linkbot-L. Since joint 3 is not movable, joint 3 is not clickable with the fainted background.

## 2.4. Control a Linkbot Using the Motion Control Panel

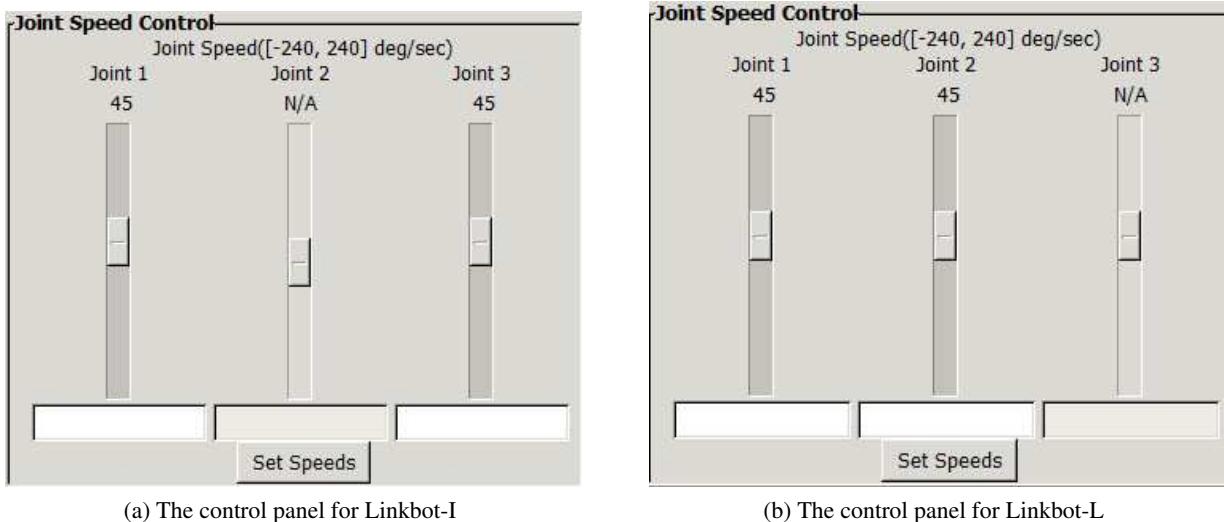


Figure 2.17: The joint speed control.

Do Exercise 3 on page 26.

#### 2.4.6 Joint Position Control

The Joint Position Control section is located in the bottom-middle of the panel, as shown in Figure 2.18. It is used to display and control the positions of each of the two joints of a Linkbot. The joint positions are displayed in the numerical text located above each vertical slider. The displayed joint positions are in units of degrees.

Like individual joint control and joint speed control, Figure 2.18a shows the “Joint Position Control” section for Linkbot-I. Since joint 2 is not movable for Linkbot-I, joint 2 is not clickable with the fainted background. Figure 2.18b shows the “Joint Position Control” section for Linkbot-L. Since joint 3 is not movable, joint 3 is not clickable with the fainted background.

## 2.4. Control a Linkbot Using the Motion Control Panel

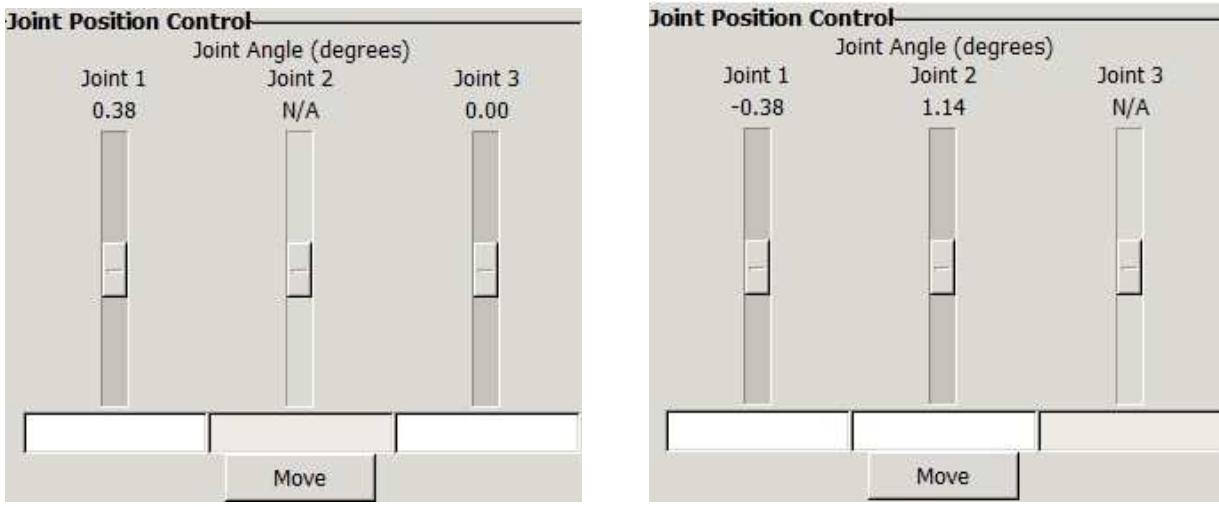


Figure 2.18: The joint position control.

Controlling the joints can be done by using the vertical sliders. Each vertical slider's position represents a joint's angle. When the position of the slider is moved, the Linkbot will move its joints to match the sliders.

An alternative method for moving the joints is by entering the exact angles for the joints. Underneath the sliders, there are two valid text entry boxes. The text boxes accept specific angles for each joint into which the user may type. If the “Move” button is clicked, each joint will move the amount in degrees specified in the text entry with respect to its current position. If any text entry is left blank, the corresponding joint will not move.

Do Exercise 4 on page 26.

### 2.4.7 Control Multiple Linkbots

A computer can connect to multiple Linkbots as described in section 2.2. The Motion Control Panel can be used to control multiple Linkbots, one at a time. If a computer is connected to multiple Linkbots, an individual Linkbot can be selected to be controlled by picking the ZigBee serial number of the Linkbot from the drop down menu labeled as “Select a robot to control” underneath the tabs as shown in Figure 2.12.

Do Exercise 5 on page 26.

### 2.4.8 Summary

This section summarizes what you should have learned in this session.

1. Control the motion of joints of a Linkbot individually through the “Motion Control Panel”.
2. Control the motion of a Linkbot as a two-wheel vehicle.
3. Set the joint speeds of a Linkbot. Joint speeds are specified in degrees per second.
4. Set the joint angle that a Linkbot will be moved to. Joint angles are specified in degrees.
5. The motion for the Linkbot’s joints has no limit.

## 2.4. Control a Linkbot Using the Motion Control Panel

6. Connect to multiple Linkbots from a computer through the BaroboLink and control one at a time through the Motion Control Panel.

### 2.4.9 Terminology

Joint angle, joint speed, individual joint control, joint speed control, and joint position control.

### 2.4.10 Exercises

1. Connect your computer to a Linkbot-I through BaroboLink. Click “Reset To Zero” to reset two joint angles of the Linkbot to the zero position on the Motion Control Panel. Move joint 1 in the positive direction through the Individual Joint Control. Move joint 3 in the positive direction. Stop the motion of joints 1 and 3. Move joints 1 and 3 in the negative direction. then stop both joints.
2. Click “Reset To Zero” to reset two joint angles of a Linkbot-I to the zero position on the Motion Control Panel. First, roll the joints 1 and 3 forward through the Rolling Control. Then, turn the robot left. Next, roll the Linkbot forward. Turn the robot right. Roll the Linkbot backward. Finally, stop the Linkbot.
3. Click “Reset To Zero” to reset two joint angles to the zero position on the Motion Control Panel. First, roll the joints 1 and 3 forward through the Rolling Control. Change the speed of joints 1 and 3 to 30 degrees per second through the Joint Speed Control while the robot is moving.
4. A Linkbot, as a two-wheel robot, turns its two wheels at 45 degrees per second. (a) How long will it take for the robot to rotate its wheels two full rotations (720 degrees)? You may set the joint speeds first, then move the joints 1 and 3 to the specified position while timing the motion using a stop watch.  
(b) If the radius of the wheel is 1.75 inches, what is the distance that the robot has moved forward?
5. Work with your partner to connect a computer to two Linkbots. Control the connected two Linkbots using a Motion Control Panel of BaroboLink on the computer.

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## CHAPTER 3

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# Getting Started With Programming Linkbots

### 3.1 Get Started with Ch for Computer Programming

In Chapter 2, we learned how to control a Linkbot using the Motion Control Panel. However, in order for a Linkbot to solve complicated problems, we need to write a computer program to control the Linkbot. Unlike using the Motion Control Panel, a computer program can be saved in a file for later use. It can also conveniently be copied to a new file and modified to solve similar problems.

The Linkbot can be controlled using a C/C++ program through Ch, a C/C++ interpreter. Ch Professional Edition or Ch Student Edition is required to run the programs for controlling Linkbot. Ch Student Edition is free to install in a computer owned by a student. Ch is user-friendly and specially designed for beginners to learn computer programming. For example, when an error occurs, Ch will give an insightful error message, instead of confusing messages or crashing. Ch is available from SoftIntegration, Inc. at <http://www.softintegration.com>. Ch programs presented in this book are available in the C:/C-STEM/LearnLinkbot folder in Windows, /opt/C-STEM/LearnLinkbot in Mac OS X, and /usr/local/C-STEM/LearnLinkbot in Linux.

In this chapter, we will learn how to write computer programs in Ch to solve applied problems and control a Linkbot.

#### 3.1.1 Getting Started with ChIDE

An Integrated Development Environment (IDE) can be used to develop computer programs. ChIDE in Ch is an IDE to edit, debug, and run C/Ch/C++ programs. ChIDE can be conveniently launched by double

### 3.1. Get Started with Ch for Computer Programming

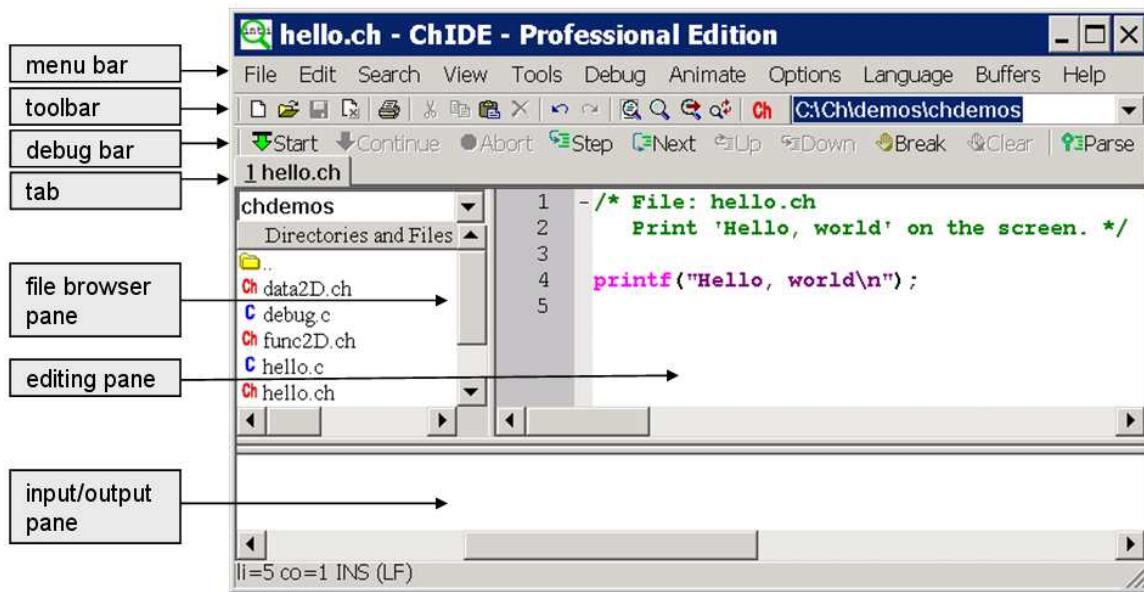


Figure 3.1: A layout and related terminologies in ChIDE.

**int*i*** clicking its icon  on the desktop. A layout of ChIDE is displayed in Figure 3.1, which also shows various terms used to describe ChIDE in this book.

#### 3.1.2 The First Ch Program

Let's get started with programming in Ch! We will write a simple program shown in Program 3.1. The program will display the following output on the screen when it is executed:

```
Hello, world
```

To run the code in Program 3.1, the source code needs to be written first. **Source code** is plain text, which contains instructions of a program. If the text in Program 3.1 is typed in the editing pane in ChIDE, the program will appear colored due to syntax highlighting and with line numbers, as shown in Figure 3.1.

```
/* File: hello.ch
Print 'Hello, world' on the screen. */

printf("Hello, world\n");
```

Program 3.1: The first Ch program *hello.ch*.

We will explain each line in Program 3.1 in detail. Contents that begin with `/*` and end with `*/` are comments. **Comments** are used to document a program to make the code more readable. When comments are processed by Ch, they are ignored and no action is taken relating to the comments. The first two lines, listed below, in Program 3.1 are comments.

```
/* File: hello.ch
Print 'Hello, world' on the screen */
```

### 3.1. Get Started with Ch for Computer Programming

They document that the file name of the program is `hello.ch` and the purpose of the program is to display the message `Hello, world` on the screen.

A Ch program typically ends with “.ch”, which is called the *file extension*. A file name generally does not contain a space.

A *function* is the basic executable module in a program. Asking a function to perform its assigned tasks is known as *calling* the function.

In the statement

```
printf("Hello, world\n");
```

The function `printf()` is used to display `Hello, world` on the screen. The symbol `\n` will be explained in section 3.1.6. Each statement in a program must end with a semicolon.

All programs presented in this book are available in the distribution of the source code for this book. Once they are installed, they are typically located in the folder `C:\C-STEM\LearnLinkbot` in Windows and `/opt/C-STEM/LearnLinkbot` in Mac OS X.

### Opening Programs in ChIDE from Windows Explorer

In Windows, a program listed in the Windows explorer can be opened in the editing pane of ChIDE by clicking on the program. The program can also be opened in the editing pane by dragging and dropping it on to the ChIDE icon on the desktop.

#### 3.1.3 Editing Programs

Text editing in ChIDE works similarly to most Windows or Mac text editors, such as Microsoft Word. As an example, open a new document by clicking the command `File->New` on the menu bar, or the first icon on the toolbar that looks like a little piece of paper with a folded corner, as shown in Figure 3.1.

You can save the document as a file named `hello.ch` by the command `File->Save As`. Follow the instruction and type the file name `hello.ch` to save as a new program. You can also right click the file name on the tab bar, located below the debug bar, and then select the command `Save As` to save the program.

#### 3.1.4 Running Programs and Stopping Their Execution

Click `Run` on the toolbar, as shown in Figure 3.2, to execute the program `hello.ch`. This will cause the interpreter to read the code and provide an output on the bottom of the ChIDE window as shown in Figure 3.2. Pressing the function key `F2` will also execute the program. If you are editing a program, pressing `F2` will save the edited program first and then run the saved program.

If the command execution has failed or execution is taking too long to complete, then the `Stop` command on the toolbar can be used to stop the program.

#### 3.1.5 Output from Execution of Programs

The *editing pane* on the top is for writing and editing a program source file or any text file. The *input/output pane* is located below the editing pane, and is initially hidden. It can be made larger by dragging the divider between it and the editing pane. The output from the program is directed into the input/output pane when it is executed using the command `Run`, as shown in Figure 3.2. When the program `hello.ch` is executed,

### 3.1. Get Started with Ch for Computer Programming

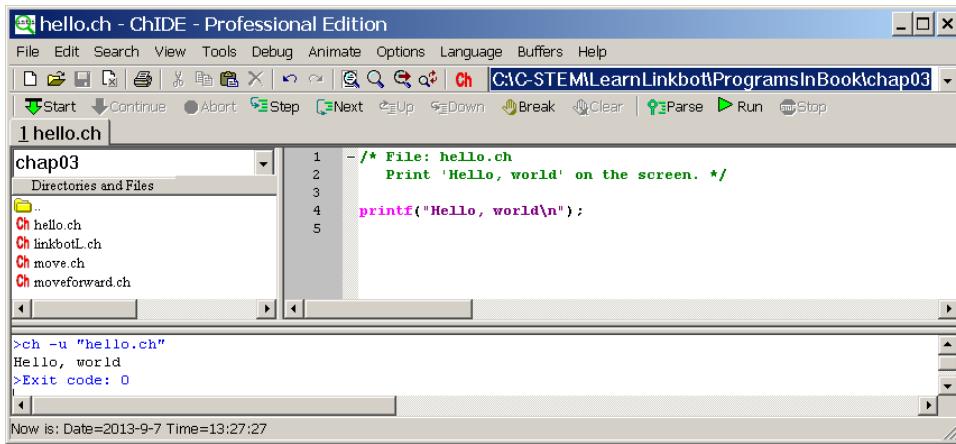


Figure 3.2: Running the program inside the editing pane in ChIDE and its output.

the input/output pane will be made visible if it is not already visible and will display the following three lines, as shown in Figure 3.2.

```

>ch -u "hello.ch" // use the command ch for Ch to execute hello.ch
Hello, world // the output from executing the program hello.ch
>Exit code: 0 // display the exit code for the program

```

An exit code of 0 indicates that the program has terminated successfully. If a failure had occurred during the execution of the program, the exit code would be -1.

Do Exercises 1, 2, and 3 on page 34.

#### 3.1.6 Newline Character

The symbol \n used in the function `printf()` in Program 3.1 means a **newline character**. It instructs the computer to start writing on a new line, like the Enter key, which can be illustrated by changing the line

```
printf("Hello, world\n");
```

to

```
printf("Hello, world\nWelcome to Ch!\n");
```

The output of the new program will become

```
Hello, world
Welcome to Ch!
```

After the newline character, the string `Welcome to Ch!` is displayed at the beginning of the next line on the screen.

#### 3.1.7 Copying Contents in a Program to Another Program in ChIDE

Unlike a calculator, an existing Ch program can be copied to a new file. This process of creating a new program can save a lot of typing. Below are the step-by-step instructions on how to create a program `hello2.ch` to produce the output described in section 3.1.6. It copies the file `hello.ch` in Program 3.1 to a new program `hello2.ch` in ChIDE to solve the above problem.

### 3.1. Get Started with Ch for Computer Programming

1. Open the file `hello.ch` in Program 3.1 in the folder `C:\C-STEM` for Windows, `/opt/C-STEM` for Mac OS X, `/usr/local/C-STEM` for Linux in the file browser pane as shown in Figure 3.5.
2. Select all the contents of this program by clicking the command `Edit->Select All` or holding the left button of the mouse and dragging the mouse to select the contents to be copied.
3. Click the right button to bring up the menu and click the `Copy` command on the menu to copy the selected contents into the buffer. Or use `Ctrl+C` for a shortcut for copying.
4. Open a new document by clicking the first icon on the toolbar that looks like a little piece of paper with a folded corner, as shown in Figure 3.1.
5. Move the cursor to the editing page, click the right button to bring up the menu, and click the `Paste` command on the menu to paste the contents in the buffer to the opened document. Or use `Ctrl+V` for a shortcut for pasting.
6. Save this document as a new program `hello2.ch`,
7. Modify the program `hello2.ch` with the statement below.

```
printf("Hello, world\nWelcome to Ch!\n");
```

 Do Exercises 4 and 5 on page 34.

#### 3.1.8 Correcting Errors in Programs

ChIDE can identify errors that occur in the source code and provide helpful responses that aid the user in finding and correcting these errors. To see this, we will create an error in the program `hello.ch` by changing the line

```
printf("Hello, world\n");
```

to

```
printf("Hello, world\n";
```

Notice that in the second statement the closing parenthesis is missing. When the program is executed, the results should look like the input/output pane in Figure 3.3. The line with incorrect syntax in the editing pane and the corresponding error message in the input/output pane will be highlighted with a yellow background. The first error message at the line

```
ERROR: missing ')' before ';'
```

indicates that a closing parenthesis is missing before the semicolon `'.'`.

Because the program fails to execute, the exit code `-1` is displayed at the end of the input/output pane as

```
>Exit code: -1
```

Errors in computer programs are called **bugs**. The process of finding and reducing the number of bugs is called **debug** or **debugging**. ChIDE is especially helpful for testing and debugging programs.

 Do Exercise 6 on page 34.

### 3.1. Get Started with Ch for Computer Programming

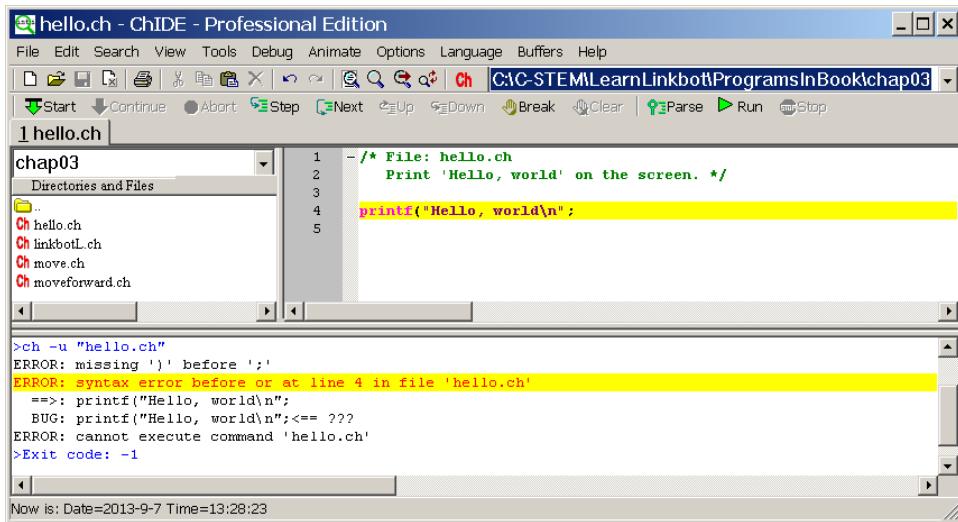


Figure 3.3: The error line in output from executing program hello.c.

#### 3.1.9 Browsing Files

All programs described in the book are available in a folder in C:\C-STEM for Windows, /opt/C-STEM for Mac OS X, /usr/local/C-STEM for Linux. If you use a computer in a laboratory, you may not have permission to write in this folder. You may copy these programs in your own folder.

In Windows, you can hover the cursor over the program name on the tab, the full path and program name will be displayed, as shown in Figure 3.4. This is useful to find out where the program is located when you open multiple programs.

Programs in the current working directory are displayed in the file browser pane, as shown in Figure 3.1. The current working directory is displayed at the end of the tool bar and also at the top of the file browser pane. The first entry under Directories and Files in the file browser pane is the parent directory of the current working directory. Clicking the arrow at the end of the current working directory in the file browser pane, all parent directories of the current working directory are displayed as shown in Figure 3.5. Selecting a parent directory, its contents will be displayed in the file browser pane.

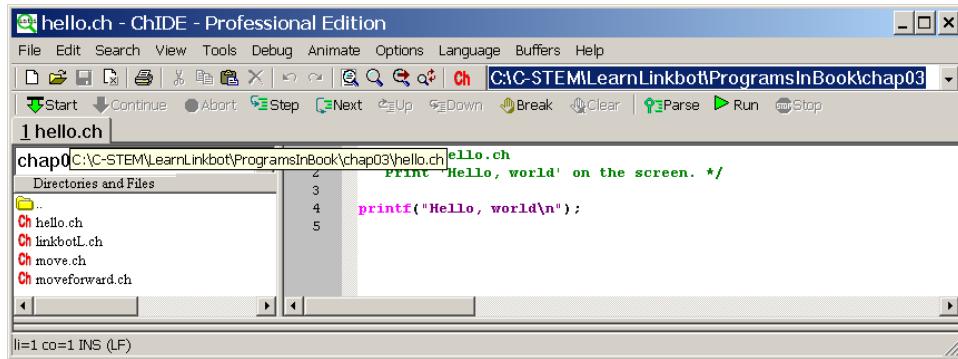
The history of current working directories can be displayed by clicking the arrow at the end of the tool bar as shown in Figure 3.6. Selecting a directory in the history of the current working directories, the selected directory will become the current working directory and its contents will be displayed in the file browser pane.

#### 3.1.10 Summary

This section summarizes what you should have learned in this session.

1. **A Ch program has a file name with a file extension ".ch". A file name generally does not contain a space.**
2. The comments in a Ch program begin with `/*` and end with `*/`.
3. Use the output function `printf()` to print a string.
4. Each statement in a Ch program ends with a semicolon.
5. Use the escape character '`\n`' as a newline character.

### 3.1. Get Started with Ch for Computer Programming



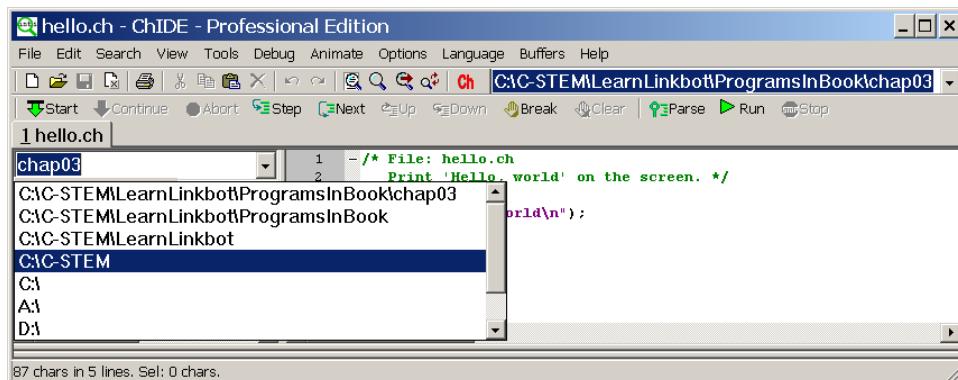
The screenshot shows the ChIDE Professional Edition interface. The title bar reads "hello.ch - ChIDE - Professional Edition". The menu bar includes File, Edit, Search, View, Tools, Debug, Animate, Options, Language, Buffers, and Help. The toolbar contains icons for Start, Continue, Abort, Step, Next, Up, Down, Break, Clear, Parse, Run, and Stop. The status bar at the bottom shows "l=1 co=1 INS (LF)". The main window displays a file named "hello.ch" with the following code:

```
chap03 /* File: hello.ch
          Print 'Hello, world' on the screen. */
          printf("Hello, world\n");
```

The left pane shows a "Directories and Files" tree with the following structure:

- ..
- Ch hello.ch
- Ch linkbotL.ch
- Ch move.ch
- Ch moveforward.ch

Figure 3.4: Displaying the full path of a program.



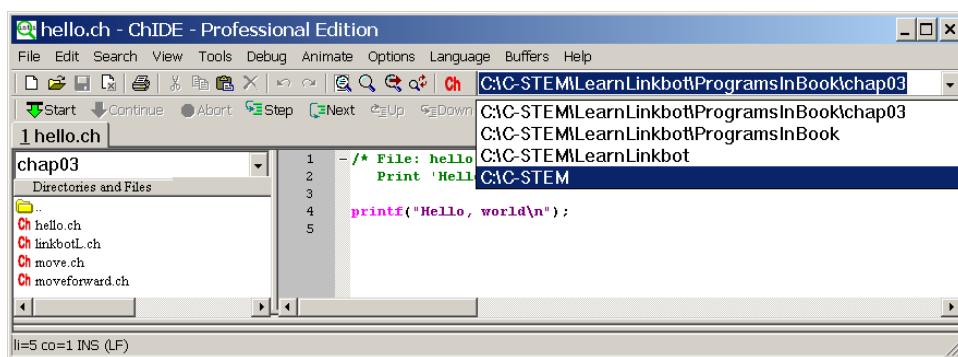
The screenshot shows the ChIDE Professional Edition interface. The title bar reads "hello.ch - ChIDE - Professional Edition". The menu bar includes File, Edit, Search, View, Tools, Debug, Animate, Options, Language, Buffers, and Help. The toolbar contains icons for Start, Continue, Abort, Step, Next, Up, Down, Break, Clear, Parse, Run, and Stop. The status bar at the bottom shows "87 chars in 5 lines. Sel: 0 chars". The main window displays a file named "hello.ch" with the following code:

```
chap03 /* File: hello.ch
          Print 'Hello, world' on the screen. */
          printf("Hello, world\n");
```

The left pane shows a "Directories and Files" tree with the following structure:

- ..
- Ch
- A:\
- D:\

Figure 3.5: Displaying the parent directories of the current working directory.



The screenshot shows the ChIDE Professional Edition interface. The title bar reads "hello.ch - ChIDE - Professional Edition". The menu bar includes File, Edit, Search, View, Tools, Debug, Animate, Options, Language, Buffers, and Help. The toolbar contains icons for Start, Continue, Abort, Step, Next, Up, Down, Break, Clear, Parse, Run, and Stop. The status bar at the bottom shows "l=5 co=1 INS (LF)". The main window displays a file named "hello.ch" with the following code:

```
chap03 /* File: hello.ch
          Print 'Hello, world' on the screen. */
          printf("Hello, world\n");
```

The left pane shows a "Directories and Files" tree with the following structure:

- ..
- Ch hello.ch
- Ch linkbotL.ch
- Ch move.ch
- Ch moveforward.ch

Figure 3.6: Displaying the history of current working directories.

### 3.1. Get Started with Ch for Computer Programming

6. Use the integrated development environment ChIDE to edit and run Ch programs.
7. Edit, save, and run Ch programs in ChIDE.
8. Run a program by pressing the function key F2.
9. Copy contents in ChIDE using Copy/Paste.
10. Find the corresponding lines in a program with error messages and fix bugs in the program.

#### 3.1.11 Terminology

bugs, calling the function, ChIDE, comment, copy program, debug, debugging, editing pane, error message, exit code, file extension, IDE, Integrated Development Environment, newline character, input/output pane, `printf()`, Run, source code, Stop

#### 3.1.12 Exercises

1. Create a folder called `learnLinkbot` to keep Ch programs that you will develop. You may use an alternative folder name and location that your instructor specifies.
2. What is wrong with this line of code:

```
printf('cool!');
```

3. Write a program `cool.ch` to display

```
This is cool!
```

Use the command `File->New` or click the first menu on the toolbar in ChIDE to open a new unsaved program to enter your code for the program. The program calls the function `printf()` to display the output on the screen. Save your program as `cool.ch` using the command `File->Save As` in the folder created in Exercise 1. Execute the program in ChIDE by the command `Run`.

4. Write a program `welcome.ch` to display

```
Hello, world.  
Welcome to Ch!  
This is cool.  
by [your_name, today's date]
```

Based on the instructions described in section 3.1.7 to copy the program `cool.ch`, developed in Exercise 3, to the program `welcome.ch`. The program calls the function `printf()` four times, one for each output line. Run the program in ChIDE.

5. Write a program `welcome2.ch` to display the same output as that from the program `welcome.ch` developed in Exercise 4. But, the program `welcome2.ch` shall call the function `printf()` only once. Based on the instructions described in section 3.1.7 to copy the program `welcome.ch` to the program `welcome2.ch`. Run the program in ChIDE.
6. Modify the program `welcome.ch` developed in Exercise 4 to introduce a bug by removing a closing parenthesis `)`. Run the modified program in ChIDE by pressing the function key F2. Find the line corresponding to the first error message in the editing pane. Then, fix the bug.

## 3.2. Move Joints Relative to their Current Positions

## 3.2 Move Joints Relative to their Current Positions



A Ch program can be developed to control the Linkbot. The working principle of a program is the same as using BaroboLink. Program 3.2 contains the code typically used for controlling a Linkbot-I. We will explain the functionality of each statement in this robot program.

```
/* File: move.ch
   Move joints relative to the current positions. */
#include <linkbot.h>
CLinkbotI robot;

/* connect to the paired robot */
robot.connect();

/* set the robot to "zero" position, where all joint angles are 0 degree. */
robot.resetToZero();

printf("Here comes a robot!\n");

/* move joint 1 by 360 degrees and joint 3 by -360 degrees */
robot.move(360, NaN, -360);

printf("Cool!\n");
```

Program 3.2: The first program to control a Linkbot-I.

A line that starts with a # has a special meaning, which depends on the symbol following it. The line

```
#include <linkbot.h>
```

instructs Ch to include the contents of the header file **linkbot.h** in the program. The contents made available via **#include** is called a **header** or **header file**. This line appears in every Linkbot program to allow control of the Linkbot through the class **CLinkbotI**. A class is a user defined data type in Ch. The symbol **CLinkbotI** can be used to create a Linkbot-I object. The line

```
CLinkbotI robot;
```

creates **robot** for controlling a Linkbot-I. A class has functions associated with it. The functions associated with a class are called **member functions**. For example, the function **robot.connect()** or **connect()** is a member function of the class **CLinkbotI**. In Program 3.2, member functions of the class **CLinkbotI** are called to control a Linkbot-I. The function call

```
robot.connect();
```

connects the variable **robot** to a Linkbot-I that has been previously configured with the computer as described in Section 2.2 on page 12. Every Linkbot program controlling the Linkbot contains the above statement.

The next line

### 3.2. Move Joints Relative to their Current Positions

```
robot.resetToZero();
```

uses the **resetToZero()** member function to move all of its joints to the zero position, as shown in Figure 2.3. It is equivalent to the Reset To Zero button on the Motion Control Panel in BaroboLink, or pressing both A and B buttons of the Linkbot. This statement is typically used in a program to move all of its joints to the zero position. If the Linkbot is already in the zero position, its joints will not move.

The next line

```
printf("Here comes a robot!\n");
```

displays the following output in the input/output pane.

```
Here comes a robot!
```

The general syntax of the **CLinkbotI** member function **move()** to move two joints of a Linkbot relative to their current positions is as follows.

```
robot.move(angle1, NaN, angle3);
```

It has three arguments for three joints, each representing a joint angle relative to its current positions. Since joint 2 cannot be moved, the argument **NaN** which stands for Not-a-Number is used. The next line

```
robot.move(360, NaN, -360);
```

moves joint 1 by 360 degrees and joint 3 by  $-360$  degrees relative to their current position. Since before the motion caused by this statement, all joints are at zero position by the previous function call of **robot.resetToZero()**, joint 1 of the Linkbot-I rotates 360 degrees and joint 3 rotates  $-360$  degrees. In this way, the robot will move forward.

If the value for a joint angle for the member function **move()** is negative, the joint moves in the opposite direction. For example, the statement

```
robot.move(-360, NaN, 360);
```

would move joint 1 by  $-360$  degrees and joint 3 by 360 degrees relative to their current positions. The robot will move backward.

Note that all member functions of the class **CLinkbotI** for motion including **move()** expect input angles in degrees. In section 7.6, we will learn how to handle joint angles specified in radians.

The last line

```
printf("Cool!\n");
```

displays **Cool!** in the input/output pane.

After your computer is connected to a Linkbot as described in the previous chapter, when Program 3.2 is executed, the following output will be displayed in the input/output pane first,

```
Here comes a robot!
```

Then, the Linkbot-I will make a full rotation for both joints 1 and 3. Finally, the following output will be displayed in the input/output pane.

```
Cool!
```

 Do Exercises 1, 2, 3 on page 37.

#### 3.2.1 Summary

This section summarizes what you should have learned in this session.

### 3.2. Move Joints Relative to their Current Positions

1. Include the header file **linkbot.h** and use the class **CLinkbotI** to declare a variable **robot** by the following two statements

```
#include <linkbot.h>
CLinkbotI robot;
```

2. Call the **CLinkbotI** member function

```
robot.connect();
```

to connect the variable **robot** to a Linkbot-I.

3. Call the **CLinkbotI** member function

```
robot.resetToZero();
```

to move all two joints of a Linkbot to their zero positions.

4. Call the **CLinkbotI** member function

```
robot.move(angle1, NaN, angle3);
```

to move joints 1 and 3 of a Linkbot-I relative to their current positions specified in its first and third arguments.

5. A Linkbot program typically begins with the following statements.

```
#include <linkbot.h>
CLinkbotI robot;
robot.connect();
robot.resetToZero();
```

to declare the variable **robot**, connect it to a Linkbot, and set the Linkbot to the zero position, where all joint angles are at zero degrees.

6. Joint angles in arguments of the **CLinkbotI** member functions, such as **move()**, are specified in degrees.

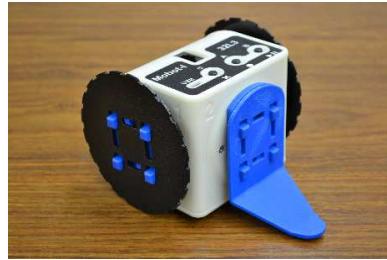
#### 3.2.2 Terminology

**#include <linkbot.h>**, **NaN**, Not-a-Number, header, header file, class, **CLinkbotI**, member function, relative position, **robot.connect()**, **robot.resetToZero()**, **robot.move()**.

#### 3.2.3 Exercises

1. Write a program **move2.ch** to move the two rotating joints of a Linkbot-I two full rotations (hint: one full rotation is 360 degrees) to the position of 720 degrees.
2. Write a program **move3.ch** to make a Linkbot-I turn left by rotating only joint 3 by -360 degrees.
3. Write a program **move4.ch** to make a Linkbot-I turn left fast using by rotating joint 1 by -360 degrees and joint 3 by -360 degrees.

### 3.3 Drive Forward and Drive Backward Relative to its Current Joint Position



A Linkbot-I can be configured as a two-wheel robot. In this case, both joints 1 and 3 can rotate together to roll forward or backward. The member function **driveForward()** causes both joints 1 and 3 to drive the Linkbot-I forward. The syntax of the member function **driveForward()** is as follows.

```
robot.driveForward(angle);
```

The amount to roll the wheels forward relative to their current positions is specified by the argument `angle`. The above member function call is equivalent to the following member function call with **move()**.

```
robot.move(angle, NaN, -angle);
```

The member function **driveBackward()** causes both joints 1 and 3 to roll the Linkbot-I backward. The syntax of the member function **driveBackward()** is as follows.

```
robot.driveBackward(angle);
```

The amount to drive the wheels backward relative to their current positions is specified by the argument `angle`. The above member function call is equivalent to the following member function call with **move()**.

```
robot.move(-angle, NaN, angle);
```

The prefix **drive** for a name of a member function is reserved for member functions to drive a Linkbot-I configured as a two-wheel robot.

```
/* File: driveforward.ch
   Drive forward and backward for Linkbot-I as a two-wheel vehicle */
#include <linkbot.h>
CLinkbotI robot;

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* drive forward by rolling two wheels for 360 degrees */
robot.driveForward(360);

/* drive backward by rolling two wheels for 360 degrees */
robot.driveBackward(360);
```

Program 3.3: Rolling forward and backward as a two-wheel vehicle using **driveForward()** and **driveBackward()**.

### 3.4. Monitor Joint Angles Using the Motion Control Panel

For example, Program 3.3 first drives the Linkbot-I forward 360 degrees for both joints 1 and 3 by

```
robot.driveForward(360);
```

Then, it drives the Linkbot-I backward 360 degrees for both joints 1 and 3 by

```
robot.driveBackward(360);
```

 Do Exercise 1 on page 39.

#### 3.3.1 Summary

1. Call the **CLinkbotI** member function

```
robot.driveForward(angle);
```

to drive a Linkbot-I forward by rolling both joints 1 and 3 with the specified angle, relative to their current positions for both joints.

2. Call the **CLinkbotI** member function

```
robot.driveBackward(angle);
```

to drive a Linkbot-I backward by rolling both joints 1 and 3 with the specified angle, relative to their current positions for both joints.

#### 3.3.2 Terminology

**robot.driveForward()**, **robot.driveBackward()**, move forward, move backward.

#### 3.3.3 Exercises

1. Write a program `driveforward2.ch` to drive backward a Linkbot-I by rolling joints 1 and 3 by 180 degrees, then drive it forward by rolling joints 1 and 3 by 360 degrees.

## 3.4 Monitor Joint Angles Using the Motion Control Panel

When a Linkbot program is executed, you can monitor the motion of its joints in the section of the Joint Position Control on the Motion Control Panel in BaroboLink as shown in Figure 2.12 in section 2.4.1 on page 20. As the Linkbot is moving, the vertical sliders for joints and the joint angles displayed above the sliders will be dynamically updated.

You can run the program `driveforward.ch` in Program 3.3 to monitor the joint angles of the Linkbot on the Motion Control Panel in BaroboLink. When you run the program, joint 1 will move from 0 to 360 degrees first and then back to 0 degree. Joint 3 will move from 0 to -360 degrees first, then back to 0 degree, as you can monitor the change of joint angles on the Motion Control Panel in BaroboLink as shown in Figure 3.7.

When a program is executed in the debug mode by the command `Next` in ChIDE, the program will be executed line by line. The currently executed statement is highlighted in the green color. For example, Figure 3.8 shows that Program 3.3 is executed in the debug mode. The currently executed statement

### 3.4. Monitor Joint Angles Using the Motion Control Panel

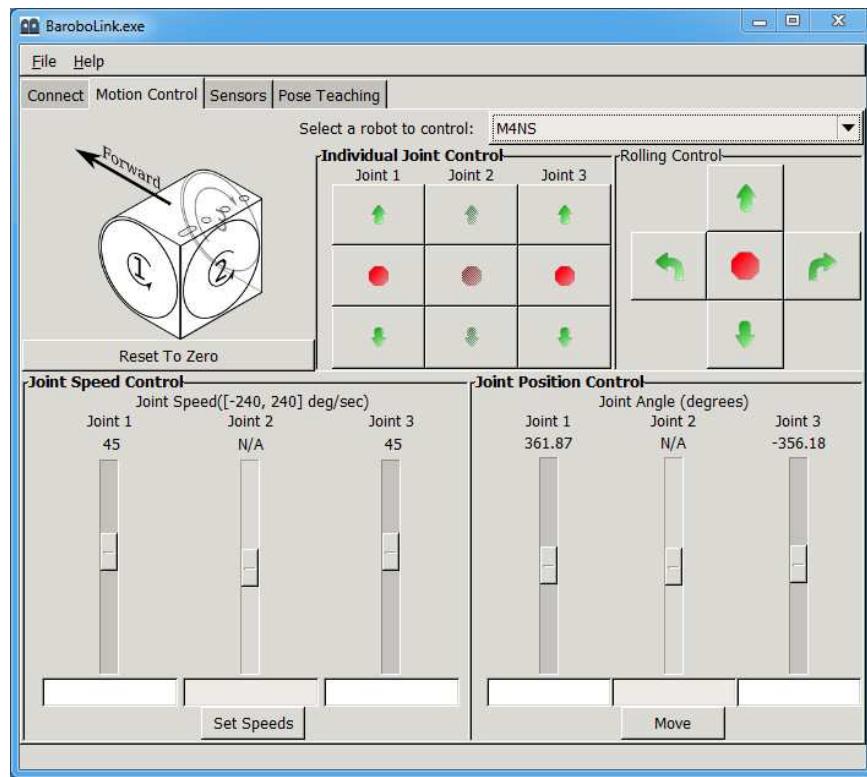


Figure 3.7: Monitoring the movements of joints of a Linkbot on the Motion Control Panel in BaroboLink.

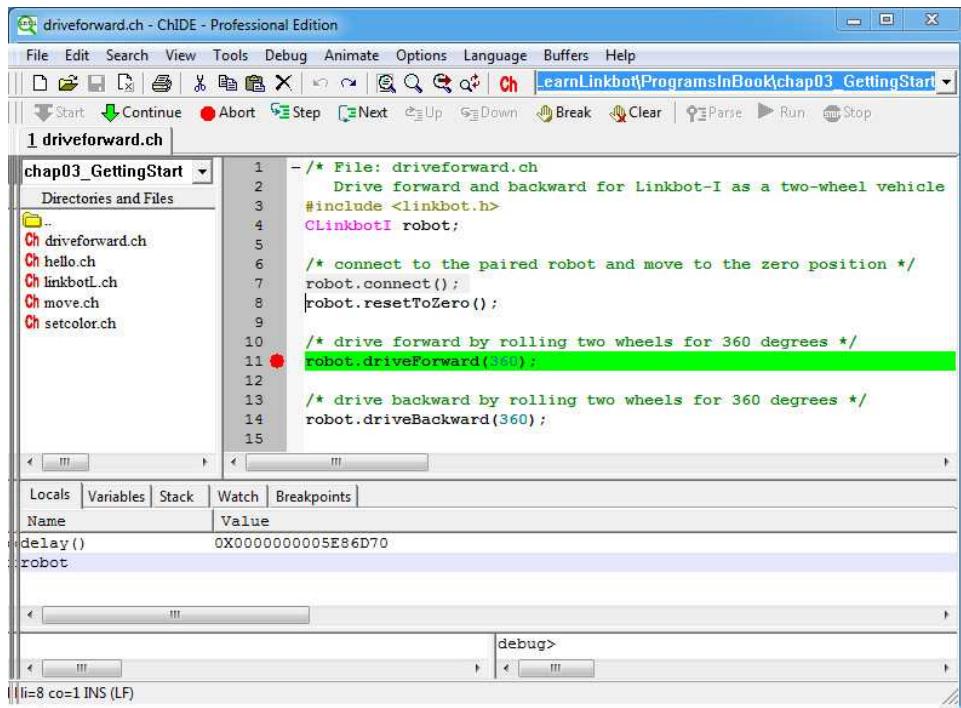


Figure 3.8: Running the program `driveforward.ch` in debug mode.

### 3.5. Set the LED Color

```
robot.driveForward(360);
```

is highlighted in the green color. The joint angles of the Linkbot at this point on the Motion Control Panel on BaroboLink is shown in Figure 3.7. Since the low-cost Linkbot is not high precision, the joint angles may not reach and stay in the exact goal positions. When you monitor the joint angles in BaroboLink, as shown in Figure 3.7, the joints are close to the goal positions. Until you click **Next** to execute the next statement, the joint angles of the robot will remain in their current goal positions.

When a program is executed in the debug mode, the command **Continue** can be clicked to continue the execution of the program until the program ends.

Please note that when BaroboLink is in Motion Control Panel, it constantly communicates with a connected Linkbot to update the positions on the panel. If a class with a large number of Linkbots connected wirelessly to many computers to run programs at the same time, it may jam the communication channel. It is recommended to disable the Motion Control Panel by switching the BaroboLink to Connect Panel for many computers running Ch programs to control Linkbots wirelessly in a classroom.

 Do Exercise 1 on page 41.

#### 3.4.1 Summary

1. Execute a Linkbot program line-by-line using the command **Next** on the debug bar in ChIDE while monitoring joint angles of a Linkbot on the Motion Control Panel in BaroboLink.
2. Use the command **Continue** to finish the execution of the remaining part of the program non-stop.

#### 3.4.2 Terminology

Debug mode, Next, Continue,

#### 3.4.3 Exercises

1. Write a program `monitormotion.ch` to drive a Linkbot-I with the following motion statements.

```
robot.move(360, NaN, -360);
robot.driveForward(360);
robot.driveBackward(720);
```

Run the program in ChIDE in debug mode with the command **Next** on the debug bar, as you monitor the change of joint angles on the Motion Control Panel in BaroboLink.

## 3.5 Set the LED Color

Section 2.3 demonstrated how to change the LED color of a Linkbot through the Sensors Panel of BaroboLink. It is also possible to change the LED color of a Linkbot within a Ch program to add visual effects. Program 3.4 shows an example of how this is done.

### 3.5. Set the LED Color

```
/* File: setcolor.ch
   Set the LED color before and after the movement */
#include <linkbot.h>
CLinkbotI robot;

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* drive forward by rolling two wheels for 360 degrees */
robot.driveForward(360);

/* change the LED color to blue */
robot.setLEDColor("blue");
/* drive backward by rolling two wheels for 360 degrees */
robot.driveBackward(360);

/* change the LED color to red */
robot.setLEDColor("red");
```

Program 3.4: Setting the LED color for a Linkbot-I.

Program 3.4 builds upon Program 3.3 by changing the LED color of the Linkbot-I after it moves forward, and again after it moves backward. The color of a Linkbot-I's LED can be changed using the **CLinkbotI** member function **setLEDColor()**. The general syntax of this member function is as follows.

```
robot.setLEDColor(color);
```

The argument **color** specifies the desired color. A full list of the 137 possible colors that can be used with the member function **setLEDColor()** can be found in Appendix C. If a color other than those listed in Appendix C is used, the LED color remains unchanged and an error message is printed to the input/output pane in ChIDE.

In Program 3.4, after the Linkbot-I moves forward, the line

```
robot.setLEDColor("blue");
```

changes the LED color of the Linkbot-I to blue. And after the Linkbot-I moves backward, the line

```
robot.setLEDColor("red");
```

changes the LED color of the Linkbot-I to red.

 Do Exercise 1 on page 43.

#### 3.5.1 Summary

1. Call the **CLinkbotI()** member function

```
robot.setLEDColor(color);
```

to set the LED color of a Linkbot-I.

#### 3.5.2 Terminology

**robot.setLEDColor()**.

3.6.  Control the Linkbot-L**3.5.3 Exercises**

1. Write a program `setcolor2.ch`, based on Program 3.4, to change the LED color of a Linkbot-I as follows: First, set the LED color to brown and then drive the Linkbot-I forward by 360 degrees. Then set the LED color to green and drive the Linkbot-I backward by 360 degrees. Finally, set the LED color to pink.

**3.6  Control the Linkbot-L**

Figure 3.9: A Linkbot-L.

In the previous chapter, we learned how to control a Linkbot-L using the BaroboLink graphical interface. Similar to controlling a Linkbot-I, a Ch program can be developed to control the Linkbot-L. Program 3.5 contains the code typically used for controlling a Linkbot-L.

```
/* File: linkbotL.ch
   Move joints relative to the current positions for Linkbot-L. */
#include <linkbot.h>
CLinkbotL robot;

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* move joint 1 by 360 degrees and joint 2 by 360 degrees */
robot.move(360, 360, NaN);
```

Program 3.5: A program to control a Linkbot-L.

Like all Linkbot programs, a Linkbot-L program begins with the line

```
#include <linkbot.h>
```

to include the contents of the header file **linkbot.h**. This header file defines both classes **CLinkbotI** and **CLinkbotL** for creating Linkbot-I and Linkbot-L objects, respectively. The line

```
CLinkbotL robot;
```

creates `robot` for controlling a Linkbot-L.

Like all other Linkbot programs, the statement

```
robot.connect();
```

connects the variable `robot` to a Linkbot-L that has been previously configured through the BaroboLink.

The next line

### 3.6. Control the Linkbot-L

```
robot.resetToZero();
```

uses the **resetToZero()** member function to move joints 1 and 2 of the Linkbot-L to the zero position.

The general syntax of the **CLinkbotL** member function **move()** to move joints 1 and 2 of a Linkbot-L relative to their current positions is as follows.

```
robot.move(angle1, angle2, NaN);
```

It has three arguments for three joints, each representing a joint angle relative to its current position. Since joint 3 cannot be moved, the argument **NaN** which stands for Not-a-Number is used. The next line

```
robot.move(360, 360, NaN);
```

moves both joints 1 and 2 by 360 degrees relative to their current positions.

Most member functions for **CLinkbotI** are available for **CLinkbotL**. They are handled similarly for both Linkbot-I and Linkbot-L. The major difference is that the Linkbot-I uses joints 1 and 3 whereas the Linkbot-L uses joints 1 and 2. In general, all ideas and concepts for programming Linkbot-I are applicable to Linkbot-L. Therefore, in the remaining part of this manuscript, the presentation will focus on the Linkbot-I.

However, since the Linkbot-I can be treated as a two-wheel vehicle, member functions **driveForward()**, **driveBackward()**, **turnLeft()**, **turnRight()**, and **driveDistance()** are available for the class **CLinkbotI** only. We will learn the member function **driveDistance()** in section 5.4.

 Do Exercises 1 and 2 on page 44.

#### 3.6.1 Summary

1. Include the header file **linkbot.h** and use the class **CLinkbotL** to declare a variable **robot** by the following two statements

```
#include <linkbot.h>
CLinkbotL robot;
```

for controlling a Linkbot-L.

2. Call the **CLinkbotL** member function

```
robot.move(angle1, angle2, NaN);
```

to move joints 1 and 2 of a Linkbot-L relative to their current positions specified in its first and second arguments.

#### 3.6.2 Terminology

**CLinkbotL**.

#### 3.6.3 Exercises

1. Write a program **linkbotL2.ch** to move the two rotating joints of a Linkbot-L two full rotations of 720 degrees.
2. Write a program **linkbotL3.ch** to rotate joint 2 by  $-360$  degrees for a Linkbot-L.

## 3.7. Control a Linkbot Wirelessly Without Connecting with a USB Cable

## 3.7 Control a Linkbot Wirelessly Without Connecting with a USB Cable

The BaroboLink in a computer can control one or multiple Linkbots. One Linkbot needs to be connected to the computer through the USB cable. For controlling multiple Linkbots, the Linkbot connected to the computer through the USB cable will act as a dongle for the BaroboLink to connect and control other Linkbots through the ZigBee wireless communication, as shown in Figure 3.10. The other Linkbots in the network can be located as far as 100 meters.



Figure 3.10: The configuration for the BaroboLink to control multiple Linkbots, with one Linkbot connected to a computer through a USB cable.

If you move the Linkbot with the serial number 7TQX acting as a dongle at the bottom in the list under the “Connect” tab as shown in Figure 3.11, the Linkbot with the serial number 9418 listed at the top, without being connected through the USB cable, can be controlled by a program wirelessly. Multiple Linkbots at the top can also be controlled by a program. Also, you do not even need to connect the Linkbot acting as a dongle in BaroboLink so long as it is connected physically through the USB cable, as shown in Figure 3.11.

### 3.7. Control a Linkbot Wirelessly Without Connecting with a USB Cable

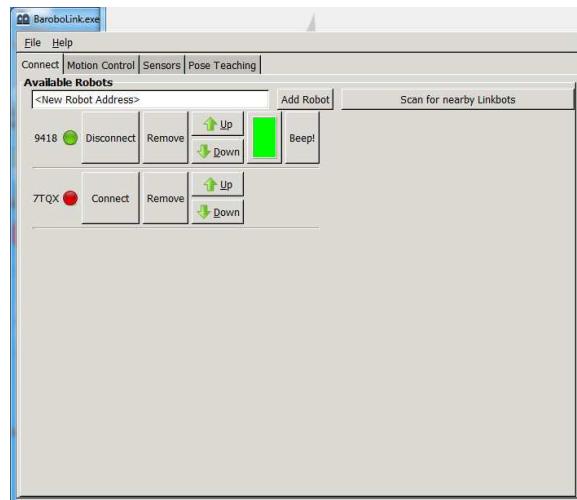


Figure 3.11: Controlling the Linkbot with the serial number 9418 wirelessly while the Linkbot with the serial number 7TQX acting as a dongle.

Do Exercise 1 on page 46.

#### 3.7.1 Summary

1. Control a Linkbot wirelessly without connecting to a USB cable.

#### 3.7.2 Terminology

wireless, dongle.

#### 3.7.3 Exercises

1. Use a Linkbot as a dongle connected through a USB cable to a computer. Control another Linkbot wirelessly using a program developed previously.

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## CHAPTER 4

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# Robot Simulation with RoboSim

**RoboSim** is a robot simulation environment, developed by the UC Davis C-STEM Center, for programming Barobo Mobots and Linkbots. Almost any program that can control hardware Barobo robots, except for programs using a controller robot, can be used to run virtual robots in RoboSim without any modification. Also any program that can control virtual robots in RoboSim, except for the coordinate system programs in Appendix B, can be run on hardware Barobo robots without any changes. RoboSim can be freely downloaded from the C-STEM web site at <http://c-stem.ucdavis.edu>.

### 4.1 RoboSim GUI

RoboSim can be conveniently launched by double clicking its icon  on the desktop. The RoboSim graphical user interface (GUI), shown in Figure 4.1, allows the user to change between hardware and virtual robots when a Ch robot program is executed. There is no save button within the GUI, all changes made are automatically saved.

## 4.1. RoboSim GUI

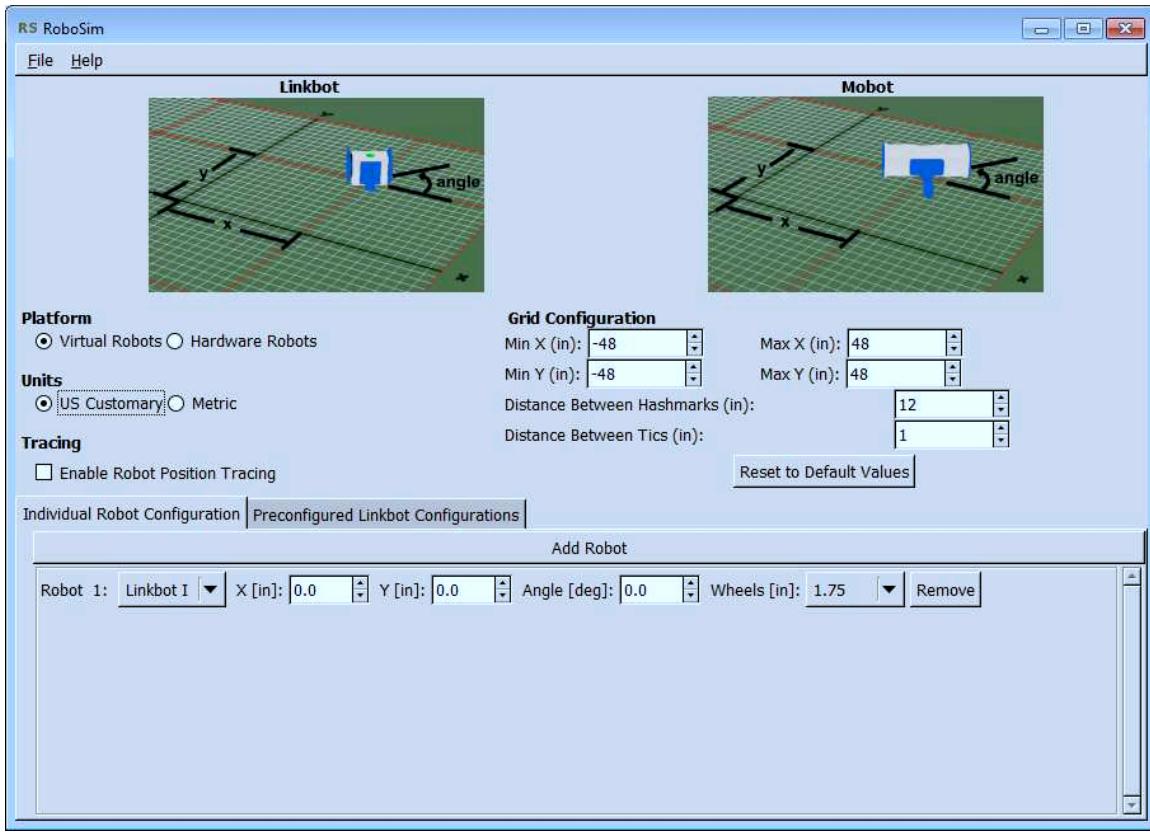


Figure 4.1: The RoboSim GUI.

### 4.1.1 Platform

The **Platform** entry, as shown in Figure 4.2, allows the user to decide whether a Ch program controls the hardware or virtual robots. Each time a new Ch program is started, it will check the setup based on this entry. For a Ch robot program to control a virtual robot, check the box for **Virtual Robots**. If the box for **Hardware Robots** is checked, a Ch program will control the physical hardware robots.



Figure 4.2: The entry for selecting a simulation or hardware platform.

### 4.1.2 Units

Simulations within RoboSim can be run either in **US Customary** units consisting of inches, degrees, and seconds or **Metric** units with centimeters, degrees, and seconds. Changing units will effect the grid spacing drawn beneath the robots and the spacing between robots. Changing between these two options will change

## 4.1. RoboSim GUI

the labels within the GUI to indicate the units being used.

### 4.1.3 Tracing

**Tracing** where robots have been can be enabled by selecting the check box “Enable Robot Position Tracing”, as shown in Figure 4.1. When the tracing is enabled, green lines for robot trajectories will be drawn for each robot. Once a simulation is running, the tracing line can be enabled or disabled by pressing the ‘t’ key.

### 4.1.4 Grid Configuration

To be able to see how far robots have moved, a grid is enabled under the robots. There are six options to alter the layout of the grid lines under the **Grid Configuration**. The minimum and maximum extends of the grid for both the X and Y directions can be specified individually. Rectangular grids of any size can be created in any of the quadrants. Hashmarks are the red lines drawn within the configuration images. By default, the distance between two hashmarks is 12 inches in US Customary units and 50 centimeters in Metric units. Tics are the most frequent lines drawn in a light gray. By default, the distance between two tics is 1 inch in US Customary units and 5 centimeters in Metric units.

Switching between US Customary and Metric units will change these default values to logical starting points for the metric system. The ‘Reset to Defaults’ button will allow the default values for both US Customary and Metric to be reinstated after they have been changed. Depending upon which units are currently selected from Section 4.1.2, either the US Customary defaults, shown in Figure 4.3, or the Metric defaults, as shown in Figure 4.4, will be set.

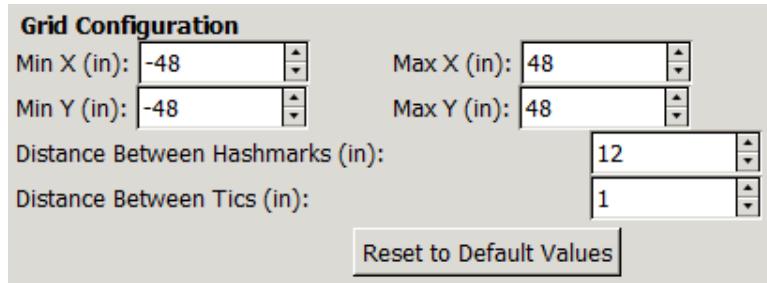


Figure 4.3: The default grid spacing in the US Customary units.

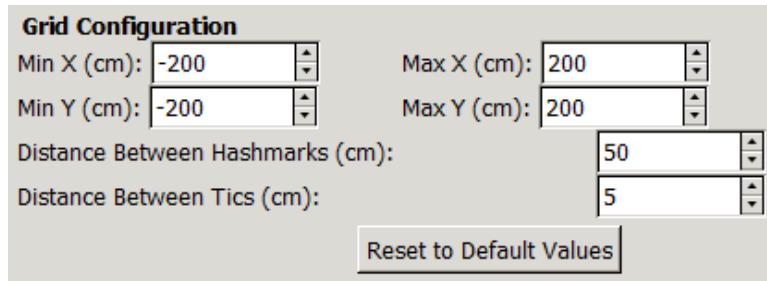


Figure 4.4: The default grid spacing in the Metric units.

## 4.1. RoboSim GUI

### 4.1.5 Individual Robot Configuration

Initial robot configurations can either be done through the **Individual Robot Configuration** or **Preconfigured Linkbot Configuration** section. The **Individual Linkbot Configuration** section, as shown in Figure 4.5, has options to allow robots to be positioned within the RoboSim scene either with or without wheels but not attached to each other.

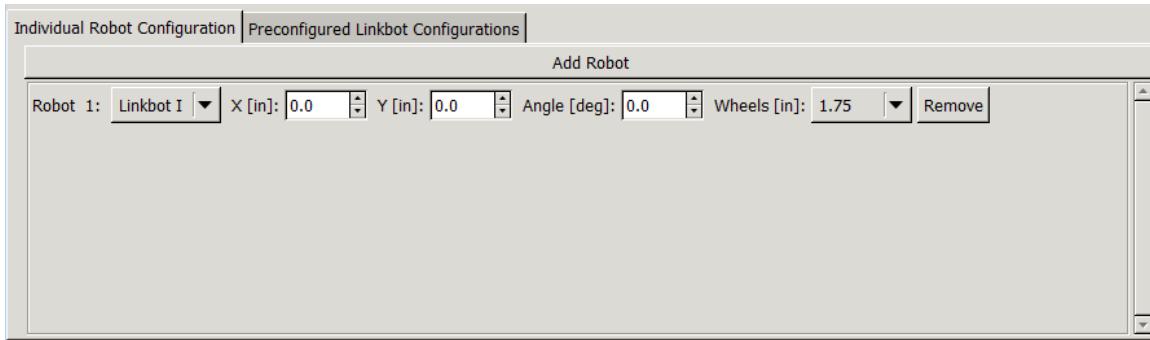


Figure 4.5: Individual robot configuration dialog.

The user can specify the x and y coordinates as well as the orientation angle of a virtual robot. Images for the Linkbot and Mobot showing the meaning of each of the options are displayed above the configuration box. They are screenshots of the virtual robots positioned at one foot in both the x and y coordinates with the orientation angle of 30 degrees from the x-axis.

Initially, the individual robot list is empty, but it can be populated by the 'Add Robot' button below the configuration images. Clicking this button each time will add a robot into the RoboSim, each offset from the previous one in the x-direction by 6 inches or 15 centimeters depending upon the units selected. The order within the robot list will be the order in which the robots will be read into the simulation program.

#### Robot Type

There are three options for robot type available. Linkbot-I, Linkbot-L, and Mobot. The options are presented in a drop down menu as shown in Figure 4.6.

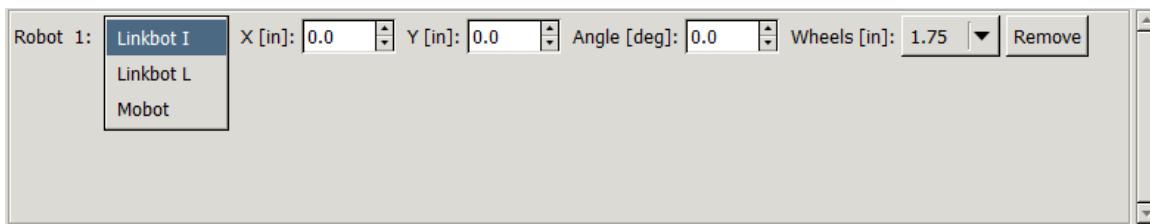


Figure 4.6: Picking a robot type.

#### Robot Position

Both x and y coordinates can be chosen independently for each robot.

## 4.1. RoboSim GUI

### Robot Angle

The rotation angle from the x-axis can be used for changing the direction of the movement for the robot or the orientation of two robots respective to each other.

### Wheels

Since so many times the robots are run with wheels and a caster connected, a drop down menu is provided to select different wheel sizes. The options listed are the radii of the wheels typically used with Linkbots. Each wheel is drawn with a series of dots along the one radius to easily show the rotation of the wheel. The correlation between wheel radius and number of dots is given in Table 4.1.

Number of Dots	Wheel Radius
2	custom radius
3	1.625 inch / 4.13 centimeter
4	1.75 inch / 4.45 centimeter
5	2.00 inch / 5.08 centimeter

Table 4.1: Wheel sizes and number of dots.

Custom wheel sizes are available by using the 'Custom' option from the drop down menu. This option creates an input box to the right to let the user enter a wheel radius.

### Remove

A robot can be removed from the RoboSim by clicking the 'Remove' button.

#### 4.1.6 Preconfigured Linkbot Configurations

In addition to positioning robots independently within the RoboSim, some **Preconfigured Linkbot Configurations**, as shown in Figure 4.7, which represent commonly used Linkbot configurations are available to the user. Selecting one of these options will display a picture of the configuration built with the hardware Linkbots, corresponding to a Ch robot program presented in Chapter 13. When one of these options is selected, the specific configuration for this setup is passed into Ch and robots specified in the individual robot configuration are ignored. To switch back to the individual configuration, just unselect the selected preconfigured robot configuration.

## 4.1. RoboSim GUI



Figure 4.7: Preconfigured robot configurations with Linkbots.

Do Exercise 1 on page 52.

### 4.1.7 Summary

1. Select simulation or hardware mode in a RoboSim GUI for controlling robots from a Ch program.
2. Select US Customary units with inches, degrees, and seconds or Metric units with centimeters, degrees, and seconds for RoboSim.
3. Add robots to the RoboSim. The information for a robot includes robot type (Linkbot-I, Linkbot-L, or Mobot), the x and y coordinates as well as the orientation angle with respect to the x-axis for the robot, attached wheels of different sizes to the robot.
4. Remove a robot from the RoboSim
5. Use Preconfigured Linkbot Configurations to run a robotic system with multiple connected Linkbots.
6. Set grid lines in the RoboSim scene with the US Customary units or Metric units.
7. Enable or disable the tracing of robot trajectories.

### 4.1.8 Terminology

RoboSim, RoboSim GUI, simulation, units, US Customary units, Metric units. robot type, x and y coordinates, orientation, grids for x and y coordinate systems, tracing robot trajectory.

### 4.1.9 Exercises

1. (a) Launch a RoboSim GUI.  
 (b) Add a Linkbot-I to the RoboSim at the x and y coordinates (6, 0) inches with an orientation angle of 30 degrees with respect to the x-axis, attach wheels with the radius of 1.75 inches to joints 1 and 3.  
 (c) Set the x and y coordinate system on the RoboSim scene. The total distance for x and y directions are 48 inches (4 feet) each. The distance between each Hashmark is 6 inches. The distance between each tics is 1 inch.  
 (d) Track the robot trajectory when the robot moves.

## 4.2. Run a Ch Program with RoboSim

## 4.2 Run a Ch Program with RoboSim

Once the simulation environment has been configured with the RoboSim GUI in Section 4.1, the user can run Ch programs in ChIDE to control the virtual robots. The RoboSim GUI should remain open while simulating robots. Once it is closed, the system will revert to hardware mode. The RoboSim scene with virtual robots for each simulation are created upon running a Ch program. For example, when the Ch program `driveforward3.ch`, listed in Program 4.1, is executed, a RoboSim scene shown in Figure 4.8 will be displayed. The message

Paused: Press any key to start

is displayed in the RoboSim scene to reminder the user that the virtual robot will not move until the user presses any key on the keyboard. This gives the user an opportunity to examine the RoboSim scene before the motion begins.

```
/* File: driveforward3.ch
   Drive forward for Linkbot-I as a two-wheel vehicle */
#include <linkbot.h>
CLinkbotI robot;

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* drive forward by rolling two wheels for 360 degrees */
robot.driveForward(360);
```

Program 4.1: Moving a Linkbot forward.

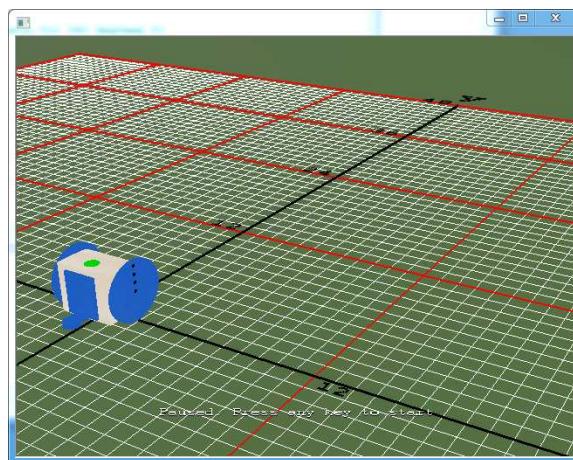


Figure 4.8: A RoboSim scene with a virtual robot at its starting position.

While a robot is moving in the RoboSim scene, the user can press any key to pause the motion of the robot. When the motion is paused, the message

## 4.2. Run a Ch Program with RoboSim

Paused: Press any key to restart

will be displayed in the RoboSim scene. The user can press any key to restart the motion.

When the user presses the 't' key, the robot trajectory is traced in a green line in the RoboSim scene as shown in Figure 4.9.

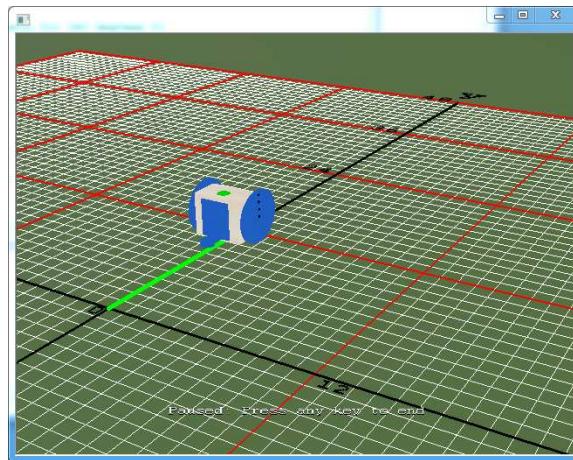


Figure 4.9: A RoboSim scene with a virtual robot and its trajectory traced.

Do Exercise 1 on page 55.

The default green color for both LED and trajectory of a robot can be changed by the member function **setLEDColor()** in a program as shown in Program 4.2.

```
/* File: setcolor3.ch
   Change the color of the LED and trajectory of the robot to red */
#include <clinkbot.h>
CLinkbotI robot;

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* change the color of the LED and trajectory to red */
robot.setLEDColor("red");

/* drive forward by rolling two wheels for 360 degrees */
robot.driveForward(360);
```

Program 4.2: Change the color of the LED and trajectory of a robot to red.

When the program is finished, the message

Paused: Press any key to end

will be displayed in the RoboSim scene. Pressing any key, the RoboSim scene will disappear.

Do Exercise 2 on page 55.

## 4.3. Interact with a RoboSim Scene

**4.2.1 Summary**

1. Run a Ch program to control a virtual robot in RoboSim.
2. Press the 't' key to trace the robot trajectory.
3. Press any key to pause and restart the motion of a robot in the RoboSim scene.

**4.2.2 Terminology**

RoboSim scene, tracing robot trajectories.

**4.2.3 Exercises**

1. (a) Write a Ch program `driveforward5.ch` to driving a Linkbot-I forward by rotating both joints 1 and 3 for 720 degrees.  
 (b) Based on the setup on the RoboSim GUI described in Exercise 1 on page 52, run the program `driveforward5.ch` to simulate the motion of the robot in RoboSim.  
 (c) When the robot is moving in the RoboSim scene, press a key on the keyboard to pause the motion of the robot. Then, press a key to restart the motion.  
 (d) When the robot is moving in the RoboSim scene, press the 't' key to toggle the tracing of the robot trajectory. Press the 'n' key to toggle the tgrid numbering.
2. Modify the program `driveforward5.ch` in Exercise 1 as the program `setcolor4.ch` to change the color of the LED and trajectory to blue.

## **4.3 Interact with a RoboSim Scene**

The user can interact with a RoboSim scene through the keyboard and mouse.

**4.3.1 Keyboard Input**

The RoboSim scene responds to keyboard input as outlined in Table 4.2.

key	action
1	set the camera to the default view
2	set the camera to the overhead view
n	Toggle grid line numbering
r	Toggle robot visibility and enable tracing
t	Toggle robot tracing
any other key	Pause and restart the motion

Table 4.2: Keyboard input for the RoboSim scene.

As described in the previous sections, the 't' key will toggle the tracing of robot trajectories. In addition the 't' key, a few other keys can be used to change the view of the RoboSim scene.

### 4.3. Interact with a RoboSim Scene

There are two views available to the user. The default view, which can be toggled with the '1' key, is from behind the robots looking into the first quadrant. This view can be seen in all RoboSim scene screenshots in this book, except for Figure 4.10 which shows the overhead view. The '2' key moves the camera directly above the origin looking down on the scene creating a 2D viewpoint of the robots.

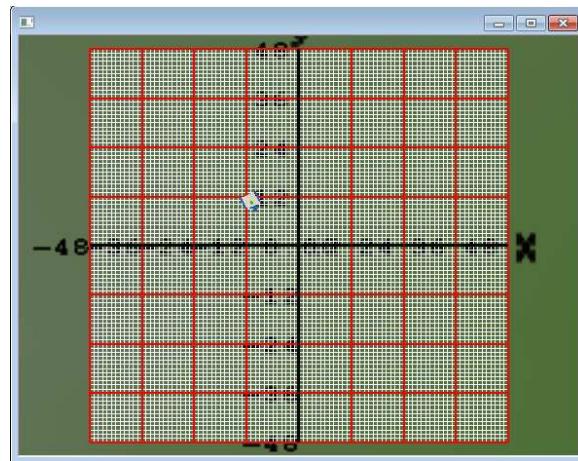


Figure 4.10: A RoboSim scene with the overhead viewing angle.

The 'n' key allows the user to toggle the display of the grid numbering. X and Y numbering is by default enabled and given for every hashmark on the grid.

The 'r' key will toggle the display of virtual robots or robot trajectories. This feature is useful when the user would like to view a trajectory traced by a robot without the virtual root blocking the trajectory. When two virtual robots collide in a RoboSim scene, the program will stop working properly. However, without showing the virtual robots, the collision will not happen. This is useful for solving math problems such as two robots intercepting. Figure 4.11 shows a RoboSim scene with a traced robot trajectory only, without the robot displayed.

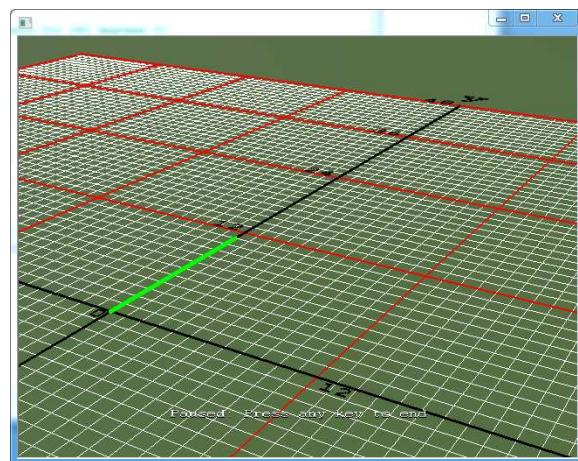


Figure 4.11: A RoboSim scene with a traced robot trajectory only.

### 4.3. Interact with a RoboSim Scene

As described in the previous section, the motion of robots in the RoboSim scene can be paused and restarted by pressing any other key on the keyboard.

#### 4.3.2 Mouse Input

Clicking on a robot in a RoboSim scene will enable a pop up which displays the robot number and the current position of the robot, as shown in Figure 4.12 with the position (0, 10.9817) inches for the x and y coordinates for robot 1.

Clicking again, the displayed position for the robot will disappear.

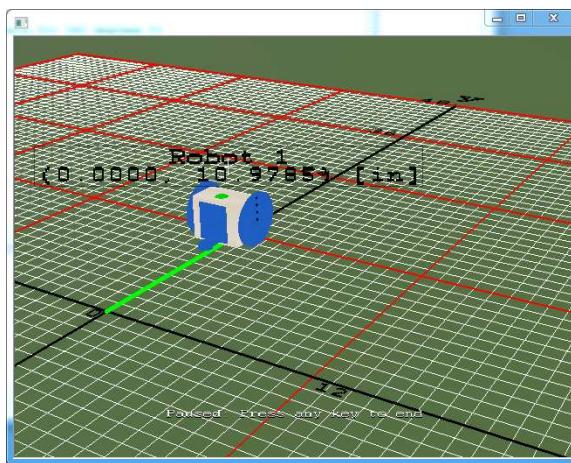


Figure 4.12: A RoboSim scene with a virtual robot and its position displayed.

The user can execute a Ch robot program in debug mode in ChIDE, line by line, with the command **Next**, as described in section 3.4. At the end of each motion statement, the user can click the robot in the RoboSim scene to obtain the x and y coordinates of the robot. The ability to obtain the x and y coordinates of a robot during its motion along a trajectory can be very useful for learning many math concepts. For example, the Ch program `driveforward4.ch`, listed in Program 4.3, drives forward a Linkbot-I twice by calling the member function **driveForward()** twice, the user can run the program in ChIDE in debug mode to find the distance traveled by each call. When the first **driveForward()** is finished, the user can click on the robot to find the x and y coordinates. The y coordinate is the distance traveled by the robot.

### 4.3. Interact with a RoboSim Scene

```
/* File: driveforward4.ch
   Drive forward twice for Linkbot-I as a two-wheel vehicle */
#include <linkbot.h>
CLinkbotI robot;

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* drive forward by rolling two wheels for 360 degrees */
robot.driveForward(360);

/* drive forward by rolling two wheels for 360 degrees again */
robot.driveForward(360);
```

Program 4.3: Driving a Linkbot forward by calling the member function **driveForward()** twice.

The mouse can be used to move the camera around the scene. Holding the left mouse button and dragging the mouse pans the camera as outlined in Table 4.3. Holding the right mouse button and dragging the mouse enables scaling of the view by zooming in and out. Holding both left and right mouse buttons and dragging changes the location of the camera within the scene.

The ground plane is for reference only. The ground plane will disappear when viewing the robots from below so that the user can inspect the movement from all angles.

<b>button</b>	<b>action</b>
Hold left mouse button and drag	Rotate camera
Hold right mouse button and drag	Zoom in and out
Hold both left and right buttons, and drag	Pan around scene
Click on a robot	Display the robot position

Table 4.3: Mouse input for the RoboSim scene.

 Do Exercise 2 on page 59.

#### 4.3.3 Summary

1. Press the 'r' key to toggle the robot visibility and tracing the robot trajectory.
2. Hold the left mouse button and drag the mouse to have different view points.
3. Hold the right mouse button and drag the mouse to zoom in and out.
4. Hold both left and right mouse buttons, and drag the mouse to scale the scene.
5. Click on a robot to display the x and y coordinates of the robot.

#### 4.3.4 Terminology

x and y coordinates for a robot.

## 4.3. Interact with a RoboSim Scene

**4.3.5 Exercises**

1. (a) Run the Ch program `driveforward5.ch` developed in Exercise 1 on page 59 in RoboSim. When the robot is moving in the RoboSim scene, press the key 'r' to toggle the visibility of the robot. When the robot is finished its motion, press the key 'r' to toggle the visibility of the robot.  
(b) Hold the left mouse button and drag the mouse to have different view points.  
(c) Hold the right mouse button and drag the mouse to zoom in and out.  
(d) Hold both left and right mouse buttons, and drag the mouse to scale the scene.  
(e) Click on a robot to display the x and y coordinates of the robot.
2. Write a Ch program `driveforward6.ch` to drive a Linkbot-I forward by rotating both joints 1 and 3 for 720 degrees using the member function **driveForward()**. Then, dirve the robot backward by rotating both joints 1 and 3 for 360 degrees using the member function **driveBackward()**. Run the program in ChIDE in debug mode by clicking the command **Next** on the ChIDE. Click on the robot to obtain the positions of the robot when the robot stops its driving forward and backward.

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## CHAPTER 5

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# Interacting with a Linkbot at Runtime through Variables and Input/Output Functions

## 5.1 Use Variables

Variables are often used in solving problems with unknown values. Variables are also a powerful tool available to programmers. Using variables to represent mathematical notation makes a program easier to modify and read. They can be used to solve complicated problems. They can also be used to obtain the information from the user at the runtime for interactive computing. Variables are also commonly used in robot programming for solving applied problems.

However, a variable has to be declared and associated with a proper data type before it can be assigned a value. In this chapter, declaration and use of variables involving commonly used data types for robot programming are described. We will also learn how to move a robot with the specified distance and radius for two wheels.

Table 5.1: Commonly used data types and their usage.

Data Type	Usage	Examples
<b>double</b>	decimals	123.4567
<b>int</b>	integers	12

### 5.1.1 Declaration of Variables and Data Type **double** for Decimals

An *identifier* is a sequence of lowercase and uppercase letters, digits, and underscores. A variable has to be declared before it can be used inside a program. A variable is declared by specifying its data type and identifier in the form

```
type name;
```

where *type* is one of the valid data types, such as **double** and **int**, and *name* is a valid identifier. For example, the statements

```
double t;           // the traveling time in seconds
double distance;   // distance traveled
```

declare variables *t* and *distance* of **double** type. In this case, **double** is a keyword as a declarator for a data type and *t* and *distance* are identifiers as variable names. The symbol *//* comments out any subsequent text located on the same line.

The difference between lowercase and uppercase letters is important. In other words, variables are case sensitive. The initial character of an identifier must not be a digit. A reserved word, such as **double** and **for**, cannot be used as an identifier. Using meaningful and consistent identifiers for variable names makes a program easier to understand, develop, and maintain. A variable name typically uses lowercase letters. Table 5.2 shows some invalid identifiers.

Table 5.2: Examples of invalid identifiers.

Invalid identifier	Reason
int	reserved word
double	reserved word
for	reserved word
2times	starts with a digit
integer#	character # not allowed
girl&boy	character & not allowed
class1+class2	character + not allowed

Multiple variables of the same type can be declared in a single statement by a list of identifiers, each separated by a comma, as shown below for two variables *t* and *distance* of **double** type.

```
double t, distance; // declare variables t and distance
```

The names *x*, *y*, *z*, *length*, *width*, *radius*, *speed*, and *distance* are used in common practice for variables of **double** type to hold decimal numbers.

### 5.1.2 Initialization

Assigning a value to a declared variable for the first time is called **initializing the variable**. You can initialize a variable in the same statement in which it is declared or you can initialize it in a separate statement. For example:

## 5.1. Use Variables

```
double t = 5.5; // declare t double type and initialize it with 5.5
and
```

```
double t; // declare t double type
t = 5.5; // initialize t with 5.5
```

accomplish the same goal of declaring a variable *t* of double type initializing it to 5.5.

### 5.1.3 Data Type **int** for Integers

Variables of **double** type can store decimals. Integers can be stored in a variable of **int** type. For example;

```
int i = 2; // declare variable i of int type and initialize it with 2
int n; // declare variable n of int type
n = 4+i; // assign n with 4+i
```

The names *i*, *j*, *k*, *m*, *n*, *num*, and *count* are used in common practice for variables of **int** type.

## Application: Calculating the Distance of a Robot Traveled

### Problem Statement:

A robot travels at the constant speed of 2.5 inches per second. The distance traveled by this robot can be expressed as follows:

$$\text{distance} = 2.5t$$

where *distance* is measured in inches from the starting point and *t* is time in seconds. Therefore, if you want to know where the robot is at any time, you will take the number of seconds and multiply that by 2.5. Let's write a program to calculate the distance when the traveling time *t* for the robot is 5.5 seconds.

We will examine the source code for this program step-by-step. We will need some variables in the program to represent variables in the equation  $\text{distance} = 2.5t$ . Since the values for distance and time can be decimals we will declare them both as **double** types.

```
double t; // the traveling time in seconds
double distance; // distance traveled
```

We also know that we are looking at the problem when 5.5 seconds have passed, or *t* = 5.5, so we can initialize the variable *t* in the program.

```
t = 5.5; // 5.5 seconds for traveling time
```

To make our program actually do something, we need to tell it how to calculate the distance

```
distance = 2.5 * t; // calculate the distance traveled
```

Note that the operators '+' and '-' in a program can be used for addition and subtraction operations in the same manner as in math. However, the program does not recognize proximity as multiplication. The multiplication operator '\*' is needed for a multiplication operation. The division operator '/' is used for a division operation.

## 5.1. Use Variables

Finally, we want to show the answer to the user by calling the function `printf()` similar to how we used it in `hello.ch` in Program 3.1. There are some additional features needed for this `printf()` function that will be explained in section 5.2. For now, accept that "%lf" is replaced by the value of the variable `distance`.

```
printf("The distance traveled by the robot is %lf inches.\n", distance);
```

Thus, the final source code will look like Program 5.1. When Program 5.1 is executed, the following output will be displayed in the input/output pane.

```
The distance traveled by the robot is 13.750000 inches.
```

The computation result from Program 5.1 will be verified experimentally using a robot program presented in Program 9.9 on page 137.

```
/* File: distance.ch
   Calculate the distance of a robot traveled at 2.5 inches per second. */
double t;           // the traveling time in seconds
double distance;   // distance traveled

t = 5.5;           // 5.5 seconds for traveling time

distance = 2.5 * t; // calculate the distance traveled
printf("The distance traveled by the robot is %lf inches.\n", distance);
```

Program 5.1: Calculating and printing the distance of a robot traveled using `printf()`.

In Program 5.1, for simplicity and consistency with the mathematical notations, the variables `t` and `distance` represent the time and distance, respectively. Comments for these variables are added in the declaration of these variables to make their intended use more clear. Using variables to represent mathematical notations make a program easier to modify and more readable. It is especially helpful for solving problems with complicated logic.

 Do Exercise 1 on page 65.

## Application: Using Variables for Joint Angles

### Problem Statement:

Write a program `angles.ch` to rotate joint 1 by 360 degrees and joint 3 by -360 degrees relative their current positions. Use variables to hold the joint angles.

Based on Program 3.2, we can develop the program `angles.ch` in Program 5.2. As pointed out in the previous section, a robot program typically begins with the following statements.

```
#include <linkbot.h>
CLinkbotI robot;
```

to declare the variable `robot`.

Since joint angles are decimal values, in this program, variables `angle1` and `angle3` of **double** type are declared and assigned with the joint angles by the statements below.

## 5.1. Use Variables

```
double angle1 = 360; // declare variable 'angle1' for joint1 with 360 degrees
double angle3 = -360; // declare variable 'angle3' for joint3 with -360 degrees
```

These variables are used as arguments of the function **move()**.

The statements

```
robot.connect();
robot.resetToZero();
```

connect the variable `robot` to a Linkbot, and set the Linkbot to the zero position, where all joint angles are at zero degrees.

The statement

```
robot.move(angle1, NaN, angle3);
```

moves joints 1 and 3 by the angles specified in the arguments `angle1` and `angle3`, respectively. Program 5.2 behaves the same as Program 3.2.

```
/* File: angles.ch
   Use variables to hold joint angles */
#include <linkbot.h>
CLinkbotI robot;
double angle1 = 360;    // declare variable 'angle1' for joint1 with 360 degrees
double angle3 = -360;   // declare variable 'angle3' for joint3 with -360 degrees

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

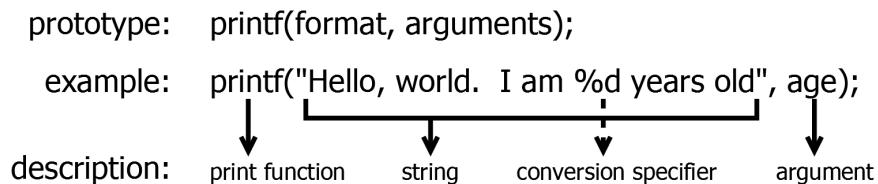
/* rotate joint1 by angle1 and joint3 by angle3 */
robot.move(angle1, NaN, angle3);
```

Program 5.2: Using variables for joint angles.

 Do Exercises 2 and 3 on page 65.

### 5.1.4 Summary

1. Reserved words. The words **int** and **double** are reserved words in Ch.
2. The data type **double** is for decimal numbers. Variable names `x`, `y`, and `z` are usually used for **double** type.
3. The data type **int** is for integers. Variable names `i`, `j`, `k`, `n`, and `m` are usually used for **int** type.
4. Learn how to use variables and variable names (identifiers).
5. Before a variable is used, it has to be declared with the data type **double** or **int**.
6. Choose descriptive names for variables.
7. Variable names are case sensitive. `x` and `X` are two different variable names.
8. Variables can be used in algebraic expressions.
9. Add a comment in a program starting with `//` till the end of the line.
10. Use the operators `'+'`, `'-'`, `'*'`, and `'/'` for the arithmetic operations of addition, subtraction, multiplication, and division, respectively.

5.2. The Output Function **printf()**Figure 5.1: A format for using the function **printf()** and an example.**5.1.5 Terminology**

algebraic equations, case sensitive, declare variables, **double**, evaluation, identifier, initialization, initialize variables, **int**, name, reserved words, variable

**5.1.6 Exercises**

1. A joint of a robot rotates at the constant speed of 90 degrees per second. The joint angle can be expressed as follows:

$$\text{angle} = 90t$$

where *angle* is measured in degrees from the starting point and *t* is time in seconds. Write a program *jointangle.ch* to calculate the joint angle of the robot 4.5 seconds after the robot starts its motion.

2. Write a program *jointangles.ch* to control a Linkbot-I. The program shall use variables *angle1* and *angle3* to hold the joint angles 360 and -360 degrees for joints 1 and 3, respectively. The program calls the function **move()** with these two variables as arguments to move the joints by the specified angles relative to their current positions.
3. Based on the program *driveforward.ch*, presented in Program 3.3 on page 38, write a program *driveforward3.ch* to control a Linkbot. The program shall use a variable *angle* to hold a joint angle of 360 degrees. The program calls the function **driveForward()** with the variable *angle* to move the robot forward.

## 5.2 The Output Function **printf()**

The **input/output**, or **I/O**, refers to the communication between a computer program and input/output devices. The inputs are the data received by the program. The outputs are the data produced by the program. In the previous section, we used the output function **printf()** to display the output from the program *hello.ch*, as shown in Figure 3.2, and the program *distance.ch* in Program 5.1. In this section, we will learn more about the output function **printf()**. We will learn the input function **scanf()** in the next section.

The function **printf()** can be used to print text and data to the input/output pane. A general form of the function **printf()** and a sample application are shown in Figure 5.1. The format in the first argument is a string. This format string can contain an object called a conversion specifier, such as "%lf" and "%d". A **conversion specifier** tells the program to replace that object with the value of the expression of specific type that follows the string. The expression can be a constant or variable. For instance, in Program 5.1 the line

```
printf("The distance traveled by the robot is %lf inches.\n", distance);
```

## 5.2. The Output Function `printf()`

contains the conversion specifier "%lf" which is replaced with the value of variable `distance` when the program is run. The printed output thus becomes:

```
The distance traveled by the robot is 13.750000 inches.
```

Table 5.3 lists the conversion specifiers we will use along with the data type they represent. The conversion specifier "%lf" is used to print a decimal number or the value of a variable of **double** type. The conversion specifier "%d" is used to print an integer number or the value of a variable of **int** type.

Table 5.3: Conversion specifiers for the functions `printf()` and `scanf()`.

Data Type	Format
<b>double</b>	"%lf"
<b>int</b>	"%d"

The conversion specifier "%lf" prints out a decimal with six digits after the decimal point. Using the wrong conversion specifier will give an incorrect result. For example, using "%d" for the decimal number 12.345 or variables of **double** type, and "%lf" for the integer 10 or variables of **int** type will give incorrect results. For example, the code below should use the conversion specifier "%lf" instead of "%d".

```
double speed = 10.5;
printf("%d", 10.5);           // incorrect.
printf("%d", speed);         // incorrect.
```

### 5.2.1 Precision of Decimal Numbers

By default, the conversion specifier "%lf" prints out a decimal number with six digits after the decimal point. When a decimal number is used to represent currency, we want to have two digits after the decimal point for cents. We can accomplish this by specifying the precision of the output. The **precision** of a decimal number specifies the number of digits after the decimal point. The precision typically takes the form of a period (.) followed by an integer. For example, the conversion specifier "% .2lf" specifies the precision with two digits after the decimal point. The number after the specified amount is rounded to the nearest value. For example, with the conversion specifier "% .2lf", the decimal number 12.1234 is printed as 12.12 with the precision value of 2, whereas 12.5678 is printed as 12.57.

### Application: Calculating the Cost for Buying the Ice Cream



## 5.2. The Output Function `printf()`

### Problem Statement:

The sale price of ice cream is \$0.47 per ounce. Write a program `icecream.ch` to calculate the cost of buying 5.5 ounces of ice cream.

Program 5.3 can calculate the cost for buying ice cream. The math formula to calculate the cost of buying the ice cream at \$0.47 per ounce is

$$\text{cost} = 0.47 * \text{weight}$$

```
/* File: icecream.ch
   Calculate the cost for 5.5 ounces of the ice cream.
   The ice cream is sold by weight. $0.47 per ounce. */

/* declare variables weight and cost */
double weight, cost;

/* initialize weight in lb */
weight = 5.5;

/* calculate the cost*/
cost = 0.47 * weight;

/* display the cost as output */
printf("The ice cream costs $%.2lf \n", cost);
```

Program 5.3: Calculating the cost for purchasing ice cream.

Program 5.3 declares two variables `weight` and `cost`, assigns the weight, and calculates the cost by the following statements.

```
double weight, cost; // weight and cost of the yogurt are declared
weight = 5.5; // weight is assigned the value 5.5
cost = 0.47 * weight; // cost is calculated
```

The cost is displayed using the following statement with the function `printf()`.

```
printf("The ice cream costs $%.2lf \n", cost);
```

The conversion specifier "% .2lf" is used to print the cost to the nearest cent, two digits after the decimal point. When Program 5.3 is executed, the following output will be displayed in the input/output pane.

```
The ice cream costs $2.58
```

 Do Exercises 1 and 2 on page 68.

### 5.2.2 Summary

1. Use the output function `printf()` with the conversion specifier "%lf" for decimal numbers with six digits after the decimal point and "%d" for integers. For example,

```
printf("distance = %lf\n", f);
```

### 5.3. Input into Programs Using Function **scanf()**

- ```
printf("n = %d\n", n);
```
2. Use the precision of the output function **printf()** for decimal numbers. The conversion specifier "%.#lf" is used for precision of decimal numbers where "#" is replaced by a whole number for printing a decimal number with "#" number of digits after the decimal point.
  3. Write programs with the output function **printf()** to solve applied problems.

#### 5.2.3 Terminology

character string, conversion specifier, conversion specifier "%lf", conversion specifier "%d", copy program, format string, I/O, input, output, precision, **printf()**

#### 5.2.4 Exercises

1. What's wrong with the following code and how do you correct it?

```
int n = 10;
printf("n is %lf\n", n);
```

2. The sale price of frozen yogurt is \$0.39 per ounce. Write a program **yogurt.ch** to calculate the cost of buying 4.5 ounces of frozen yogurt.

## 5.3 Input into Programs Using Function **scanf()**

In the previous section, we learned how to produce the output from a program using the function **printf()**. In this section, we will learn how to write a program to accept the input values from the user. Therefore, the same program can be used to solve the same problems with different data. The function **scanf()** is used to input data to a program from the standard input, which is usually the keyboard. The input function **scanf()** can set a variable with the value from the user input. The conversion specifiers listed in Table 5.3 can also be used for the function **scanf()** in the form of

```
scanf("%lf", &x);
```

for a variable **x** of **double** type and

```
scanf("%d", &n);
```

for a variable **n** of **int** type. The address operator '&', preceding a variable name, obtains the address of the variable so that the value from the user input can be stored in the variable. **For the function scanf(), you must use & before the variable name or you will get an error.**

### Application: An Ice Cream Shop

#### Problem Statement:

Write a program **icecream2.ch** for an Ice Cream Shop to process the sale of ice cream.  
The sale price for ice cream is \$0.47 per ounce.

5.3. Input into Programs Using Function **scanf()**

```

/* File: icecream2.ch
   Calculate the cost for the ice cream */

/* declare variables weight and cost */
double weight, cost;

/* get the user input for the value of the variable weight */
printf("Welcome to the Amazing Ice Cream Shop\n");
printf("We sell ice cream by weight, $0.47 per ounce.\n");
printf("Enter the weight in ounces.\n");
scanf("%lf", &weight);

/* calculate the cost */
cost = 0.47 * weight;

/* display the cost as output */
printf("The ice cream costs $%.2lf \n", cost);
printf("Thank you.\n");

```

Program 5.4: Using the function **scanf()** to input the weight of ice cream.

Program 5.4 can be used to process the purchase of ice cream. Like the program `icecream.ch` in Program 5.3, it declares two variables `weight` and `cost`. When the program is executed, the user enters the weight of the ice cream in ounces to be purchased to the variable `weight` through the function **scanf()**. After the program obtains the weight input from the user, the cost is calculated by multiplying the weight with 0.47. The conversion specifier `"%.2lf"` is used to print the cost to the nearest cent with two digits after the decimal point. An interactive execution of Program 5.4 through the input/output pane is displayed below:

```

Welcome to the Amazing Ice Cream Shop
We sell ice cream by weight, $0.47 per ounce.
Enter the weight in ounces.
5
The ice cream costs $2.35
Thank you.

```

In this execution, the value 5 for the weight in ounces is entered after the prompt.

If a program is used interactively, it is important that a message be displayed before the function **scanf()** is called so that the user of the program is asked to input data accordingly, as shown by the statement `"Enter ..."`

 Do Exercise 1 on page 71.

### Application: Controlling a Linkbot with the User Input Joint Angles



5.3. Input into Programs Using Function **scanf()****Problem Statement:**

Write a program `angles_p.ch` to control a Linkbot-I with joint angles for joints 1 and 3 input by the user at runtime.

```
/* File: angles_p.ch
   User inputs the values for joint angles for joints 1 and 3 */
#include <linkbot.h>
CLinkbotI robot;
double angle1; // declare variable 'angle1' to value for joint 1
double angle3; // declare variable 'angle3' to value for joint 3

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* User input angle1 and angle3 */
printf("Enter the angle to rotate joint1\n");
scanf("%lf", &angle1);
printf("Enter the angle to rotate joint3\n");
scanf("%lf", &angle3);

/* rotate joint1 by angle1 and joint3 by angle3 */
robot.move(angle1, NaN, angle3);
```

Program 5.5: Using the function **scanf()** to input joint angles.

Based on Program 5.2, we can develop the program `angles_p.ch` in Program 5.5. Unlike Program 5.2, joint angles `angle1` and `angle3` for joints 1 and 3, respectively, are obtained from the user at the runtime through the input function **scanf()**. An interactive execution of Program 5.5 is shown below.

```
Enter the angle to rotate joint1
180
Enter the angle to rotate joint3
-360
```

In this case, joint 1 rotates 180 degrees whereas joint 3 rotates  $-360$  degrees. Since both joints rotate at the same default speed of 45 degrees per second, joint 1 will stop moving first. We will learn how to set the joint speed in Chapter 7.

 Do Exercises 2 and 3 on page 71.

### 5.3.1 Summary

1. Use the input function **scanf()** with the conversion specifier "`%lf`" for variables of **double** type and "`%d`" for variables of **int** type. The symbol ‘&’ must precede a variable name. For example,

```
scanf ("%lf", &weight);
```

2. Write programs with the input/output functions to solve applied problems.

## 5.4. Move a Distance for a Two-Wheel Robot

**5.3.2 Terminology**

address operator &, buffer, copy program, **scanf()**

**5.3.3 Exercises**

1. Write a program `yogurt2.ch` for a Yogurt Shop to process the sale of frozen yogurt. The sale price for frozen yogurt is \$0.39 per ounce.
2. Write a program `angles.p2.ch` to control a Linkbot-I. The program shall use variables `angle1` and `angle3` to get the joint angles from the user at runtime through the function **scanf()**. Then use the member function **move()** with these two variables as arguments to move the joints by the user specified angles. Test the program with the joint angles of 360 and -360 degrees for joints 1 and 3, respectively.
3. Modify the program `driveforward3.ch` developed in Exercise 3 on page 3 as a new program `driveforward4.p.ch` to control a Linkbot. The program shall use a variable `angle` to get the joint angles from the user at runtime through the function **scanf()**. The program calls the function **driveForward()** with the variable `angle` to drive the Linkbot forward. Test the program with the joint angle 360 degrees.

## 5.4 Move a Distance for a Two-Wheel Robot

A Linkbot-I can be configured as a two-wheel robot as shown in Figure 5.2. In this configuration, the faceplates for joints 1 and 3 are attached with two wheels. Joints 2 and 3 are locked by a caster to serve as passive contacting point while the two wheels rotating. In this section, we will learn how to use the member function **driveDistance()** to control a Linkbot-I as a two-wheel robot. More advanced control of a two-wheel robot will be described in Chapter 9.

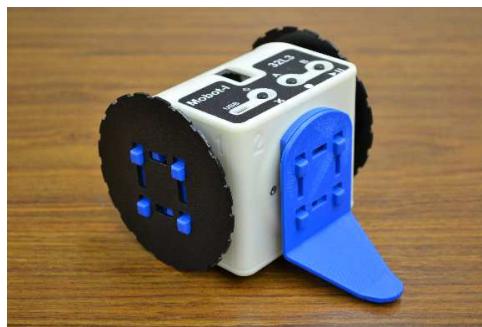


Figure 5.2: A two-wheel robot.

Like the member function **driveForward()**, the member function **driveDistance()** causes both faceplates (joints 1 and 3) to roll the Linkbot-I forward. The syntax of the member function **driveDistance()** is as follows.

```
robot.driveDistance(distance, radius);
```

## 5.4. Move a Distance for a Two-Wheel Robot

Unlike the member function **driveForward()**, the distance for the Linkbot-I to drive forward is specified by the first argument **distance**. The radius of the two wheels, attached to the joints of the Linkbot-I, is specified by the second argument **radius**. The units for both distance and radius must be the same. They can be inches, feet, centimeters, meters, etc.

```
/* File: drivendistance.ch
   Drive a robot as a two-wheel robot for a given distance. */
#include <linkbot.h>
CLinkbotI robot;
double distance=5; // the distance of 5 inches to drive forward
double radius=1.75; // the radius of 1.75 inches of the two wheels of the robot

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* drive forward for 'distance' in inches with a specified radius of wheels */
robot.driveDistance(distance, radius);
```

Program 5.6: Moving a Linkbot-I with a specified distance using **driveDistance()**.

For example, Program 5.6 drives a Linkbot-I configured as a two-wheel robot with wheels attached to joints 1 and 3. The radius of each wheel is 1.75 inches. The program drives the Linkbot-I forward for 5 inches. by the statement

```
robot.driveDistance(distance, radius);
```

If the first argument for distance for the member function **driveDistance()** is negative, a Linkbot will drive backward.

 Do Exercises 1 and 2 on page 72.

### 5.4.1 Summary

1. Call the **CLinkbotI** member function

```
robot.driveDistance(distance, radius);
```

to drive a Linkbot-I forward by the specified distance and radius for two wheels relative to its current position.

### 5.4.2 Terminology

**robot.driveDistance()**, **robot.driveBackward()**, **distance**, **move a distance**, **radius of a wheel**.

### 5.4.3 Exercises

1. Write a program **drivendistance2.ch** to control a Linkbot-I. The program calls the function **driveDistance()** to drive the robot forward for 6 inches, then drive the robot backward for 5 inches. Assume the radius of wheels is 1.75 inches.

## 5.5. Turn Left and Turn Right

2. Write a program `drivedistance3_p.ch` to control a Linkbot-I. The program shall use variables `distance` and `radius` to get the distance and radius of two-wheels from the user at runtime through the function `scanf()`. The program calls the function `driveDistance()` with the variables `distance` and `radius` to drive the Linkbot forward. Test the program with the distance 6 inches and radius of 1.75 inches. You can also test the program with wheels of different radius.

## 5.5 Turn Left and Turn Right

The `CLinkbotI` class contains several other member functions with useful preprogrammed motions. The member function `turnLeft()` turns a two-wheel toward left with the syntax as follows.

```
robot.turnLeft(angle, radius, trackwidth);
```

The amount turned by the robot is specified in the argument `angle` in degrees. The second argument is the radius of the two wheels. The third argument is the **track width**, the distance between the two wheels as shown in Figure 5.3. In order to turn the robot with the correct angle, the radius of the two-wheels and the track width need to be specified. The units for both radius and track width must be the same. They can be inches, feet, centimeters, meters, etc.



Figure 5.3: The track width for a two-wheel robot.

Similar to the member function `turnLeft()`, the member function `turnRight()` turns a robot toward right with the syntax as follows.

```
robot.turnRight(angle, radius, trackwidth);
```

The amount turned by the robot is specified in the argument `angle` in degrees. The second argument is the radius of the two wheels. The third argument is the track width.

```
/* File: turn.ch
   Turn left and turn right */
#include <linkbot.h>
CLinkbotI robot;
double radius = 1.75;      // radius of 1.75 inches
double trackwidth = 3.69;  // the track width, the distance between two wheels

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

robot.driveForward(360);
robot.turnRight(90, radius, trackwidth);
robot.driveForward(360);
robot.turnLeft(90, radius, trackwidth);
robot.driveForward(360);
```

Program 5.7: Turning left and turning right.

For example, Program 5.7 rolls a Linkbot-I forward for 360 degrees, turns right for 90 degrees, rolls forward for another 360 degrees, turns left for 90 degrees, then rolls forward for 360 degrees again.

You can run the program in ChIDE in debug mode with the command Next on the debug bar to watch the action of each motion statement, as you monitor the change of joint angles on the Motion Control Panel in BaroboLink.

 Do Exercises 1 and 2 on page 75.

At this point, you may read section B.1 in Appendix B on how to use the member function **drivexyTo()** only available in RoboSim. This member function provides the motions of the member functions **turnLeft()** or **turnRight()** with **driveDistance()**.

### 5.5.1 Summary

1. Call the **CLinkbotI** member function

```
robot.turnLeft(angle, radius, trackwidth);
```

to turn a Linkbot-I toward left with the specified angle, radius for two wheels, and track width.

2. Call the **CLinkbotI** member function

```
robot.turnRight(angle, radius, trackwidth);
```

to turn a Linkbot-I toward right with the specified angle, radius for two wheels, and track width.

### 5.5.2 Terminology

**robot.turnLeft()**, **robot.turnRight()**, turn left, turn right.

### 5.5.3 Exercises

1. Write a program `turn2.ch` to drive a Linkbot-I forward for 360 degrees, turn left for 180 degrees, drive forward for 360 degrees, turn right for 180 degrees, and roll forward for 360 degrees.
2. Run the program `turn2.ch` developed in Exercise 1 in ChIDE in debug mode with the command `Next` on the debug bar, as you monitor the change of joint angles on the Motion Control Panel in BaroboLink.

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## CHAPTER 6

---

# Writing Programs to Control a Group of Linkbots to Perform Identical Tasks

## 6.1 Control a Group of Linkbots with Identical Movements

By using groups, Linkbots can be synchronized easily using only a few lines of code.



(a) 1st Linkbot

(b) 2nd Linkbot

Figure 6.1: Control two Linkbots to perform identical tasks simultaneously.

## 6.1. Control a Group of Linkbots with Identical Movements

```
/* File: group.ch
   Control multiple robot modules simultaneously using the CLinkbotIGroup class */
#include <linkbot.h>
CLinkbotI robot1, robot2;
CLinkbotIGroup group; // the robot group

/* add the two modules as members of the group */
group.addRobot(robot1);
group.addRobot(robot2);

/* connect to the robots in the group.
   move robots in the group to the zero position */
group.connect();
group.resetToZero();

group.driveForward(360); // drive robots forward
group.driveBackward(360); // drive robots backward
```

Program 6.1: Controlling a group of Linkbots with identical movements.

Program 3.3 on page 38 controls a single Linkbot-I to roll forward by 360 degrees and then roll backward by 360 degrees. Program 6.1 performs identical movements for two Linkbot-Is in the same manner as Program 3.3.

After declaring a separate variable for each of the two Linkbot-Is, the line

```
CLinkbotIGroup group;
```

creates a variable `group` of class **CLinkbotIGroup**. The class **CLinkbotIGroup** is defined in the header file **linkbot.h**, just as the classes **CLinkbotI** and **CLinkbotL** are. The general syntax of the **CLinkbotIGroup** member function **addRobot()**, which is used to add a Linkbot-I to a group, is as follows:

```
group.addRobot(name);
```

The argument `name` represents the variable name of the Linkbot-I that you want to add to the group. The next two lines

```
group.addRobot(robot1);
group.addRobot(robot2);
```

adds each Linkbot-I object to the group, one at a time. After these statements are executed, the variable `group` will be used to control both `robot1` and `robot2` at the same time. You can add any number of Linkbot-Is to a group.

The class **CLinkbotIGroup** includes member functions that are similar to those included in the classes **CLinkbotI** and **CLinkbotL**. Examples of such member functions include **connect()**, **resetToZero()**, **driveForward(angle)**, and **driveBackward(angle)**. In later sections we will see additional examples of such functions. The **CLinkbotIGroup** versions of these member functions have one important difference: they move all the Linkbot-Is in a group identically, instead of only a single Linkbot-I. It is more convenient to be able to write one line of code to move all the Linkbot-Is in a single group than it is to write a separate line of code for each Linkbot-I.

For instance, the statement

```
group.connect();
```

is similar to the statement **robot.connect()** from Program 3.3. The only difference is that instead of connecting just one Linkbot-I to a variable, **group.connect()** connects both variables `robot1` and `robot2` to Linkbot-Is that have been configured through the BaroboLink.

The next line

## 6.1. Control a Group of Linkbots with Identical Movements

```
group.resetToZero();
```

is similar to the statement **robot.resetToZero()** seen in Program 3.3. But instead of resetting the joints of only one Linkbot-I, **group.resetToZero()** resets the joints of both `robot1` and `robot2` to the zero position.

Finally, the lines

```
group.driveForward(360);
group.driveBackward(360);
```

cause both `robot1` and `robot2` to roll forward at the same time by 360 degrees and then roll backward at the same time by 360 degrees, just as **robot.driveForward(angle)** and **robot.driveBackward(angle)** did for a single Linkbot-I in Program 3.3.

 Do Exercises 1, 2, and 3 on page 79.

### 6.1.1 Summary

1. Include the header file **linkbot.h** and use the class **CLinkbotIGroup** to declare a variable group by the following two statements

```
#include <linkbot.h>
CLinkbotIGroup group;
```

for controlling a group of Linkbot-Is.

2. Call the **CLinkbotIGroup** member function

```
group.addRobot(name);
```

to add a single Linkbot-I to a group.

3. Call the **CLinkbotIGroup** member function

```
group.connect();
```

to connect all variables in a group to their corresponding Linkbot-Is through Barobolink.

4. Call the **CLinkbotIGroup** member function

```
group.resetToZero();
```

to reset the joints of all Linkbot-Is in a group to the zero position.

5. Call the **CLinkbotIGroup** member functions

```
group.driveForward(angle);
group.driveBackward(angle);
```

to drive all Linkbot-Is in a group forward or backward by the same specified angle, relative to their current positions.

### 6.1.2 Terminology

**CLinkbotIGroup**, **group.addRobot()**, **group.connect()**, **group.resetToZero()**, **group.driveForward()**, **group.driveBackward()**, groups, identical movements.

### 6.1.3 Exercises

1. Run the program `group.ch` in Program 6.1 to perform identical movements for two Linkbots.
2. Write a program `group2.ch` to perform identical movements, as presented in Program 6.1, for three Linkbots.



3. Write a program `group3.ch` to perform identical movements, as presented in Program 6.1, for four Linkbots.



## 6.2 Control an Array of Linkbots with Identical Movements

Another way to add multiple robots to a group is to use an array of robots. This is demonstrated in Program 6.2 below.

## 6.2. Control an Array of Linkbots with Identical Movements

```

/* File: grouparray.ch
 * A group with 4 Linkbot-I's in synchronized motion using an array of 4 elements.
 *
 *      1      2
 *      |--|    |--|
 *      |__|    |__|
 *
 *      3      4
 *      |--|    |--|
 *      |__|    |__|
 *
 * Make sure that robots are attached with wheels. */

#include <linkbot.h>

CLinkbotI robot[4];      /* declare an array of 4 Linkbot-I's */
CLinkbotIGroup group;    /* declare a Linkbot-I group */
double radius = 1.75;    // radius of 1.75 inches
double trackwidth = 3.69; // the track width, the distance between two wheels

group.addRobots(robot);  /* add 4 Linkbot-I's to the group */
group.connect();
group.resetToZero();

group.driveForward(360);
group.driveBackward(360);
group.turnLeft(90, radius, trackwidth);
group.driveForward(360);
group.driveBackward(360);
group.turnLeft(45, radius, trackwidth);
group.driveForward(360);
group.driveBackward(360);
group.turnRight(135, radius, trackwidth);
group.driveDistance(5, radius);
group.driveDistance(-5, radius);

```

Program 6.2: Controlling a group of four Linkbot-Is with identical movements using an array of 4 elements.

Chapter 6. Writing Programs to Control a Group of Linkbots to Perform Identical Tasks  
6.2. Control an Array of Linkbots with Identical Movements



Figure 6.2: A group of four Linkbots with identical movements.

Program 6.2 performs identical movements for four Linkbot-Is using an array with 4 elements. In this program, instead of declaring a separate variable for each Linkbot-I, we declare one variable for multiple Linkbot-Is. The line

```
CLinkbotI robot[4];
```

declares an array of 4 Linkbot-Is. An **array** is a special kind of variable that stores a collection of individual values that are of the same data type. Each item in the collection can be accessed by using an index number. Arrays are useful because instead of having to separately store related information in different variables, you can store them as a collection in just one variable. The general syntax for declaring an array is as follows

```
type name [num];
```

where num specifies the number of elements you want in the array. This number can be any positive integer value.

In particular, an array comes in handy in our program for use with the **CLinkbotIGroup** member function **addRobots()**. The syntax for this new function is

```
group.addRobots(name);
```

where name refers to an array of Linkbot-Is, instead of just one Linkbot-I. With this member function, we can add all of our robots to a group at once, instead of one at a time like we did in Program 6.2. For instance, the line

```
group.addRobots(robot);
```

adds the array of four Linkbot-Is to the group with just one line of code. This is easier than using four lines of code to add four Linkbot-Is to the group.

With Program 6.2 we discovered that the class **CLinkbotIGroup** has its own versions of the member functions **connect()**, **resetToZero()**, **driveForward()**, and **driveBackward()**. Now we can add three more member functions to this list: **turnLeft()**, **turnRight()**, and **driveDistance()**. The line

```
group.turnLeft(90, radius, trackwidth);
```

turns not just one Linkbot-I but all four Linkbot-Is left by 90 degrees at the same time. Similarly, the line

```
group.turnRight(135, radius, trackwidth);
```

## 6.2. Control an Array of Linkbots with Identical Movements

turns all four Linkbot-Is 135 degrees right. The statements

```
group.driveDistance(5, radius);
group.driveDistance(-5, radius);
```

drive all Linkbot-Is in the group forward by 5 inches first, then backward by 5 inches.

 Do Exercises 1 and 2 on page 82.

### 6.2.1 Summary

1. Declare an array variable to store a group of Linkbot-Is.

```
CLinkbotI robot[4];
```

The number in square brackets is the number of Linkbot-Is in the group. This number can be any positive integer value.

2. Call the **CLinkbotIGroup** member function

```
group.addRobots(name);
```

to add an array of Linkbot-Is to a group. In this case `name` is the array name (identifier) instead of a single variable name.

3. Call the **CLinkbotIGroup** member functions

```
group.turnLeft(angle, radius, trackwidth);
group.turnRight(angle, radius, trackwidth);
```

to turn a group of Linkbot-Is left or right with the specified angle, radius for two wheels, and track width.

4. Call the **CLinkbotIGroup** member function

```
group.driveDistance(distance, radius);
```

to drive a group of Linkbot-Is by the `distance` with the specified `radius` for two wheels.

### 6.2.2 Terminology

array, **group.addRobots()**, **group.turnLeft()**, **group.turnRight()**, **group.driveDistance()**.

### 6.2.3 Exercises

1. Run the program `grouparray.ch` in Program 6.2 to perform identical movements for 4 Linkbots.
2. Write a program `grouparray2.ch` to control a group of 9 Linkbots with the same motion as presented in the program `grouparray.ch` in Program 6.2.

## 6.2. Control an Array of Linkbots with Identical Movements



Figure 6.3: A group of 9 Linkbots with identical movements.

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## CHAPTER 7

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# Writing Programs to Control a Single Linkbot with Different Motion Characteristics

In the previous chapters, we learned the member functions `robot.connect()`, `robot.resetToZero()`, `robot.move()`, `robot.driveForward()`, `robot.driveBackward()`, `robot.driveDistance()` `robot.turnLeft()`, `robot.turnRight()`, and of the class `CLinkbotI` for controlling the Linkbot-I. In this chapter, we will learn more features of the Linkbot-I and additional member functions to control the Linkbot-I for various applications.

### 7.1 Multiple Motion Statements in a Program

A Linkbot program can contain multiple motion statements. For example, Program 7.1 has three motion statements. The program first moves all joints into the zero position by the member function `resetToZero()`. It then calls the member function `move()` three times. The first function call

```
robot.move(180, NaN, -180);
```

moves joint 1 by 180 degrees and joint 3 by  $-180$  degrees relative to the zero position. The second time when

```
robot.move(180, NaN, -180);
```

is called, joint 1 moves by 180 degrees and joint 3 by  $-180$  degrees relative to their current position. After this function call, the absolute positions of joint 1 is 360 degrees and joint 3 is  $-360$  degrees. The function call

```
robot.move(360, NaN, -360);
```

## 7.2. Move Joints to their Absolute Positions

```
/* File: multiplemove.ch
   Move all joints relative to the current positions . */
#include <linkbot.h>
CLinkbotI robot;

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* move the joint 1 by 180 degrees and joint 3 by -180 degrees */
robot.move(180, NaN, -180);

/* move the joint 1 by 180 degrees and joint 3 by -180 degrees */
robot.move(180, NaN, -180);

/* move the joint 1 by 360 degrees and joint 3 by -360 degrees */
robot.move(360, NaN, -360);
```

Program 7.1: Moving joints relative to the current position using **move()**.

moves joint 1 by 360 degrees and joint 3 by  $-360$  degrees relative to the current position. At the end of the program, the absolute positions of joint 1 is 720 degrees and joint 3 is  $-720$  degrees.

 Do Exercise 1 on page 85.

### 7.1.1 Summary

This section summarizes what you should have learned in this session.

1. Call the **CLinkbotI** member function

```
robot.move(angle1, NaN, angle3);
```

multiple times to move a Linkbot-I.

### 7.1.2 Terminology

multiple movements.

### 7.1.3 Exercises

1. Write a program `multiplemove2.ch` to move a Linkbot-I forward by 360 degrees and then backward by 360 degrees using the function **move()** only.

## 7.2 Move Joints to their Absolute Positions

The member function **move()**, first presented in section 3.2, can be used to move joints of a Linkbot relative to their current positions. Similar to **move()**, the member function **moveTo()** can move joints of a Linkbot to its specified absolute positions. The syntax of the member function **moveTo()** is as follows.

## 7.2. Move Joints to their Absolute Positions

```
robot.moveTo(angle1, NaN, angle3);
```

The function uses the first and third arguments for joints 1 and 3, respectively, each representing an absolute position of a joint.

```
/* File: moveto.ch
Move all joints to the absolute positions. */
#include <linkbot.h>
CLinkbotI robot;

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* move joints 1 to 180 degrees and joint 3 to -180 degrees */
robot.moveTo(180, NaN, -180);

/* move joints 1 to 360 degrees and joint 3 to -360 degrees */
robot.moveTo(360, NaN, -360);

/* move joints 1 to 720 degrees and joint 3 to -720 degrees */
robot.moveTo(720, NaN, -720);
```

Program 7.2: Calling **moveTo()** multiple times.

For example, Program 7.2 has three motion statements using the member function **moveTo()**. As indicated in the comments, the following statements

```
/* move joint 1 to 180 degrees and joint 3 to -180 degrees */
robot.moveTo(180, NaN, -180);

/* move joint 1 to 360 degrees and joint 3 to -360 degrees */
robot.moveTo(360, NaN, -360);

/* move joint 1 to 720 degrees and joint 3 to -720 degrees */
robot.moveTo(720, NaN, -720);
```

first move joint 1 to 180 degrees and joint 3 to  $-180$  degrees. As soon as the joints reach these positions, joint 1 is commanded to move to the position of 360 degrees and joint 3 to the position of  $-360$  degrees. Subsequently, joint 1 is moved to the position of 720 degrees and joint 3 to the position of  $-720$  degrees. When you run the program, joints 1 and 3 appear continuously moving from 0 to 720 degrees.

The motion of Program 7.2 using the member function **moveTo()** is the same as that of Program 7.1 using the member function **move()**. When you run these programs, joint 1 appears continuously moving from 0 to 720 degrees whereas joint 3 moving from 0 to  $-720$  degrees. You can monitor the change of joint angles on the Motion Control Panel in BaroboLink as described in section 3.4. You can execute the program in debug mode by the command **Next** in ChIDE to watch the action of each motion statement.

 Do Exercises 1, 2, 3, and 4 on page 87.

### 7.2.1 Summary

1. Call the **CLinkbotI** member function

```
robot.moveTo(angle1, NaN, angle3);
```

to move joints 1 and 3 of a Linkbot-I to their absolute positions.

### 7.3. Get Joint Angles

#### 7.2.2 Terminology

absolute position, **robot.moveTo()**.

#### 7.2.3 Exercises

1. What is the difference between the member functions **moveTo()** and **move()**.
2. Write a program **moveto2.ch** to move joints 1 and 3 forward by 360 degrees and then backward by 360 degrees using the function **moveTo()** only.
3. Write a program **moveto3.ch** to first move joints 1 and 3 to the absolute positions of 90 degrees. Then, move joint 1 by 45 degrees and joint 3 by 90 degrees relative to its current position. Finally, move joints 1 and 3 to the absolute positions of 360 degrees.
4. Run the program **moveto3.ch** developed in Exercise 3 in ChIDE in debug mode with the command **Next** on the debug bar, as you monitor the change of joint angles on the Motion Control Panel in BaroboLink.

## 7.3 Get Joint Angles

#### 7.3.1 Get a Joint Angle

After a Linkbot is moved through several motion statements, you may want to know the current angular position of a joint of the Linkbot. The member function **getJointAngle()** can be used to obtain a joint angle of a Linkbot. The syntax of the member function **getJointAngle()** is as follows.

```
robot.getJointAngle(id, angle);
```

The first argument **id** is for a joint number. It should be one of the enumerated values defined in Table 7.1. These enumerated values are also used in several other member functions to identify joint numbers. The second argument **angle** should be a variable of **double** type. When the function is called, it will read the joint angle of a Linkbot 10 times and store the average of 10 joint angles in degrees in the variable **angle**.

Table 7.1: The enumerated values for joint number.

| Enumerated Value | Joint Number |
|------------------|--------------|
| <b>JOINT1</b>    | Joint 1      |
| <b>JOINT2</b>    | Joint 2      |
| <b>JOINT3</b>    | Joint 3      |

### 7.3. Get Joint Angles

```
/* File: getjointangle.ch
   Get a joint angle. */
#include <linkbot.h>
CLinkbotI robot;
double angle; // declare the variable 'angle' to hold a joint angle

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* move the joint 1 by 90 degrees and joint 3 by -90 degrees */
robot.move(90, NaN, -90);
/* obtain the angle for joint 1 */
robot.getJointAngle(JOINT1, angle);
printf("Joint1 angle = %.2lf degrees.\n", angle);

/* move the joint 1 by 360 degrees and joint 3 by -360 degrees */
robot.moveTo(360, NaN, -360);
robot.getJointAngle(JOINT1, angle);
printf("Joint1 angle = %.2lf degrees.\n", angle);
```

Program 7.3: Getting a joint angle using **getJointAngle()**.

For example, Program 7.3 uses the member function **getJointAngle()** to obtain joint angles. When Program 7.3 is executed, the following output will be displayed in the input/output pane.

```
Joint1 angle = 90.68 degrees.
Joint1 angle = 360.96 degrees.
```

The resolution for joint angle is about 0.6 degrees. In addition, the robotic system involves many components, most of which are not high precision. Therefore, the function **getJointAngle()** does not give an exact angle. If you run the program in your computer, the displayed joint angles will be different.

After the first movement statement

```
robot.move(90, NaN, -90);
```

the function call

```
robot.getJointAngle(JOINT1, angle);
```

obtains the joint angle 90.68 degrees for joint 1 and store the result in the variable `angle`. After the second movement statement

```
robot.moveTo(360, NaN, -360);
```

the joint angle for joint 1 from the function **getJointAngle()** is 360.96 degrees.

 Do Exercises 1 and 2 on page 90.

#### 7.3.2 Get Multiple Joint Angles

The member function **getJointAngle()** can be used to obtain one joint angle at a time. You can call the function multiple times to obtain joint angles for different joints. However, you can call the member function **getJointAngles()** once to obtain joint angles for both joints 1 and 3 of a Linkbot-I. The syntax of the member function **getJointAngles()**.

```
robot.getJointAngles(angle1, NaN, angle3);
```

### 7.3. Get Joint Angles

The function uses arguments `angle1` and `angle3` to store the joint angles for joints 1 and 3, respectively. Similar to the member function `getJointAngle()`, each joint angle is the average of 10 joint angles read from the Linkbot-I.

```
/* File: getjointangles.ch
   Get joint angles. */
#include <linkbot.h>
CLinkbotI robot;
// declare the variables to hold joint angles
double angle1, angle3;

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* move the joint 1 to 360 degrees and joint 3 to -180degrees */
robot.moveTo(360, NaN, -180);
/* obtain joint angles for all four joints */
robot.getJointAngles(angle1, NaN, angle3);
printf("Joint1 angle = %.2lf degrees.\n", angle1);
printf("Joint3 angle = %.2lf degrees.\n", angle3);
```

Program 7.4: Getting joint angles using `getJointAngles()`.

For example, Program 7.4 uses the member function `getJointAngles()` to get the two joint angles of a Linkbot-I. When the program is executed, the following output will be displayed in the input/output pane.

```
Joint1 angle = 361.02 degrees.
Joint3 angle = 45.29 degrees.
```

 Do Exercise 3 on page 90.

#### 7.3.3 Summary

1. Use the enumerated values **JOINT1**, **JOINT2**, and **JOINT3** to specify joints 1, 2, and 3, respectively.
2. Call the **CLinkbotI** member function

```
robot.getJointAngle(JOINT1, angle);
```

to get the joint angle in the second argument for a specified joint in the first argument.

3. Call the **CLinkbotI** member function

```
robot.getJointAngles(angle1, NaN, angle3);
```

to get the two joint angles of a Linkbot-I.

#### 7.3.4 Terminology

**JOINT1**, **JOINT2**, **JOINT3**, `robot.getJointAngle()`, `robot.getJointAngles()`.

## 7.4. Move a Single Joint

**7.3.5 Exercises**

1. What do you think the average means for the function **getJointAngle()**? Can you think of a situation where using the function **getJointAngle()** is necessary.
2. Write a program `getjointangle2.ch` to move joints 1 and 3 to the absolute positions of 180 and -360 degrees, respectively. Then, get the joint angles for each joint by the function **getJointAngle()** and display the values of these joint angles.
3. Write a program `getjointangles2.ch` to move joints 1 and 3 to the absolute positions of 180 and -360 degrees, respectively. Then, get the joint angles for two joints 1 and 3 by the function **getJointAngles()** and display the values of these joint angles.

## 7.4 Move a Single Joint

The member functions **moveTo()** and **move()** can be used to move two joints of a Linkbot to its specified absolute positions and new positions relative to its current positions. The member functions **moveJointTo()** and **moveJoint()** can be used to move a single joint. The member function **moveJointTo()**, can be used to move a joint of a Linkbot-I to its specified absolute position. The member function **moveJoint()** can move a joint to a new position relative to its current position.

**7.4.1 Move a Single Joint to the Absolute Position**

The syntax of the member function **moveJointTo()** is as follows.

```
robot.moveJointTo(id, angle);
```

The function has two arguments. The first argument `id` is for a joint number. It should be one of the three enumerated values defined in Table 7.1 for joint numbers. The second argument `angle` is the absolute position of the joint angle.

## 7.4. Move a Single Joint

```

/* File: movejointto.ch
   Move a joint to the absolute position. */
#include <linkbot.h>
CLinkbotI robot;
double angle;

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* move joint 1 to the position of 180 degrees. */
robot.moveJointTo(JOINT1, 180);

/* move joint 1 to the position of 360 degrees. */
robot.moveJointTo(JOINT1, 360);

/* move joint 1 to the position of 720 degrees. */
robot.moveJointTo(JOINT1, 720);

robot.getJointAngle(JOINT1, angle);
printf("Joint1 angle = %.2lf degrees.\n", angle);

```

Program 7.5: Moving a joint to the absolute position using **moveJointTo()**.

For example, Program 7.5 calls the member function **moveJointTo()** by

```
robot.moveJointTo(JOINT1, 180);
```

to move joint 1 to the position of 180 degrees first. Next, it calls the member function **moveJointTo()** twice again to move joint 1 to 360 degrees and 720 degrees. Then, it calls the member function **getJointAngle()** to obtain the joint angle for joint 1. Finally, it displays the joint angle on the screen. When the program is executed, the output from the following output will be displayed in the input/output pane.

```
Joint1 angle = 720.99 degrees.
```

 Do Exercise 1 on page 93.

### 7.4.2 Move a Single Joint Relative to the Current Position

The syntax of the member function **moveJoint()**, similar to that of **moveJointTo()**, is as follows.

```
robot.moveJoint(id, angle);
```

The function has two arguments. The first argument **id** is for a joint number. It should be one of the three enumerated values defined in Table 7.1 for joint numbers. The second argument **angle** is the position of the joint angle relative to its current position. An application example using the member function **moveJoint()** will be presented in the next section.

### 7.4.3 Delay the Motion of a Linkbot Using the Member Function **delaySeconds()**

In some applications, you may want to pause a program for a specified time. For example, a robot may pose for a few seconds for choreography in a robot dance. You may also pause a program so that the motion of a Linkbot can be settled down. The delay of a program execution can be accomplished by the member function **delaySeconds()** with the syntax as follows.

## 7.4. Move a Single Joint

```
robot.delaySeconds(seconds);
```

The argument `seconds` is the pause time in seconds. The pause time can be less than one second. A sample application of the member function `delaySeconds()` is shown in Program 7.6.

```
/* File: movejoint.ch
   Move a joint relative to its current position. */
#include <linkbot.h>
CLinkbotI robot;
double angle;

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* move joint 1 by 180 degrees. */
robot.moveJoint(JOINT1, 180);

robot.delaySeconds(0.5); // delay 0.5 second

/* move joint 1 by 180 degrees. */
robot.moveJoint(JOINT1, 180);

robot.delaySeconds(0.5); // delay 0.5 second

/* move joint 1 by 360 degrees. */
robot.moveJoint(JOINT1, 360);

robot.delaySeconds(0.5); // delay 0.5 second

robot.getJointAngle(JOINT1, angle);
printf("Joint1 angle = %.2lf degrees.\n", angle);
```

Program 7.6: Moving a joint relative to the current position using `moveJoint()`.

Program 7.6 calls the member function `moveJoint()` to move joint 1 multiple times. The member function call

```
robot.delaySeconds(0.5); // delay 0.5 second
```

pauses the program between each call of the member function `moveJoint()`. At the end of the program, the joint angle for joint 1 is obtained by the member function `getJointAngle()`.

When the program is executed, the following output will be displayed in the input/output pane.

```
Joint1 angle = 720.86 degrees.
```

If you remove the statement

```
robot.delaySeconds(0.5); // delay 0.5 second
```

in the program, the joint angle obtained by the function `getJointAngle()` will deviate more from the desired angle 720 degrees. This is because the movement created by the function `moveJoint()` will start before the previous movement is fully settled down. These errors will be accumulated at each subsequent call of the function `moveJoint()`. This accumulation error also occurs for the function `move()`, which moves joints relative to its current positions.

Because the functions `moveJointTo()` and `moveTo()` use absolute positions, there is no accumulated error each time when they are called. Therefore, for the accuracy with multiple movements, functions `moveJointTo()` and `moveTo()` shall be used.

## 7.5. Get and Set Joint Speeds

### 7.4.4 Summary

1. Call the member function

```
robot.moveJoint(id, angle);
```

to move a joint with the specified angle relative to its current position.

2. Call the member function

```
robot.moveJointTo(id, angle);
```

to move a joint with the specified angle to its absolute position.

3. Call the member function

```
robot.delaySeconds(seconds);
```

to pause a program for seconds.

4. There are accumulated errors for each movement relative to its current position.

### 7.4.5 Terminology

**robot.delaySeconds()**, **robot.moveJoint()**, **robot.moveJointTo()**, accumulated error, relative position, absolute position.

 Do Exercise 2 on page 93.

### 7.4.6 Exercises

1. Write a program `moveJointTo2.ch` to move joint 1 to 45 degrees first, then move joint 3 to 120 degrees. Then get and display the joint angles for joints 1 and 3.
2. Write a program `moveJoint2.ch` to move joint 3 to the position of 90 degrees, delay for two seconds, next move joint 3 again by 180 degrees relative to its current position, then get and display the joint angle for joint 3.

## 7.5 Get and Set Joint Speeds

By default, each Linkbot joint rotates at the angular speed of 45 degrees per second. You can change a joint speed and obtain the joint speed through some member functions of the **CLinkbotI** class.

## 7.5. Get and Set Joint Speeds

### 7.5.1 Get and Set a Joint Speed

The member function **getJointSpeed()** can be used to obtain a joint speed of a Linkbot. The syntax of the member function **getJointSpeed()** is as follows.

```
robot.getJointSpeed(id, speed);
```

The first argument `id` is for a joint number. It should be one of the enumerated values defined in Table 7.1. The second argument `speed` should be a variable of **double** type. When the function is called, it will store the joint speed in degrees per second in the variable `speed`.

The member function **setJointSpeed()** can be used to set the angular speed of a joint for a Linkbot. The syntax of the member function **setJointSpeed()** is as follows.

```
robot.setJointSpeed(id, speed);
```

The first argument `id` is for a joint number. It should be one of the enumerated values defined in Table 7.1. The second argument `speed` is the angular speed to be set for the joint. The minimum joint speed for a Linkbot is  $-240$  degrees per second. The maximum joint speed for a Linkbot is  $240$  degrees per second. When the speed is positive, a joint moves in count clockwise direction as shown in Figure 2.2. When the speed is negative, a joint moves in clockwise direction.

```
/* File: setjointspeed.ch
   Get and set a joint speed. */
#include <linkbot.h>
CLinkbotI robot;
double speed; // the joint speed in degrees per second

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* get the joint speed for joint 1 */
robot.getJointSpeed(JOINT1, speed);
printf("Joint1 speed = %.2lf degrees per second\n", speed);

/* set the joint speed for joint 1 to 90 degrees per second */
speed = 90;
robot.setJointSpeed(JOINT1, speed);

/* rotate joint 1 by 360 degrees */
robot.moveJoint(JOINT1, 360);

/* get the joint speed for joint 1 */
robot.getJointSpeed(JOINT1, speed);
printf("Joint1 speed = %.2lf degrees per second\n", speed);
```

Program 7.7: Getting and setting a joint speed in degrees per second using **getJointSpeed()** and **setJointSpeed()**.

For example, when Program 7.7 is executed, the following output will be displayed in the input/output pane.

```
Joint1 speed = 45.00 degrees per second
Joint1 speed = 90.00 degrees per second
```

## 7.5. Get and Set Joint Speeds

The first function call

```
robot.getJointSpeed(JOINT1, speed);
```

obtains the default speed of 45 degrees per second for joint 1. When the function **getJointSpeed()** is called the second time, the joint speed of 90 degrees per second, set by the function **setJointSpeed()**, will be obtained.

 Do Exercise 1 on page 99.

### 7.5.2 Get and Set Joint Speeds

The member functions **getJointSpeed()** and **setJointSpeed()** can be used to get and set one joint speed at a time, respectively. You can call the function multiple times to set and get joint speeds for different joints.

However, you can call the member function **getJointSpeeds()** once to obtain angular speeds for both joints of a Linkbot. The syntax of the member function **getJointSpeeds()** is as follows.

```
robot.getJointSpeeds(speed1, NaN, speed3);
```

The function uses two arguments `speed1` and `speed3` to store the joint speeds for joints 1 and 3, respectively.

Similarly, you can call the member function **setJointSpeeds()** once to set angular speeds for two joints of a Linkbot-I. The syntax of the member function **setJointSpeeds()** is as follows.

```
robot.setJointSpeeds(speed1, NaN, speed3);
```

The function has two arguments `speed1` and `speed3` to set the angular speeds for joints 1 and 3, respectively.

```
/* File: setjointspeeds.ch
   Get and set joint speeds. */
#include <linkbot.h>
CLinkbotI robot;
double speed1, speed3; // the joint speeds

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* set the joint speed 75 degrees/second for all joints */
speed1 = 75;
speed3 = 75;
robot.setJointSpeeds(speed1, NaN, speed3);

/* move the joint 1 by 180 degrees and joint 3 by -180 degrees */
robot.move(180, NaN, -180);

/* get the joint speed speed for all joints */
robot.getJointSpeeds(speed1, NaN, speed3);
printf("Joint1 speed = %.2lf degrees per second\n", speed1);
printf("Joint3 speed = %.2lf degrees per second\n", speed3);
```

Program 7.8: Getting and setting joint speeds in degrees per second using **getJointSpeeds()** and **setJointSpeeds()**.

## 7.5. Get and Set Joint Speeds

For example, when Program 7.8 is executed, the following output will be displayed in the input/output pane.

```
Joint1 speed = 75.00 degrees per second
Joint3 speed = 75.00 degrees per second
```

 Do Exercises 2 and 3 on page 99.

### 7.5.3 Get and Set a Joint Speed Ratio

The joint speed of a Linkbot can be specified not only in degrees per second, but also in a ratio. A *speed ratio* of a joint is the percentage of the maximum joint speed. Its value ranges from  $-1$  to  $1$ . In other words, if the ratio is set to  $0.5$ , the joint will turn at  $50\%$  of its maximum angular velocity while moving continuously or moving to a new goal position. The member function **getJointSpeedRatio()** can be used to obtain the speed ratio of a joint of a Linkbot-I. The syntax of the member function **getJointSpeedRatio()** is as follows.

```
robot.getJointSpeedRatio(id, ratio);
```

The first argument **id** is for a joint number. It should be one of the enumerated values defined in Table 7.1. The second argument **ratio** should be a variable of **double** type. When the function is called, it will store the speed ratio of the joint in the range of  $-1$  to  $1$ .

The member function **setJointSpeedRatio()** can be used to set the speed ratio of a joint for a Linkbot. The syntax of the member function **setJointSpeedRatio()** is as follows.

```
robot.setJointSpeedRatio(id, ratio);
```

The first argument **id** is for a joint number. It should be one of the enumerated values defined in Table 7.1. The second argument **ratio** is the speed ratio to be set for the joint. The minimum speed ratio for a joint of a Linkbot is  $-1$ . The maximum speed ratio for a joint of a Linkbot is  $1$ .

## 7.5. Get and Set Joint Speeds

```

/* File: setjointspeedratio.ch
   Get and set joint speed ratio. */
#include <linkbot.h>
CLinkbotI robot;
double ratio; // joint speed ratio
double speed; // the joint speed in degrees per second

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* get the joint speed ratio for joint 1 */
robot.getJointSpeedRatio(JOINT1, ratio);
printf("Joint1 speed ratio = %lf\n", ratio);

/* set the joint speed ratio for joint 1 to 0.75 (75% of the max speed). */
ratio = 0.75;
robot.setJointSpeedRatio(JOINT1, ratio);

/* rotate joint 1 by 180 degrees */
robot.moveJoint(JOINT1, 180);

/* get the joint speed ratio for joint 1 */
robot.getJointSpeedRatio(JOINT1, ratio);
printf("Joint1 speed ratio = %lf\n", ratio);

/* get the joint speed for joint 1 */
robot.getJointSpeed(JOINT1, speed);
printf("Joint1 speed = %lf degrees per second\n", speed);

```

Program 7.9: Getting and setting a joint speed ratio using **getJointSpeedRatio()** and **setJointSpeedRatio()**.

For example, when Program 7.9 is executed, the following output will be displayed in the input/output pane.

```

Joint1 speed ratio = 0.375000
Joint1 speed ratio = 0.750000
Joint1 speed = 90.000000 degrees per second

```

 Do Exercise 4 on page 100.

### 7.5.4 Get and Set Joint Speed Ratios

The member functions **getJointSpeedRatio()** and **setJointSpeedRatio()** can be used to get and set one speed ratio for a joint at a time, respectively. You can call the function multiple times to set and get speed ratios for different joints.

However, you can call the member function **getJointSpeedRatios()** once to obtain speed ratios for two joints of a Linkbot-I. The syntax of the member function **getJointSpeedRatios()** is as follows.

```
robot.getJointSpeedRatios(ratio1, NaN, ratio3);
```

The function uses two arguments **ratio1** and **ratio3** to store the joint speeds for joints 1 and 3, respectively.

Similarly, you can call the member function **setJointSpeedRatios()** once to set speed ratios for two joints of a Linkbot. The syntax of the member function **setJointSpeedRatios()** is as follows.

## 7.5. Get and Set Joint Speeds

```
robot.setJointSpeedRatios(ratio1, NaN, ratio3);
```

The function uses two arguments `ratio1` and `ratio3` to set the angular speeds for joints 1 and 3, respectively.

```
/* File: setjointspeedratios.ch
   Get and set joint speed ratios for all joints. */
#include <linkbot.h>
CLinkbotI robot;
double ratio1, ratio3;

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* set the joint speed ratio for all joints to 0.75 */
ratio1 = 0.75;
ratio3 = 0.75;
robot.setJointSpeedRatios(ratio1, NaN, ratio3);

/* rotate joints 1 and 3 by 180 degrees */
robot.move(180, NaN, 180);

/* get the joint speed ratio for all joints */
robot.getJointSpeedRatios(ratio1, NaN, ratio3);
printf("Joint1 speed ratio = %.2lf\n", ratio1);
printf("Joint3 speed ratio = %.2lf\n", ratio3);
```

Program 7.10: Getting and setting joint speed ratios using `getJointSpeedRatios()` and `setJointSpeedRatios()`.

For example, when Program 7.10 is executed, the following output will be displayed in the input/output pane.

```
Joint1 speed ratio = 0.75
Joint3 speed ratio = 0.75
```

 Do Exercises 5 and 6 on page 100.

### 7.5.5 Summary

1. Call the `CLinkbotI` member function

```
robot.getJointSpeed(JOINT1, speed);
```

to get the joint speed in the second argument for a specified joint in the first argument.

2. Call the `CLinkbotI` member function

```
robot.setJointSpeed(JOINT1, speed);
```

to set the joint speed in the second argument for a specified joint in the first argument.

3. Call the `CLinkbotI` member function

## 7.5. Get and Set Joint Speeds

```
robot.getJointSpeeds(speed1, NaN, speed3);
```

to get the joint speeds for two joints of a Linkbot-I.

4. Call the **CLinkbotI** member function

```
robot.setJointSpeeds(speed1, NaN, speed3);
```

to set the joint speeds for two joints of a Linkbot-I.

5. Call the **CLinkbotI** member function

```
robot.getJointSpeedRatio(JOINT1, ratio);
```

to get the speed ratio in the second argument for a specified joint in the first argument.

6. Call the **CLinkbotI** member function

```
robot.setJointSpeedRatio(JOINT1, ratio);
```

to set the speed ratio in the second argument for a specified joint in the first argument.

7. Call the **CLinkbotI** member function

```
robot.getJointSpeedRatios(ratio1, NaN, ratio3);
```

to get the speed ratios for two joints of a Linkbot-I.

8. Call the **CLinkbotI** member function

```
robot.setJointSpeedRatios(ratio1, NaN, ratio3);
```

to set the speed ratios for two joints of a Linkbot-I.

### 7.5.6 Terminology

angular speed, speed ratio, **robot.getJointSpeed()**, **robot.setJointSpeed()**, **robot.getJointSpeeds()**, **robot.setJointSpeeds()**, **robot.getJointSpeedRatio()**, **robot.setJointSpeedRatio()**, **robot.getJointSpeedRatios()**, **robot.setJointSpeedRatios()**.

### 7.5.7 Exercises

1. Write a program **setjointspeed2.ch** to move joint 1 by 360 degrees at the speed of 45 degrees per second, then move joint 1 by another 360 degrees at the speed of 90 degrees per second. At the end of the program, get the joint speed for joint 1 using the member function **getJointSpeed()**.
2. Write a program **setjointspeeds2.ch** to move joint 1 by 360 degrees and joint 3 by -360 degrees at the speed of 45 degrees per second. then move joint 1 by 360 degrees and joint 3 by -360 degrees at the speed of 90 degrees per second. At the end of the program, get the joint speeds for joints 1 and 3 using the member function **getJointSpeed()**.

## 7.6. ‡ Convert Units of Angles between Degrees and Radians

3. Write a program `setjointspeeds3.ch` to set the joint speed for joint 1 to 45 degrees per second and the joint speed for joint 3 to 90 degrees per second. Then, call the function `moveTo()` as follows:

```
robot.moveTo(360, NaN, -360);
```

What motion would occur? Why?

4. Write a program `setjointspeedratio2.ch` to move joint 1 with two full rotations at the maximum speed set by the member function `setJointSpeedRatio()`. Then move joint 1 backward one full rotation with a speed ratio of 0.25. At the end of the program, get the joint speed ratio for joint 1 using the member function `getJointSpeedRatio()`, and get the joint speed for joint 1 using the member function `getJointSpeed()`.
5. Write a program `setjointspeedratios2.ch` to move the robot forward with two full rotations for both joints 1 and 3 at the maximum speed set by the member function `setJointSpeedRatios()`. Then move the robot backward one full rotation for joints 1 and 3 with a speed ratio of 0.25. At the end of the program, get the joint speed ratios for joints 1 and 3 using the member function `getJointSpeedRatios()`.
6. What are the four different ways to set joint speeds? Which functions would you use to change speeds for multiple joints at once?

## 7.6 ‡ Convert Units of Angles between Degrees and Radians

In some applications, joint angles are specified in radians, instead of degrees. However the member functions for movements such as `move()` expect input angles in degrees. In this case, angles in radians must first be converted to degrees, then passed to the movement functions. Similarly, a joint speed might be specified in radian per second, instead of degrees per second. The angular speed needs to be converted to degrees per second before it is used in the function `setJointSpeed()`.

The function `radian2degree()` can be used to convert an angle from radians to degrees with the following syntax.

```
degree = radian2degree(radian);
```

The function `radian2degree()` takes an angle in radians as its argument and returns the angle in degrees. The function can also be used to convert a joint speed from radians per second to degrees per second. The function is implemented in Ch with the code

```
double radian2degree(double radian)
{
    double degree;
    double pi = 3.14159265358979323846;
    degree = radian * 180 / pi;
    return degree;
}
```

## 7.6. ‡ Convert Units of Angles between Degrees and Radians

How to write a function is beyond the scope of this book.

If desired, values in radians can be converted to degrees using the counterpart function, **degree2radian()** with the following syntax.

```
radian = degree2radian(degree);
```

The function is implemented as follows.

```
double degree2radian(double degree)
{
    double radian;
    double pi = 3.14159265358979323846;
    radian = degree * pi / 180;
    return radian;
}
```

```
/* File: radian.ch
   Move the robot joint 1 with speed specified in radians per second. */
#include <linkbot.h>
CLinkbotI robot;
double angle;
double speed;

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* set the speed specified in radians per second */
speed = 1.5;           // speed in 1.5 radians per second
speed = radian2degree(speed); // convert the speed to degrees per second
robot.setJointSpeed(JOINT1, speed);

/* rotate joint 1 by 90 degrees */
robot.moveJoint(JOINT1, 90);

/* get the joint angle in degrees, display in both degrees and radians */
robot.getJointAngle(JOINT1, angle);
printf("Joint1 angle = %.2lf degrees.\n", angle);
angle = degree2radian(angle); // convert the angle in degrees to radian
printf("Joint1 angle = %.2lf radians.\n", angle);
```

Program 7.11: Converting units of angles between degrees and radians using **degree2radian()** and **radian2degree()**.

For example, Program 7.11 moves 90 degrees for joint 1 at the speed of 1.5 radian per second. After joint 1 finishes its movement, the joint angle for joint 1 is obtained and displayed in both degrees and radians. The function calls

```
/* set the speed specified in radians per second */
speed = 1.5;           // speed in 1.5 radians per second
speed = radian2degree(speed); // convert the speed to degrees per second
robot.setJointSpeed(JOINT1, speed); // set joint in degree per second
```

set the joint speed for joint 1 to 1.5 radians per second. The function calls

## 7.6. ‡ Convert Units of Angles between Degrees and Radians

```
/* get the joint angle in degrees, display in both degrees and radians */
robot.getJointAngle(JOINT1, angle);
printf("Joint1 angle = %.2lf degrees.\n", angle);
angle = degree2radian(angle); // convert the angle in degrees to radian
printf("Joint1 angle = %.2lf radians.\n", angle);
```

get the joint angle for joint 1 in degrees, display it in both degrees and radians. When Program 7.11 is executed, the following output will be displayed in the input/output pane.

```
Joint1 angle = 89.88 degrees.
Joint1 angle = 1.56 radians.
```

 Do Exercise 1 on page 102.

### 7.6.1 Summary

1. Call the function **radian2degree()** to convert an angle from radians to degrees .

```
degree = radian2degree(radian);
```

2. Call the function **degree2radian()** to convert an angle from degrees to radians.

```
radian = degree2radian(degree);
```

### 7.6.2 Terminology

radian, **degree2radian()**, **radian2degree()**.

### 7.6.3 Exercises

1. Write a program **radian2.ch** to set the joint speeds of both faceplates of a Linkbot to 0.5 radian per second and move the Linkbot's two faceplates one full rotation. Then, use the member function **getJointAngle()** to obtain the joint angle for joint 1. Display the joint angle in degrees and radians.

---

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## CHAPTER 8

---

# Writing Advanced Programs to Control a Single Linkbot

In the previous chapters, we learned the member functions for controlling a Linkbot with different characteristics. In this chapter, we will learn advanced features of the Linkbot and additional member functions to control the Linkbot for various other applications.

## 8.1 Plot a Curve Using the Plotting Member Function **data2DCurve()**

A picture is worth a thousand words. Graphical plotting is useful for visualization and understanding many problems in engineering and science. Graphical plotting can be conveniently accomplished in Ch. The member function **data2DCurve()** of the plotting class **CPlot** can be used to plot data in arrays of the form

```
plot.data2DCurve(x, y, n);
```

The array x stores data for the x-axis, whereas the array y stores data for the y-axis. Both arrays x and y will have the same number of elements, which is specified by the third argument n of integral value.

**Problem Statement:**

The time and corresponding positions of a robot are recorded in Table 8.1 from an experiment. Write a program to plot the trajectory of the robot based on this table.

8.1. Plot a Curve Using the Plotting Member Function **data2DCurve()**

Table 8.1: Positions of a robot versus time.

|                   |      |      |      |      |      |       |
|-------------------|------|------|------|------|------|-------|
| time (seconds)    | 0.00 | 2.00 | 4.00 | 6.00 | 8.00 | 10.00 |
| position (meters) | 1.25 | 1.75 | 2.25 | 2.75 | 3.25 | 3.75  |

```
/* File: posplot.ch
   Plot the positions of a robot versus time for 6 points of data in arrays */
#include <chplot.h>      /* for the function plotxy() */

CPlot plot;
/* declare two sets of arrays with 6 points for plotting for p versus t */
double t[6] = {0.00, 2.00, 4.00, 6.00, 8.00, 10.00};
double p[6] = {1.25, 1.75, 2.25, 2.75, 3.25, 3.75};

plot.mathCoord();
plot.title("Position Plot");
plot.label(PLOT_AXIS_X, "time (seconds)");
plot.label(PLOT_AXIS_Y, "position (meters)");
plot.data2DCurve(t, p, 6);
plot.plotting();
```

Program 8.1: Plotting positions versus time for motion of a robot using arrays.

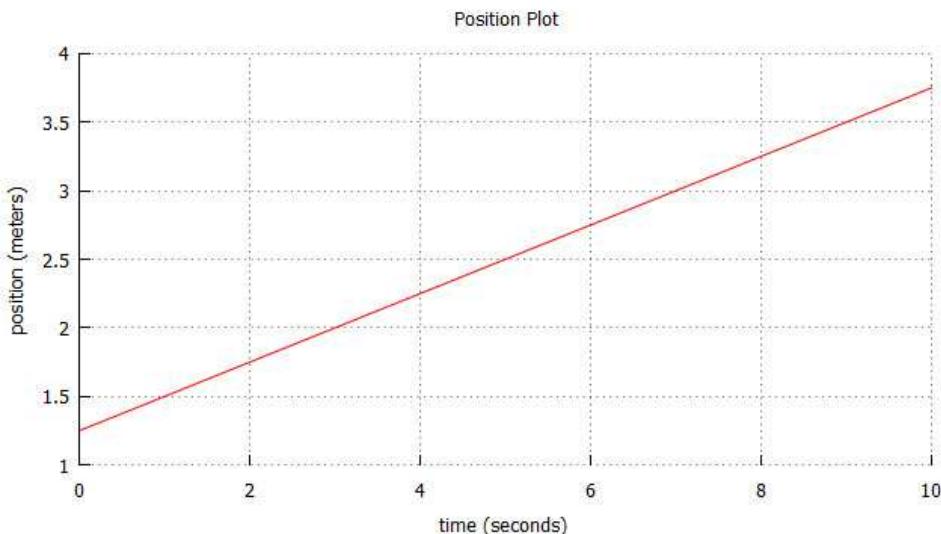


Figure 8.1: The plot for the position versus time from Program 8.1.

As seen in Program 8.1, a program generating a plot typically contains the following statements.

```
#include <chplot.h>
CPlot plot;
plot.mathCoord();
plot.title("title");
```

8.1. Plot a Curve Using the Plotting Member Function **data2DCurve()**

```
plot.label(PLOT_AXIS_X, " xlabel");
plot.label(PLOT_AXIS_Y, " ylabel");
/* add plotting data here */
plot.plotting();
```

The line

```
#include <chplot.h>
```

includes the header file **chplot.h**. The purpose of including the header file **chplot.h** is to use the class **CPlot** defined in this header file. As we have learned in previous chapters, a class is a user defined data type in Ch. The symbol **CPlot** can be used in the same manner as the symbol **int** or **double** to declare variables.

The following lines

```
double t[6] = {0.00, 2.00, 4.00, 6.00, 8.00, 10.00};
double p[6] = {1.25, 1.75, 2.25, 2.75, 3.25, 3.75};
```

consist of the data that will be plotted. The array with the variable name **t** holds six time values, and the array with the variable name **p** holds the six corresponding distance values. Both are of type **double** since we are plotting time and distance, which are typically written as decimal numbers. For generating the plot, **t** will be the x-axis values and **p** will be the y-axis values.

The next line

```
CPlot plot; //plotting class
```

declares the variable **plot** of type **CPlot** for plotting. A function associated with a class is called a **member function**. For example, the function **plot.mathCoord()** or **mathCoord()** is a member function of the class **CPlot**. In Program 8.1, member functions of the class **CPlot** are called to process the data for the object **plot**.

The function call

```
plot.mathCoord();
```

sets proper attributes such as grids for a mathematical coordinate system. The function call

```
plot.title("title");
```

adds a title to the plot. The argument for this member function is a string. If this member function is not called, the generated plot will have no title. In Program 8.1, the line

```
plot.title("Position Plot");
```

adds the appropriate label for our intended purpose.

The subsequent two function calls

```
plot.label(PLOT_AXIS_X, " xlabel");
plot.label(PLOT_AXIS_Y, " ylabel");
```

add labels to the x and y coordinates. The macros **PLOT\_AXIS\_X** and **PLOT\_AXIS\_Y** for the x and y axes, respectively, are defined in the header file **chplot.h**. The second arguments of the above two member functions are also strings for labels. If these two functions are not called, by default, the label for the x-axis will be “x” whereas the label for the y-axis will be “y”. Thus the lines in Program 8.1

```
plot.label(PLOT_AXIS_X, "time (seconds)");
plot.label(PLOT_AXIS_Y, "position (meters)");
```

add the correct labels for position versus time.

The next line

8.1. Plot a Curve Using the Plotting Member Function **data2DCurve()**

```
plot.data2DCurve(t, p, 6);
```

plots the trajectory of the Linkbot based on the six data points from Table 8.1.

Finally, after the plotting data are added, the program needs to call the function

```
plot.plotting();
```

to generate a plot. The generated graph is shown in Figure 8.1.

 Do Exercise 1 on page 107.

You may read section B.1 in Appendix B to learn how to plot points and lines using member functions of the plotting class **CPlot**.

### 8.1.1 Summary

- Include the header file **chplot.h** and use the class **CPlot** to declare a variable **plot** by the following two statements

```
#include<chplot.h>
CPlot plot;
```

- Call the **CPlot** member function

```
plot.mathCoord();
```

to set the proper attributes for a coordinate system.

- Call the **CPlot** member function

```
plot.title("title");
```

to add a title to the plot.

- Call the **CPlot** member functions

```
plot.label(PLOT_AXIS_X, " xlabel");
plot.label(PLOT_AXIS_Y, " ylabel");
```

To label the x and y axes of the graph.

- Call the **CPlot** member function

```
plot.data2DCurve(x, y, n);
```

to plot n data points stored in arrays x and y.

- Call the **CPlot** member function

```
plot.plotting();
```

To generate the final graph.

## 8.2. Plot Recorded Joint Angles and Time

**8.1.2 Terminology**

```
#include <chplot.h>, CPlot, plot.mathCoord(), plot.title(), plot.label(), plot.data2DCurve(),
plot.plotting()
```

**8.1.3 Exercises**

- When a soccer ball is kicked on the ground, the time and corresponding positions of the soccer ball are recorded in Table 8.2. Write a program posplot2.ch using the member function **data2DCurve()** to plot the trajectory of the soccer ball based on the data in the table.

Table 8.2: Positions of a soccer ball versus time.

|                   |   |     |     |     |     |      |      |      |      |      |      |     |     |     |     |     |
|-------------------|---|-----|-----|-----|-----|------|------|------|------|------|------|-----|-----|-----|-----|-----|
| time (seconds)    | 0 | 0.2 | 0.4 | 0.6 | 0.8 | 1    | 1.2  | 1.4  | 1.6  | 1.8  | 2    | 2.2 | 2.4 | 2.6 | 2.8 | 3   |
| position (meters) | 0 | 2.8 | 5.2 | 7.2 | 8.9 | 10.1 | 10.9 | 11.4 | 11.5 | 11.1 | 10.4 | 9.3 | 7.8 | 5.9 | 3.6 | 0.9 |

**8.2 Plot Recorded Joint Angles and Time**

In the previous section data is provided to the program specifically. In this section we will learn how to write a program to receive data from a Linkbot-I in real time. The ability to record and process real time data is a powerful tool with multiple applications in robotics. It aids in the understanding of how a robot is functioning so that we can improve upon that robot's design. Real time data acquisition also allows a robot to interact with its environment through sensors or user input. An example would be a robot that can receive and respond to voice commands using an audio sensor. Another example would be a robot that can recognize and react to its surroundings using a visual sensor.

Program 8.2 demonstrates how to record and plot real time joint angle data for a Linkbot-I. This plot can be used to show the angle of a Linkbot-I joint at a specific point in time.

**Problem Statement:**

Write a program **recordangle.ch** to rotate joints 1 and 3 of a Linkbot forward for 720 degrees at 45 degrees per second. Record the joint angle for joint 1 with a time interval of 0.1 second. Plot the joint angle versus time.

## 8.2. Plot Recorded Joint Angles and Time

```

/* File: recordangle.ch
   Record a joint angle and time, plot the acquired data */
#include <linkbot.h>
#include <chplot.h>
CLinkbotI robot;
double speed = 45;           // speed in 45 degrees/seconds
double timeInterval = 0.1;    // time interval in 0.1 second
int numDataPoints;           // number of data points recorded
robotRecordData_t timedata, angledata; // recorded time and angles for joint 1
CPlot plot;                  // plotting class

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* set the joints 1 and 3 speed */
robot.setJointSpeed(JOINT1, speed);
robot.setJointSpeed(JOINT3, speed);

/* begin recording time and angle */
robot.recordAngleBegin(JOINT1, timedata, angledata, timeInterval);

/* drive the Linkbot-I forward by 720 degrees */
robot.driveForward(720);

/* end recording time and angle */
robot.recordAngleEnd(JOINT1, numDataPoints);

/* plot the data */
plot.mathCoord();
plot.title("Angles for joint 1 versus time");
plot.label(PLOT_AXIS_X, "time (seconds)");
plot.label(PLOT_AXIS_Y, "angle for joint1 (degrees)");
plot.data2DCurve(timedata, angledata, numDataPoints);
plot.plotting();

```

Program 8.2: Recording a joint angle using the function **recordAngleBegin()** and **recordAngleEnd()**.

## 8.2. Plot Recorded Joint Angles and Time

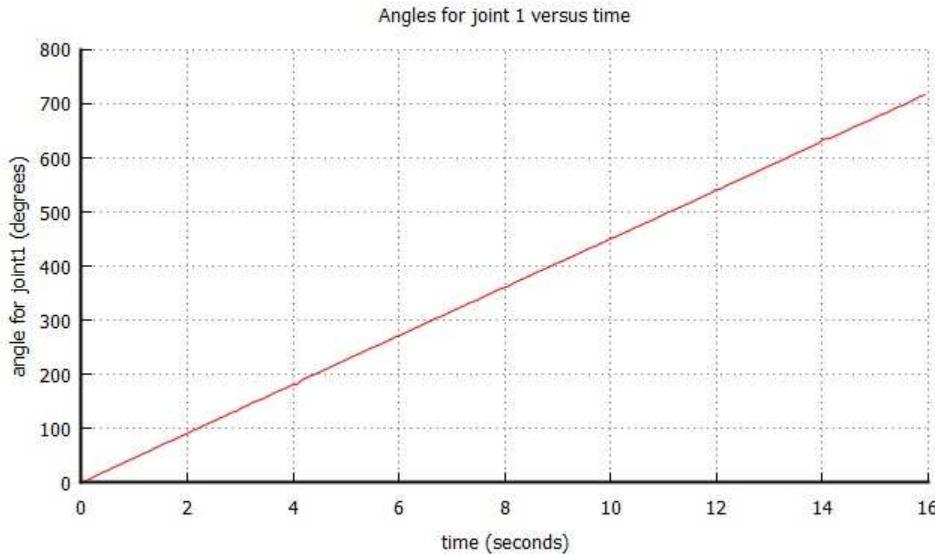


Figure 8.2: The plot for the joint angle versus time from Program 8.2.

Program 8.2 records the angle of joint1 of a Linkbot-I every 0.1 seconds. It then uses the **CPlot** member functions demonstrated in Program 8.1 to plot the recorded joint angles versus time for this Linkbot. In order to collect and plot the angle data from the Linkbot-I, we need to declare a few extra variables in the program. The line

```
double timeInterval = 0.1; //time interval in 0.1 second
```

specifies that we want to measure the angle every 0.1 second after the robot starts to move. The next line

```
int numDataPoints; //number of data points recorded
```

declares an **int** variable to keep hold the number of data points the program has collected. The following line

```
robotRecordData_t timedata, angledata; //recorded time and angles for joint 1
```

creates two variables of type **robotRecordData\_t**. This is a special type of array defined in the header file **linkbot.h** that can be used when we don't know ahead of time how many values we will be recording. Variables of type **robotRecordData\_t** dynamically grow to the size that you need while the program is running. These two variables, **timedata** and **angledata**, will be used to keep track of the data points while the Linkbot-I is in motion. To record angle data while the robot is moving, we need to use two new **CLinkbotI** member functions **recordAngleBegin()** and **recordAngleEnd()**. The general syntax of the **CLinkbotI** member function **recordAngleBegin()** is as follows

```
robot.recordAngleBegin(id, timedata, angledata, timeInterval);
```

The argument **id** specifies the joint from which you wish to record data. The argument **timedata** is used to record time values in seconds elapsed since the Linkbot-I starts to move, and argument **angledata** is used to record the angle values in degrees. The argument **timeInterval** specifies the amount of time between each recorded measurement. In Program 8.2 the line

```
robot.recordAngleBegin(JOINT1, timedata, angledata, timeInterval);
```

## 8.2. Plot Recorded Joint Angles and Time

starts the process of recording the angle of joint 1 every 0.1 seconds. It is important to include this statement before the Linkbot-I starts moving, so that the program does not miss any data points.

After the Linkbot-I has stopped moving, we must use **recordAngleEnd()** to stop the recording of data. The general syntax of the function **recordAngleEnd()** is as follows

```
robot.recordAngleEnd(id, numDataPoints);
```

The argument **id** is the joint you wish to stop recording, and the argument **numDataPoints** keeps track of the total number of data points that were collected while the Linkbot-I was moving.

In Program 8.2, after the Linkbot-I has finished moving forward 720 degrees, the line

```
robot.recordAngleEnd(JOINT1, numDataPoints);
```

stops the recording of data after the Linkbot-I has stopped moving forward. **numDataPoints** will now hold the total number of data points that were collected while the Linkbot-I was in motion. In addition, **angledata** will hold all the angle values that were recorded while the Linkbot-I was in motion, and **timedata** will hold all the corresponding time values.

When a joint rotates at 45 degrees per second, the relation between the joint angle ( $s$ ) and time ( $t$ ) in Figure 8.2 can be formulated by the following linear equation.

$$s = 45t \quad (8.1)$$

If we change the statement

```
robot.driveForward(720);
```

in Program 8.2 to

```
robot.driveBackward(720);
```

to rotate the joints 1 and 3 in the opposite direction. The plot generated by such a program **recordangleneg.ch** is shown in Figure 8.3. The relation between the joint angle ( $s$ ) and time ( $t$ ) in Figure 8.3 can be formulated by the following linear equation.

$$s = -45t \quad (8.2)$$

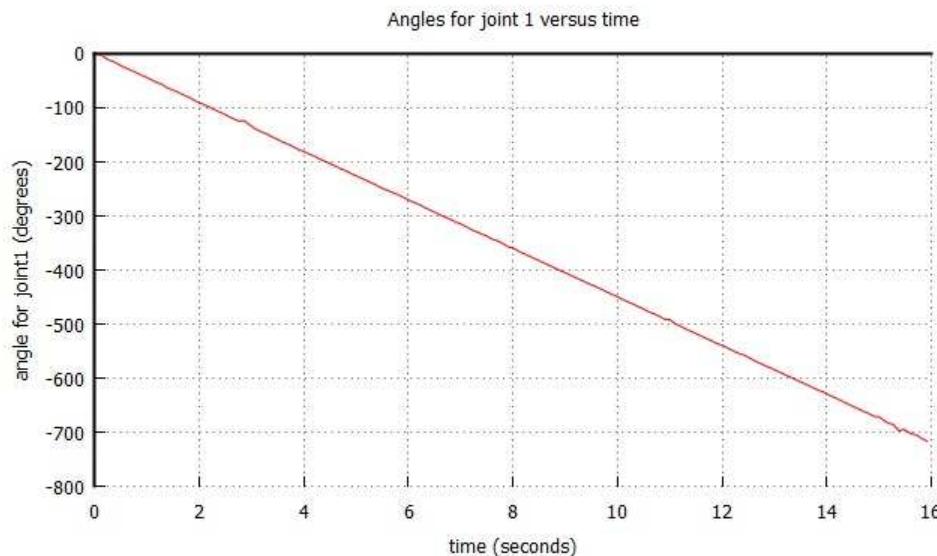


Figure 8.3: The plot for the joint angle versus time for a Linkbot moving in the negative direction.

## 8.2. Plot Recorded Joint Angles and Time

 Do Exercises 1 and 2 on page 111.

**8.2.1 Summary**

1. Use the data type **robotRecordData\_t** to record data points when you don't know ahead of time how many points you will get.
2. Call the **CPlot** member function

```
robot.recordAngleBegin(id, timedata, angledata, timeInterval);
```

when you want to begin recording joint angle data from a Linkbot-I.

3. Call the **CPlot** member function

```
robot.recordAngleEnd(id, numDataPoints);
```

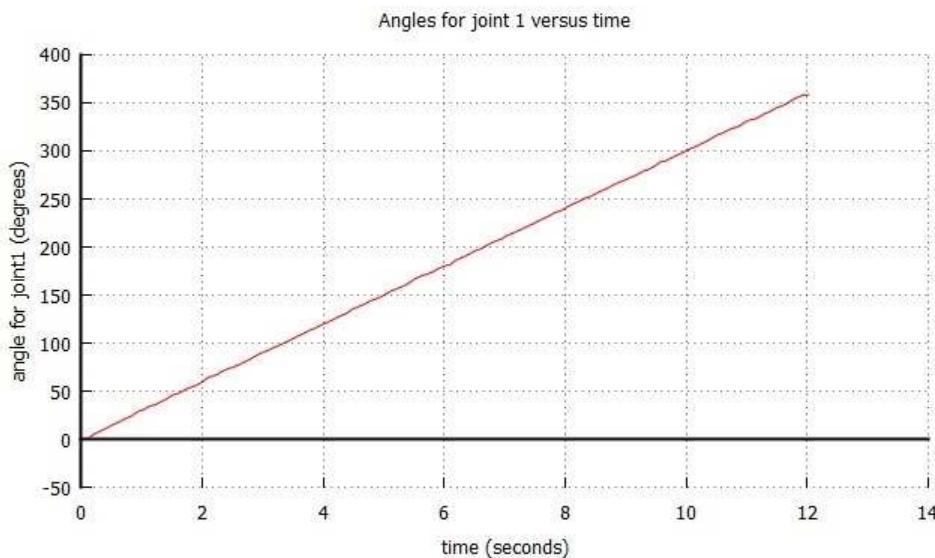
when you want to stop recording joint angle data from a Linkbot-I.

**8.2.2 Terminology**

**robotRecordData\_t**, **robot.recordAngleBegin()**, **robot.recordAngleEnd()**.

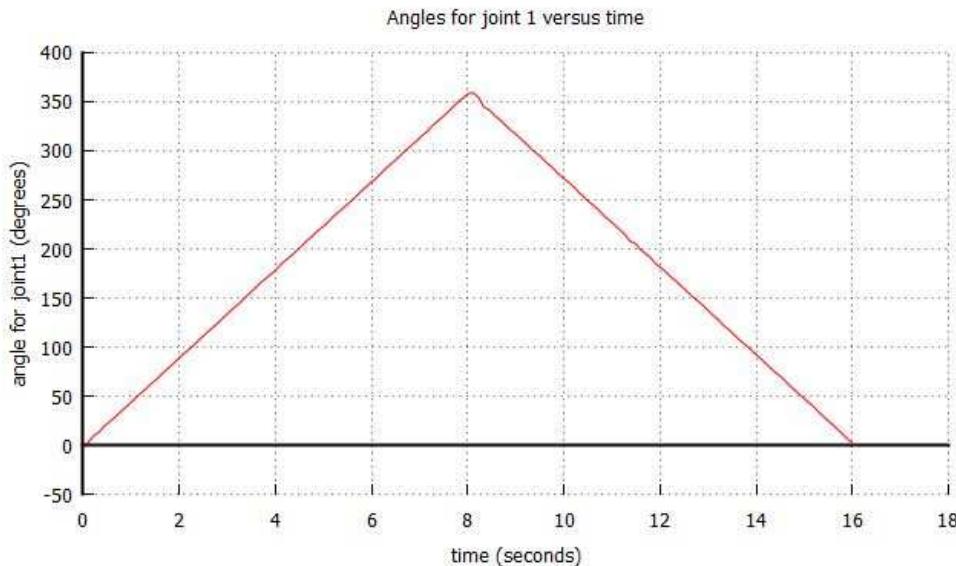
**8.2.3 Exercises**

1. Write a program **recordangle2.ch** to record the joint angle for joint 1 of a Linkbot with a time interval of 0.1 second while the Linkbot rolls forward for 360 degrees at 30 degrees per second. Plot the joint angle versus time as shown in the figure below. What is the equation for the linear relation shown in the figure?



## 8.3. Move Joints with a Specified Time

2. Write a program `recordangle3.ch` to record the joint angle for joint 1 of a Linkbot-I with a time interval of 0.1 second when the robot drives forward by rotating joints by 360 degrees and drives backward by 360 degrees. Plot the joint angle versus time as shown in the figure below.



## 8.3 Move Joints with a Specified Time

Sometimes it may be necessary to move joints of a robot for a specified time. The member function **moveTime()** can be used for such a purpose. The general syntax of this function is

```
robot.moveTime(seconds);
```

The argument, `seconds`, defines how long each joint will be moved in seconds. The direction of the motion for each joint is determined by the speed of the joint. If the speed is positive, the joint will move in the counter clockwise direction. If the speed is negative, the joint will move in the clockwise direction.

```
/* File: movetime.ch
Move a robot for a specified time. */
#include <linkbot.h>
CLinkbotI robot;
double time=5; // five seconds
double speed=90; // 90 degrees per second

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* set the joint speeds for all joints to 90 degrees per second */
robot.setJointSpeeds(speed, NaN, speed);

/* rotate joints 1 and 3 for the specified 'time', based on the speed */
robot.moveTime(time);
```

Program 8.3: Moving a joint with a specified time using **moveTime()**.

### 8.3. Move Joints with a Specified Time

Program 8.3 sets the speeds of joints 1 and 3 to 90 degrees per second using the function **setJointSpeeds()**, which was introduced in Program 7.8.

The line

```
robot.moveToTime(time);
```

moves a Linkbot-I for 5 seconds at the speed set by **setJointSpeeds()**. Note that the speeds for both joints are positive, the robot will spin and not drive forward.

 Do Exercise 1 on page 114.

It is also possible to move only one joint, using the **CLinkbotI** member function **moveJointTime()**. The general syntax of this function is

```
robot.moveJointTime(id, seconds);
```

The first argument **id** specifies which joint you want to move. The second argument, **seconds**, indicates how long the joint will move in seconds.

```
/* File: movejointtime.ch
   Move a joint in a specified time. */
#include <linkbot.h>
CLinkbotI robot;
double time=5; // five seconds
double speed=90; // 90 degrees per second

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* set the joint speed for joint 1 to 90 degrees per second */
robot.setJointSpeed(JOINT1, speed);

/* rotate joint 1 for the specified 'time' */
robot.moveJointTime(JOINT1, time);
```

Program 8.4: Moving a joint with a specified time using **moveJointTime()**.

Program 8.4 works the same way as Program 8.3 except that the last line

```
robot.moveJointTime(JOINT1, time);
```

moves only joint 1 for 5 seconds, at 90 degrees per second.

In the program **movejointtimeneg.ch** distributed for the curriculum the joint speed is changed to -90 degrees per second by the statement

```
robot.setJointSpeed(JOINT1, -speed);
```

joint 1 of the robot will move in clockwise direction instead of counter clockwise direction.

 Do Exercise 2 3 on page 114.

#### 8.3.1 Summary

1. Call the **CLinkbotI** member function

```
robot.moveToTime(seconds);
```

## 8.4. Hold the Joints At Exit

to move joints for a number of seconds indicated by the argument `seconds`.

2. Call the `CLinkbotI` member function

```
robot.moveJointTime(id, seconds);
```

to move a joint specified by the argument `id` for the number of seconds indicated by the argument `seconds`.

### 8.3.2 Terminology

`robot.moveTo()`, `robot.moveJointTime()`.

### 8.3.3 Exercises

1. Write a program `movetime2.ch` to rotate joints 1 and 3 of a Linkbot-I in opposite directions at the speed of 45 degrees per second for 8 seconds. What is the resulting motion?
2. Write a program `movejointtime2.ch` to rotate joint 1 in the positive direction (counter clockwise) at the speed of 45 degrees per second for 8 seconds.
3. Write a program `movejointtimeneg2.ch` to rotate joint 1 in the negative direction (clockwise) at the speed of 45 degrees per second for 8 seconds.

## 8.4 Hold the Joints At Exit

By default, when the program finishes, all joints are relaxed. When joints are relaxed, depending on how the Linkbot is positioned, the joint angles can be different after the program finishes its execution. In some applications, especially for a robot configured with multiple Linkbots, you may want to hold the pose of the robot after the program exits. You can hold all joint angles of a Linkbot at the exit of a program by calling the function `holdJointsAtExit()`. The general syntax of this function is

```
robot.holdJointsAtExit();
```

```
/* File: holdjointsatexit.ch
   Hold the joints at the exit. */
#include <linkbot.h>
CLinkbotI robot;
double angle=360;      // angle for rotation

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* drive forward for 'angle' */
robot.driveForward(angle);

/* Hold the joints at exit .*/
robot.holdJointsAtExit();
```

Program 8.5: Holding the joints after the exit using the function `holdJointsAtExit()`.

8.5. Measure the Clock Time Using the Member Function **systemTime()**

Program 8.5 moves a Linkbot-I forward 360 degrees. The last line

```
robot.holdJointsAtExit();
```

holds the position of the Linkbot's motors in its final position.

 Do Exercises 1 and 2 on page 115.

### 8.4.1 Summary

1. Call the **CLinkbotI** member function

```
robot.holdJointsAtExit();
```

to hold the final position of a Linkbot-I.

### 8.4.2 Terminology

**robot.holdJointsAtExit()**.

### 8.4.3 Exercises

1. Write a program `holdjointsatexit2.ch` to rotate joint 3 to 45 degrees (without holding the joints at the exit). After the program is run, try to rotate joint 3 manually.
2. Modify the program `holdjointsatexit2.ch` in Exercise 1 as a new program `holdjointsatexit3.ch`, which holds all the joint at exit. After the program is run, try to rotate joint 3 manually.

## 8.5 Measure the Clock Time Using the Member Function **systemTime()**

You can time the motion of a Linkbot-I using the member function **systemTime()**. The syntax of the member function **systemTime()** is as follows.

```
robot.systemTime(time);
```

This member function passes the time in seconds since 00:00:00 January 1, 1970 on Mac OS X and Linux systems. In Windows this function returns the time in seconds since the system last started. Program 8.6 gives an example of using **systemTime()** to time a Linkbot's motion for a specified joint angle and joint speed.

#### Problem Statement:

The joint 1 of a Linkbot rotates two full rotations for 720 degrees at the speed of 90 degrees per second. Write a program `time.ch` to measure the time for the Linkbot to complete the motion.

8.5. Measure the Clock Time Using the Member Function **systemTime()**

```

/* File: time.ch
   Get the time for a robot to finish its motion */
#include <linkbot.h>

CLinkbotI robot;
double speed = 90;           // speed in degrees/second
double angle = 720;          // joint angle
double time1, time2, elapsedtime; // system time and elapsed time

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* set the joint speed for joint 1 */
robot.setJointSpeed(JOINT1, speed);

robot.systemTime(time1);      // get the system time since the system starts
robot.moveJoint(JOINT1, angle); // rotate joint 1 by 'angle'
robot.systemTime(time2);      // get the system time since the system starts
elapsedtime = time2 - time1; // Calculate the time for the motion.

printf("The motion for the robot took %.2lf seconds\n", elapsedtime);
printf("The motion should take %.2lf seconds in theory.\n", angle/speed);

```

Program 8.6: Get the time for a Linkbot to complete a motion with specified joint angle and joint speed using the member function **systemTime()**.

Program 8.6 declares three variables of type **double**: `time1`, `time2`, and `elapsedtime`, which will be used to time the motion of the Linkbot-I. The line

```
robot.systemTime(time1); // the system time since the system starts
```

records the system time in seconds immediately before joint 1 of the Linkbot-I starts moving. Then the line

```
robot.systemTime(time2); // the system time since the system starts
```

records the system time in seconds immediately after joint 1 of the Linkbot-I stops moving. The next line

```
elapsedtime = time2 - time1; // Calculate the time for the motion.
```

calculates the difference between the end time and the start time. This difference gives the total actual time joint 1 of the Linkbot-I was in motion.

The last two lines of the program displays the actual `elapsedtime` that was calculated using **systemTime()**, as well as the theoretical time. The theoretical time of a Linkbot-I's motion as a function of joint angle and joint speed is defined as

$$\text{theoretical time} = \frac{(\text{joint angle in degrees})}{(\text{joint speed in degrees per second})}$$

When Program 8.6 is executed, the following output will be displayed in the input/output pane

```
The motion for the Linkbot took 8.14 seconds.
The motion should take 8.00 seconds in theory.
```

 Do Exercises 1 and 2 on page 117.

8.5. Measure the Clock Time Using the Member Function **systemTime()****8.5.1 Summary**

1. Call the member function

```
robot.systemTime(time);
```

to get the system time in seconds since the system was last started.

**8.5.2 Terminology**

actual time, theoretical time, **robot.systemTime()**.

**8.5.3 Exercises**

1. Write a program `time2.ch` to drive forward for 450 degrees at the speed of 45 degrees per second. Use the member function **systemTime()** to measure the time for the Linkbot to complete its motion.
2. Based on program `movejointtime2.ch` developed in Exercise 2 on page 114, write a program `time3.ch` to drive joints 1 and 3 forward at the speed of 45 degrees per second for 8 seconds using the function **moveTime()**. Use the member function **systemTime()** to measure the time for the Linkbot to complete its motion.

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## CHAPTER 9

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# Controlling a Linkbot-I as a Two-Wheel Robot

In the previous chapters, we learned the member functions of the **CLinkbotI** class for controlling two joints of a Linkbot-I with different characteristics. A Linkbot-I can be configured as a two-wheel robot as shown in Figure 9.1. In this configuration, joints 1 and 3 are attached with two wheels. In this Chapter, we will learn various programming features on how to control a Linkbot-I as a two-wheel robot.

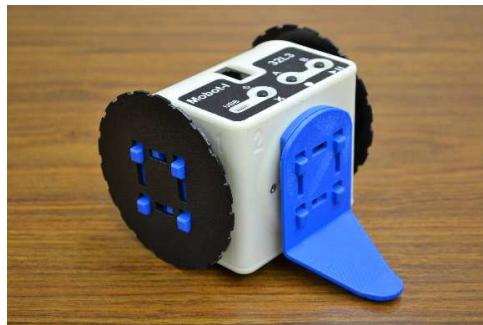


Figure 9.1: A two-wheel robot.

## 9.1. Move a Two-Wheel Robot with the Specified Distance

## 9.1 Move a Two-Wheel Robot with the Specified Distance

### 9.1.1 Move a Two-Wheel Robot with the Specified Speed, Joint Angles, and Distance

The **CLinkbotI** class includes two additional member functions that can be used for the two-wheel Linkbot-I configuration. The first of these two member functions is **setSpeed()**, which can be used to set both joints 1 and 3 of a Linkbot-I to the desired speed with the specified wheel radius. The general syntax of this function is

```
robot.setSpeed(speed, radius);
```

The argument `speed` is the desired vehicle speed in distance/second. The argument `radius` is the radius of the currently attached wheels, which should have the same units of distance as the argument `speed`. For instance, if `speed` is in inches/second, then `radius` should be in inches. If the speed is positive, the robot will drive forward. If the speed is zero, the robot will not move. If the speed is negative, the robot will drive backward.

The second member function is **driveDistance()**, which can be used to drive a Linkbot-I a desired distance using a specific wheel radius. The general syntax of this function is

```
robot.driveDistance(distance, radius);
```

where `distance` specifies how far you want the Linkbot-I to move and `radius` specifies the radius of the currently attached wheels. The values of both `distance` and `radius` should have the same unit.

The member functions **setSpeed()** and **driveDistance()** can be used in combination to drive a Linkbot-I with a specified speed and distance, as demonstrated solving the following problem.

#### Problem Statement:

A Linkbot-I is configured as a two-wheel robot with wheels attached to joints 1 and 3. The radius of each wheel is 1.75 inches. Write a program `setspeed.ch` to drive forward 360 degrees using the member function **driveForward()**, drive backward 360 degrees using the member function **driveBackward()**, and then drive forward 5 inches using the member function **driveDistance()**. For these three motions, the robot drives at the speed of 2.5 inches per second.

## 9.1. Move a Two-Wheel Robot with the Specified Distance

```

/* File: setspeed.ch
   Set the speed of a two-wheel robot. */
#include <linkbot.h>
CLinkbotI robot;
double radius=1.75; // the radius of the two wheels of the robot in inches
double speed=3;    // the speed in 3 inches per second for a two-wheel robot
double distance=5; // the distance in 5 inches to drive forward

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* set the speed for a two-wheel robot to 3 inches per second */
robot.setSpeed(speed, radius);

/* drive the robot 360 degrees forward for joints 1 and 3 */
robot.driveForward(360);

/* drive the robot 360 degrees backward for joints 1 and 3 */
robot.driveBackward(360);

/* drive forward for 'distance' inches */
robot.driveDistance(distance, radius);

```

Program 9.1: Setting the speed of a two-wheel robot using **setSpeed()**.

In Program 9.1 the variable `radius` is set to 1.75 inches, the variable `speed` is set to 2.5 inches per second, and the variable `distance` is set to 5 inches. The line

```
robot.setSpeed(speed, radius);
```

sets the speeds for joints 1 and 3 of the Linkbot-I to drive the robot at 2.5 inches per second with a wheel radius of 1.75 inches. Then when the next two lines

```
robot.driveForward(360);
robot.driveBackward(360);
```

are executed, the Linkbot-I drives forward 360 degrees and then backward 360 degrees at a speed of 2.5 inches per second. The last line

```
robot.driveDistance(distance, radius);
```

drives the Linkbot-I forward 5 inches at the same speed of 2.5 inches per second.

 Do Exercise 1 on page 133.

### 9.1.2 Control a Linkbot-I with the Speed and Distance Input from the User Using the Function **scanf()**

In the previous section we set the speed and distance of a Linkbot-I by providing those values in the program specifically. In this section we will learn how to set the speed and distance of a Linkbot-I with user input. This way the same program can be used to solve the same problem but with different data. Code reusability is an effective and convenient programming tool.

#### Problem Statement:

A Linkbot-I is configured as a two-wheel robot with wheels attached to joints 1 and 3. The radius of each wheel is 1.75 inches. Write a program `drivedistance_p.ch` to accept the user input of speed and distance for moving the robot using the member function **driveDistance()**.

## 9.1. Move a Two-Wheel Robot with the Specified Distance

```
/* File: drivendistance_p.ch
   Drive a two-wheel robot with the user specified radius of wheels, speed,
   and distance. */
#include <linkbot.h>
CLinkbotI robot;
double speed;           // the speed in inches per second for a two-wheel robot
double radius;          // the radius of the two wheels of the robot in inches
double distance;        // distance to drive

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

printf("Enter the radius of the two wheels in inches\n");
scanf("%lf", &radius);

printf("Enter the speed of the two-wheel robot in inches per second\n");
scanf("%lf", &speed);
/* set the speed for a two-wheel robot */
robot.setSpeed(speed, radius);

printf("Enter the distance in inches for the two-wheel robot to drive\n");
scanf("%lf", &distance);

/* drive the specified distance based on the radius of the wheels */
robot.driveDistance(distance, radius);
```

Program 9.2: Using the input function **scanf()** to specify the speed and distance.

Program 9.2 uses the function **scanf()** to set the variables `speed`, `radius`, and `distance` to the values desired by the user. As we learned in Section 5.3, the input function **scanf()** is used to set the value of a variable from the user input at runtime. For instance, the line

```
scanf("%lf", &radius);
```

is used to set the value of the variable `radius` from keyboard input at runtime. Recall that when using **scanf()** the address operator ‘&’ must precede the variable name `radius` in order to obtain the address of that variable. Since all three variables are of **double** type, the conversion specifier “`%lf`” is used for **scanf()**.

An interactive execution of Program 9.2 is shown below.

```
Enter the radius of the wheels in inches
1.75
Enter the speed of the two-wheel robot in inches per second
1
Enter the distance in inches for the two-wheel robot to drive
5
```

For a Linkbot-I configured as a two-wheel robot with the radius of 1.75 inches for wheels, the above execution will drive the Linkbot-I forward 5 inches at the speed of 1 inch per second.

 Do Exercise 2 on page 133.

### 9.1.3 Estimate the Error in Distance and Use the Function **getDistance()**

In some applications it is useful to compare the specified distance of a robot’s motion with the actual distance that it has moved. Such a comparison can indicate whether the robot is working as intended. The member

## 9.1. Move a Two-Wheel Robot with the Specified Distance

function **getDistance()** can be used to get the distance that a Linkbot-I has moved using a specific wheel radius. The general syntax of this function is

```
robot.getDistance(distance, radius);
```

where **distance** specifies how far you the Linkbot-I has moved and **radius** specifies the radius of the currently attached wheels. The values of both **distance** and **radius** have the same units.

**Problem Statement:**

A Linkbot-I is configured as a two-wheel robot with wheels attached to joints 1 and 3. The radius of each wheel is 1.75 inches. Write a program **errorindistance.ch** to drive the robot for 12 inches at the speed of 2.5 inches per second. Estimate the error between the specified distance and driven distance.

```
/* File: errorindistance.ch
Estimate the error in the distance between the specified and driven distances
using robot.getDistance() */

#include <linkbot.h>
CLinkbotI robot;
double speed = 2.5;           // speed in inches/second
double radius = 1.75;         // radius of the wheel
double distance = 12;         // distance to drive in inches
double distance2;             // distance driven

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* set the robot speed */
robot.setSpeed(speed, radius);

/* drive the specified distance based on the radius of the wheels */
robot.driveDistance(distance, radius);

/* get the drive distance */
robot.getDistance(distance2, radius);

printf("The distance to drive is %.2lf inches.\n", distance);
printf("The actual distance driven is %.2lf inches.\n", distance2);
printf("The error is %lf inches.\n", distance-distance2);
printf("The error is %lf percent.\n", (distance-distance2)/distance *100);
```

Program 9.3: Estimate the error between the specified distance and driven distance using **getDistance()**.

The member function **getDistance()** is used to get the actual distance in inches that was traveled by the Linkbot. The error of the distance that a robot has moved is defined as

$$\text{error} = (\text{distance to be moved}) - (\text{distance moved})$$

The percentage of the error of the distance that a robot has moved is defined as

$$\text{percentage of error} = \frac{(\text{distance to be moved}) - (\text{distance moved})}{(\text{distance to be moved})} \times 100$$

When Program 9.3 is executed, the following output will be displayed in the input/output pane

## 9.1. Move a Two-Wheel Robot with the Specified Distance

```
The distance to drive is 12.00 inches.
The actual distance drived is 11.98 inches.
The error is 0.020000 inches.
The error is 0.016667 percent.
```

The output indicates that the robot actually drives about 9.98 inches, with the error of 0.02 inches and 0.16667 percent of the distance to drive.

 Do Exercise 3 on page 133.

#### 9.1.4 ‡ Use the Functions `distance2angle()` and `angle2distance()`

In the previous section, we use the member function `getDistance()` to get the distance that a Linkbot-I has moved. In this section, we will an alternative method to get the distance. As we learned in Chapter 7, we can get the joint angle after a Linkbot-I has stopped moving using the member function `getJointAngle()`. We can convert this joint angle value into the actual distance that the Linkbot-I has moved using the function `angle2distance()`. The general syntax of this function is

```
distance = angle2distance(radius, angle);
```

where `radius` is the radius of the wheels attached to the Linkbot-I and `angle` is the joint angle in degrees. The distance returned will be in the same units as `radius`. The function `angle2distance()` is implemented in Ch with the code

```
double angle2distance(double radius, double angle) {
    double distance;
    double pi = 3.14159265358979323846;
    distance = radius*(angle * pi/180);
    return distance;
}
```

It is also possible to convert a distance value into a joint angle value using the counterpart function `distance2angle()`, which has te following syntax

```
angle = distance2angle(radius, distance);
```

where `radius` is the radius of the wheels attached to the Linkbot-I and `distance` is the distance a Linkbot-I has traveled. Both `radius` and `distance` should have the same units. The value `angle` returned from this function is in degrees. The function `distance2angle()` is implemented in Ch as follows

```
double distance2angle(double radius, double distance) {
    double angle;
    double pi = 3.14159265358979323846;
    angle = (distance/radius)*180/pi;
    return angle
}
```

We will solve the same problem presented in the previous section using the member function `getJointAngle()` and function `angle2distance()`.

##### Problem Statement:

A Linkbot-I is configured as a two-wheel robot with wheels attached to joints 1 and 3. The radius of each wheel is 1.75 inches. Write a program `errorindistance.ch` to drive the robot for 12 inches at the speed of 2.5 inches per second. Estimate the error between the specified distance and drived distance.

## 9.1. Move a Two-Wheel Robot with the Specified Distance

```

/* File: errorindistance2.ch
Estimate the error in the distance between the specified and drive distances
using robot.getJointAngle() and angle2distance() */
#include <linkbot.h>
CLinkbotI robot;
double speed = 2.5;           // speed in inches/second
double radius = 1.75;         // radius of the wheel
double distance = 12;         // distance to drive in inches
double angle;                // angle corresponding to the driven distance in degrees
double distance2;             // distance driven based on the angle

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* set the robot speed */
robot.setSpeed(speed, radius);

/* drive the specified distance based on the radius of the wheels */
robot.driveDistance(distance, radius);

/* obtain the angle for joint 1 */
robot.getJointAngle(JOINT1, angle);

/* calculate the distance based on the joint angle */
distance2 = angle2distance(radius, angle);

printf("The distance to drive is %.2lf inches.\n", distance);
printf("The actual distance driven is %.2lf inches.\n", distance2);
printf("The error is %lf inches.\n", distance-distance2);
printf("The error is %lf percent.\n", (distance-distance2)/distance *100);

```

Program 9.4: Estimate the error between the specified distance and driven distance using **angle2distance()**.

### The motion statement

```
robot.driveDistance(distance, radius);
```

is equivalent to the statements

```
angle = distance2angle(radius, distance);
robot.driveForward(angle);
```

### The motion statement

```
robot.getDistance(distance, radius);
```

is equivalent to the statements

```
robot.getJointAngle(JOINT1, angle);
distance = angle2distance(radius, angle);
```

The member function **getJointAngle()** is used to get the value of the joint angle after the Linkbot has stopped moving, then the statement

```
distance2 = angle2distance(radius, angle);
```

gives the actual distance in inches that were traveled by the Linkbot.

When Program 9.4 is executed, the output will be similar to that of Program 9.3.

 Do Exercise 4 on page 133.

## 9.1. Move a Two-Wheel Robot with the Specified Distance

**9.1.5 Get the Time for a Two-Wheel Robot to Complete its Movement with the Specified Speed and Distance**

In Program 8.6 we measured how long it took for a Linkbot-I to complete a motion of a specified joint for a specified angle. The member function **systemTime()** can be used in many other applications. One example is measuring the time it takes for a Linkbot-I to complete its movement with a specified speed and distance.

**Problem Statement:**

A Linkbot-I is configured as a two-wheel robot with wheels attached to joints 1 and 3. The radius of each wheel is 1.75 inches. Write a program **gettime.ch** to drive the robot forward 10 inches at the speed of 2.5 inches per second. The program shall measure how long it takes for the robot to complete the motion.

```
/* File: gettime.ch
   Get the time to drive the vehicle with a specified speed and distance */
#include <linkbot.h>

CLinkbotI robot;
double speed = 2.5;           // speed in inches/second
double radius = 1.75;         // radius of the wheel
double distance = 10;         // distance in inches
double time1, time2, elapsedtime; // system time and elapsed time

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* set the robot speed */
robot.setSpeed(speed, radius);

robot.systemTime(time1);      // get the system time since the system starts
/* drive the specified distance based on the radius of the wheels */
robot.driveDistance(distance, radius);
robot.systemTime(time2);      // get the system time since the system starts
elapsedtime = time2 - time1; // Calculate the time for the motion.

printf("The motion for the robot took %.2lf seconds\n", elapsedtime);
printf("The motion should take %.2lf seconds in theory.\n", distance/speed);
```

Program 9.5: Get the time for a two-wheel robot to complete a motion with a specified speed and distance using the member function **systemTime()**.

Similar to what was done in Program 8.6, the statement

```
robot.systemTime(time1); //the system time since the system starts
```

is called before the Linkbot-I starts moving in order to record the current system time in seconds. Then the statement

```
robot.driveDistance(distance, radius);
```

drives the Linkbot-I the specified distance of 10 inches at the set speed of 2.5 inches/second. Then the statement

```
robot.systemTime(time2); //the system time since the system starts
```

## 9.1. Move a Two-Wheel Robot with the Specified Distance

is called to record the system time in seconds after the Linkbot-I stops moving. The following statement

```
elapsedtime = time2 - time1;           //calculate the time for the motion.
```

calculates the difference between the end time and the start time, to give the total time the Linkbot was in motion. This time is then displayed, along with the theoretical time. In the case of Linkbot movement with a specified speed and distance, the theoretical time is defined as

$$\text{theoretical time} = \frac{(\text{distance in inches})}{(\text{speed in inches per second})}$$

When Program 9.5 is executed, the following output will be displayed in the input/output pane

```
The motion for the Linkbot-I took 4.12 seconds.  
The motion should take 4.00 seconds in theory.
```

 Do Exercise 5 on page 133.

### 9.1.6 Plot Distances versus Time for a Two-Wheel Linkbot-I with the Specified Speed and Distance

As we learned in Section 8.2, we can record and plot joint angle values versus time for a Linkbot-I. It is also possible to record and plot the distance versus time for a Linkbot. To record distance data, we use the two **CLinkbotI** member functions **recordDistanceBegin()** and **recordDistanceEnd()**.

The general syntax for the function **recordDistanceBegin()** is

```
robot.recordDistanceBegin(id, time, distance, radius, timeInterval);
```

The first argument **id** indicates which joint to begin recording. It should be one of the enumerated values **JOINT1** or **JOINT3**. The second and third arguments **time** and **distance** are variables of type **robotRecordData\_t**. The reason for this is the same as why the **timedata** and **angledata** arguments are of type **robotRecordData\_t** in Program 8.2. Recall that the arguments **time** and **distance** are special arrays that grow to the size needed during the execution of the program. The fourth argument **radius** is the radius of the wheels attached to the Linkbot. The final argument **timeInterval** is the time interval between angle readings. The minimum possible value for **timeInterval** is 0.05 seconds.

The general syntax for the function **recordDistanceEnd()** is

```
robot.recordDistanceEnd(id, num);
```

The argument **id** is the enumerated value of the joint to stop recording. The argument **num** is the total number of data points that were recorded while the Linkbot-I was moving.

We can use the functions **recordDistanceBegin()** and **recordDistanceEnd()** in combination with the member functions of the **CPlot** class we learned in Section 8.2. This will enable the recording and plotting of distance versus time for a two-wheel Linkbot-I.

#### Problem Statement:

A Linkbot-I is configured as a two-wheel robot with wheels attached to joints 1 and 3. The radius of each wheel is 1.75 inches. Write a program **recorddistance.ch** to drive the Linkbot for 12 inches at the speed of 2.5 inches per second. Record the distance as the Linkbot moves with a time interval of 0.1 second. Plot the distance versus time.

## 9.1. Move a Two-Wheel Robot with the Specified Distance

```

/* File: recorddistance.ch
   Record time and distances, plot the acquired data */
#include <linkbot.h>
#include <chplot.h>
CLinkbotI robot;
double speed = 2.5;           // speed in 2.5 inches/seconds
double radius = 1.75;         // radius of the wheel in inches
double distance = 12;         // distance in inches
double timeInterval = 0.1;    // time interval in 0.1 second
int numDataPoints;            // number of data points recorded
robotRecordData_t timedata, distances; // recorded time and distances
CPlot plot;                  // plotting class

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* set the robot speed */
robot.setSpeed(speed, radius);

/* begin recording time and distance based on joint 1 */
robot.recordDistanceBegin(JOINT1, timedata, distances, radius, timeInterval);

/* drive the specified distance based on the radius of the wheels */
robot.driveDistance(distance, radius);

/* end recording time and distance */
robot.recordDistanceEnd(JOINT1, numDataPoints);

/* plot the data */
plot.mathCoord();
plot.title("Distance versus time");
plot.label(PLOT_AXIS_X, "Time (seconds)");
plot.label(PLOT_AXIS_Y, "Distance (inches)");
plot.data2DCurve(timedata, distances, numDataPoints);
plot.plotting();

```

Program 9.6: Plotting the distance of a Linkbot-I versus time for a two-wheel robot with a specified distance.

Similar to Program 8.2, we begin the recording of time and distance before the Linkbot-I starts moving. The statement

```
robot.recordDistanceBegin(JOINT1, timedata, distances, radius, timeInterval);
```

starts recording data from joint 1 of the Linkbot-I every 0.1 second. After the Linkbot stops moving, the statement

```
robot.recordDistanceEnd(JOINT1, numDataPoints);
```

stops recording data from joint 1.

When a two-wheel robot moves at the speed of 2.5 inches per second, the relation between the distance ( $d$ ) and time ( $t$ ) in Figure 9.2 can be formulated by the following linear equation.

$$d = 2.5t \quad (9.1)$$

 Do Exercise 6 on page 133.

If we change the statement

## 9.1. Move a Two-Wheel Robot with the Specified Distance

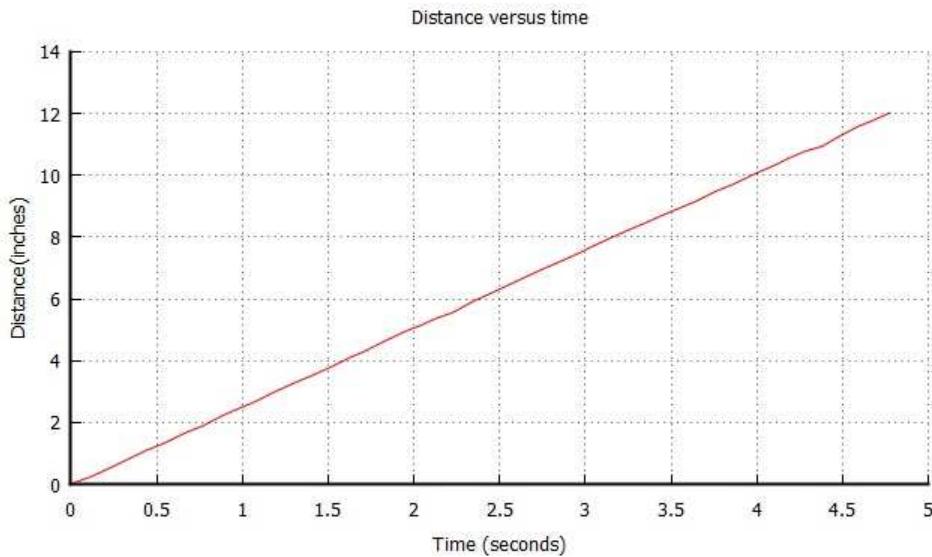


Figure 9.2: The plot for the distance versus time from Program 9.6.

```
robot.driveDistance(distance, radius);
```

in Program 9.6 to

```
robot.driveDistance(-distance, radius);
```

to drive the Linkbot-I in the opposite direction. The plot generated by such a program recorddistance.neg.ch is shown in Figure 9.3.

If we change the statement

```
robot.setSpeed(speed, radius);
```

in Program 9.6 to

```
robot.setSpeed(-speed, radius);
```

to drive the Linkbot-I in the opposite direction. the program will also generate Figure 9.3.

The relation between the distance ( $d$ ) and time ( $t$ ) in Figure 9.3 can be formulated by the following equation.

$$d = -2.5t \quad (9.2)$$

## 9.1. Move a Two-Wheel Robot with the Specified Distance

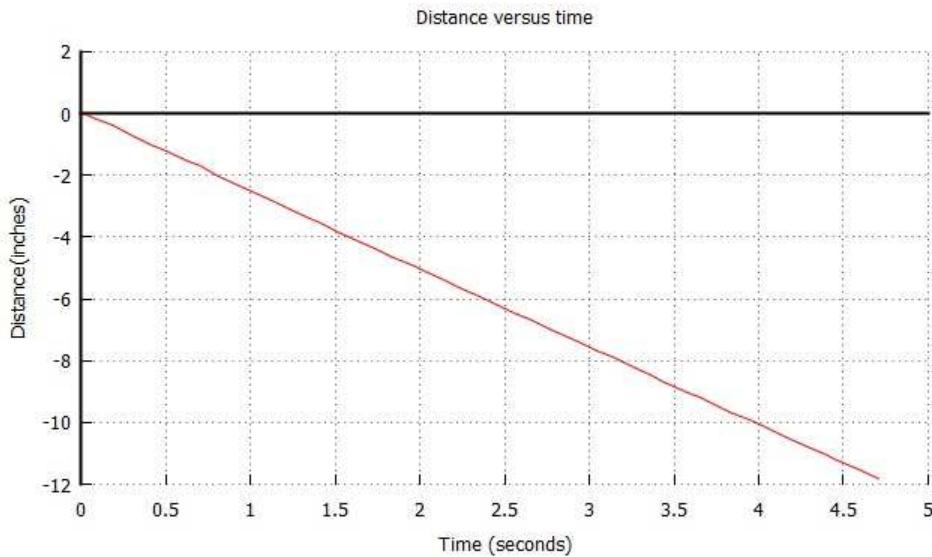


Figure 9.3: The plot for the distance versus time for a Linkbot-I moving in the negative direction from the program `recorddistance.neg.ch` with a specified distance.

Do Exercise 7 on page 134.

### 9.1.7 Plot Distances versus Time with an Offset for the Distance

For plotting distances versus time with the specified speed and distance in the previous section, it is assumed that the robot is placed in the origin. We have learned in Chapter 4 that a robot can be placed at different locations in a coordinate system. In this section, we will learn how to plot the distances versus time with an initial offset for the distance. The ideas presented in this section can be used to handle the distance offset in other situations which will be described in the next section as well.

The offset for the distance of a robot can be added by the member function `recordDistanceOffset()`. The general syntax for the function `recordDistanceOffset()` is

```
robot.recordDistanceOffset(offset)
```

The argument `offset` of type **double** is the offset of the distance.

When the member function `recordDistanceBegin()` is called by

```
robot.recordDistanceBegin(JOINT1, timedata, distances, radius, timeInterval);
```

the time and distances will be recorded in the variables `timedata` and `distances`. The offset set by the member function `recordDistanceOffset()` will be added to the `distances` for each sampling point. Therefore, The member function `recordDistanceOffset()` should be called before the member function `recordDistanceBegin()` is called.

#### Problem Statement:

A Linkbot-I is configured as a two-wheel robot with wheels attached to joints 1 and 3. The radius of each wheel is 1.75 inches. The robot is placed in an X-Y coordinate system at the coordinate (0, 4). Write a program `recorddistanceoffset.ch` to drive the Linkbot for 8 inches at the speed of 2.5 inches per second. Record the distance as the Linkbot moves with a time interval of 0.1 second. Plot the distance versus time.

## 9.1. Move a Two-Wheel Robot with the Specified Distance

```

/* File: recorddistanceoffset.ch
   Record time and distances with an initial offset distance by
       robot.recordDistanceOffset(offset);
   plot the acquired data */
#include <linkbot.h>
#include <chplot.h>
CLinkbotI robot;
double speed = 2.5;           // speed in 2.5 inches/seconds
double radius = 1.75;         // radius of the wheel in inches
double distance = 8;          // distance in inches
double offset = 4;            // the offset for the initial distance
double timeInterval = 0.1;    // time interval in 0.1 second
int numDataPoints;           // number of data points recorded
robotRecordData_t timedata, distances; // recorded time and distances
CPPlot plot;                 // plotting class

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* set the robot speed */
robot.setSpeed(speed, radius);

/* set the offset of the distance */
robot.recordDistanceOffset(offset);

/* begin recording time and distance based on joint 1 */
robot.recordDistanceBegin(JOINT1, timedata, distances, radius, timeInterval);

/* drive the specified distance based on the radius of the wheels */
robot.driveDistance(distance, radius);

/* end recording time and distance */
robot.recordDistanceEnd(JOINT1, numDataPoints);

/* plot the data */
plot.mathCoord();
plot.title("Distance versus time");
plot.label(PLOT_AXIS_X, "Time (seconds)");
plot.label(PLOT_AXIS_Y, "Distance (inches)");
plot.axisRange(PLOT_AXIS_Y, 0, 14);
plot.ticsRange(PLOT_AXIS_Y, 1);
plot.data2DCurve(timedata, distances, numDataPoints);
plot.plotting();

```

Program 9.7: Plotting the distance of a Linkbot-I versus time for a two-wheel robot with a specified distance with an initial offset for the distance.

Comparing Program 9.7 with Program 9.6, we changed the line

```
double distance = 12;      // distance in inches
```

in Program 9.6 to

```
double distance = 8;        // distance in inches
double offset = 4;          // the offset for the initial distance
```

in Program 9.7 with the new distance of 8 inches and the offset of 4 inches. The offset for the distance is added to each recorded distance by the statement

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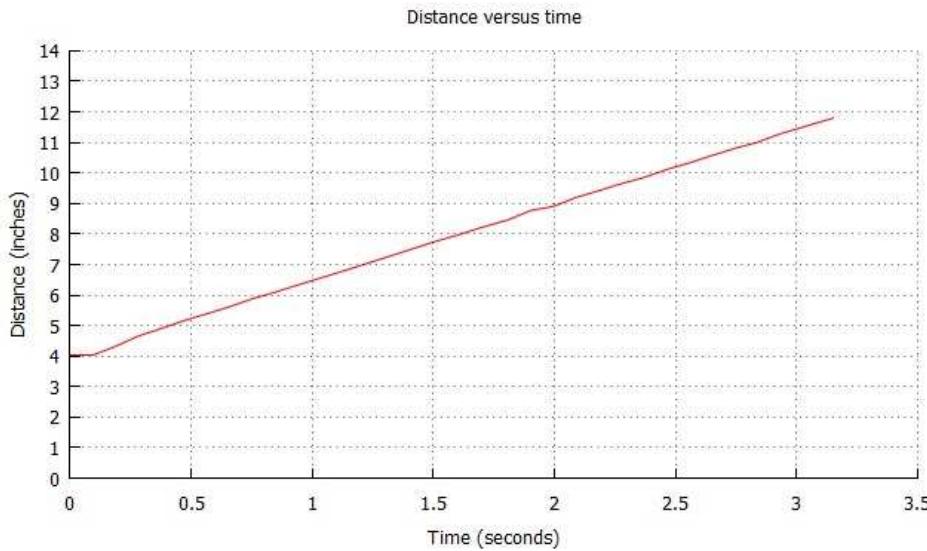


Figure 9.4: The plot for the distance versus time from Program 9.7.

```
robot.recordDistanceOffset(offset);
```

When Program 9.7 is executed, the plot shown in Figure 9.4 will be displayed. The linear relation shown in Figure 9.4 can be formulated by the equation

$$d = 4 + 2.5t \quad (9.3)$$

When  $t$  is 3.2 seconds, the distance is 12 inches.

The offset is the y-intercept of this linear equation. To show the y-intercept, Program 9.7 calls the member function **axisRange** of the plotting class **CPlot** to set the range of the y axis . The general syntax of the member function **axisRange** is as follows.

```
plot.axisRange(axis, minimum, maximum);
```

The first argument **axis** specifies the axis. The macros **PLOT\_AXIS\_X** and **PLOT\_AXIS\_Y** can be used for **axis** to specify the x and y axes, respectively. The second argument **minimum** is for the minimum value on the axis. The third argument **maximum** is for the maximum value on the axis.

The tick marks on an axis can be set by the member function **ticsRange** as follows.

```
plot.ticsRange(axis, incr);
```

Like the member function **plot.axisRange()**, the first argument **axis** specifies the axis. The second argument **incr** gives the increment between tick marks.

The two statements

```
plot.axisRange(PLOT_AXIS_Y, 0, 14);
plot.ticsRange(PLOT_AXIS_Y, 1);
```

in Program 9.7 set the range for the y axis from 0 to 14 with the increment value of 1 between two tick marks.

Do Exercise 8 on page 134.

The offset can also be created by a separate motion statement before the data recording starts. In the program **recorddistanceoffset2.ch** distributed along with the other programs in this book, the statement

## 9.1. Move a Two-Wheel Robot with the Specified Distance

```
robot.recordDistanceOffset(offset);
```

is replaced by the statement

```
robot.driveDistance(offset, radius);
```

The program `recorddistanceoffset2.ch` will generate the same plot as shown in Figure 9.4.

To run Program 9.7 in RoboSim, the robot needs to be placed at the coordinate (0, 4). However, to run the program `recorddistanceoffset2.ch`, the robot should be placed at the origin (0, 0).

 Do Exercise 9 on page 134.

### 9.1.8 Summary

1. Call the **CLinkbotI** member function

```
robot.setSpeed(speed, radius);
```

to set both joints 1 and 3 of a Linkbot-I to the desired speed and wheel radius.

2. Call the function

```
distance = angle2distance(radius, angle);
```

to convert a joint angle value to a distance.

3. Call the function

```
angle = distance2angle(radius, distance);
```

to convert a distance to a joint angle value.

4. Call the **CLinkbotI** member function

```
robot.recordDistanceBegin(id, time, distance, radius, timeInterval);
```

to start recording time and distance values for a joint angle of a Linkbot-I, for a specified wheel radius and a specified interval between distance readings.

5. Call the **CLinkbotI** member function

```
robot.recordDistanceEnd(id, num);
```

to stop recording time and distance values for a joint angle of a Linkbot-I.

6. Call the **CLinkbotI** member function

```
robot.recordDistanceOffset(offset);
```

to add an offset to the recorded distance by the member function `recordDistanceBegin()`.

7. Call the **CPlot** member function

## 9.1. Move a Two-Wheel Robot with the Specified Distance

```
plot.axisRange(axis, minimum, maximum);
plot.ticsRange(axis, incr);
```

to set the range of an axis.

- Call the **CPlot** member function

```
plot.ticsRange(axis, incr);
```

to set the increment between tick marks for an axis.

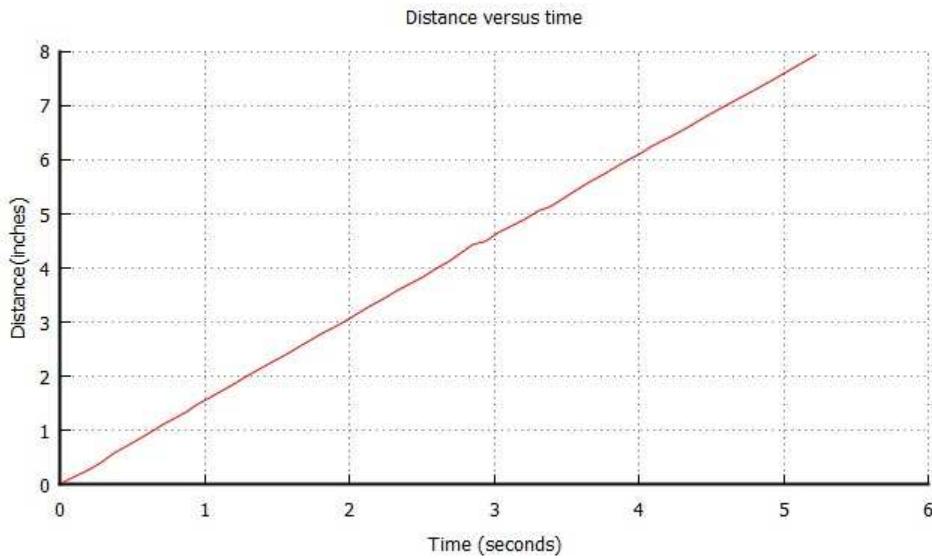
### 9.1.9 Terminology

**angle2distance()**, **distance2angle()**, **plot.axisRange()**, **plot.ticsRange()**, **robot.recordDistanceBegin()**, **robot.recordDistanceEnd()**, **robot.recordDistanceOffset()**, **robot.setSpeed()**.

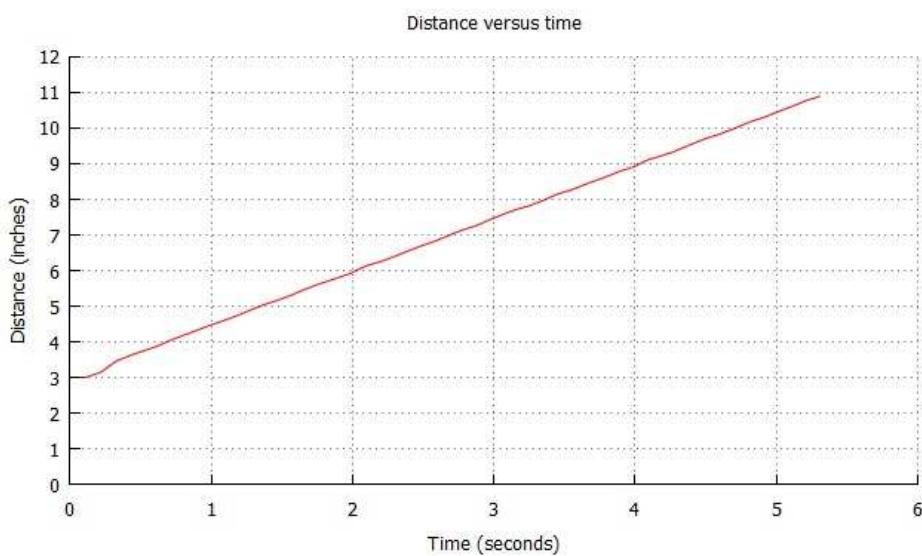
### 9.1.10 Exercises

- A Linkbot-I is configured as a two-wheel robot with wheels attached to joints 1 and 3. The radius of each wheel is 1.75 inches. Write a program `setspeed2.ch` to drive forward 360 degrees using the member function **driveForward()** at the speed of 2.5 inches per second, and then drive backward 3 inches using the member function **driveDistance()**.
- A Linkbot-I is configured as a two-wheel robot with wheels attached to joints 1 and 3. The radius of each wheel is 1.75 inches. Use the program `drivedistance_p.ch` in Program 9.2 to make the Linkbot-I move 12 inches in 5 seconds (Note that the speed is defined as the distance divided by the time).
- A Linkbot-I is configured as a two-wheel robot with wheels attached to joints 1 and 3. The radius of each wheel is 1.75 inches. Write a program `errorindistance3.ch` to accept the user input of the radius of wheels, speed, and distance for moving the robot using the member function **driveDistance()**. The program shall estimate the distance that the robot has moved using the member function **getDistance()**. It shall also calculate the error and percentage of error of the distance moved. (a) Test your program with the input speed of 2.5 inches per second and distance of 12 inches. (b) Test your program with the input speed of 2.5 inches per second and distance of 2 inches.
- Solve the same problem described in Exercise 3 without using the member function **getDistance()**.
- A Linkbot-I is configured as a two-wheel robot with wheels attached to joints 1 and 3. The radius of each wheel is 1.75 inches. Write a program `gettime2.ch` to drive the robot for 12 inches at the speed of 3.2 inches per second. The program shall measure how long it takes for the robot to complete the motion using the member function **systemTime()**. Also try to measure this motion using a stopwatch. Is the time measured by the program `gettime2.ch` the same as that on a stopwatch? Why?
- A Linkbot-I is configured as a two-wheel robot with wheels attached to joints 1 and 3. The radius of each wheel is 1.75 inches. Write a program `recorddistance2.ch` to drive the Linkbot 8 inches forward at the speed of 1.5 inches per second. Record the distance as the Linkbot travels with a time interval of 0.1 second. Plot the distance versus time as shown in the figure below. What is the equation of motion with the linear relation shown in the figure?

## 9.1. Move a Two-Wheel Robot with the Specified Distance



7. Modify the program `recorddistance2.ch` developed in Exercise 6 as the program `recorddistanceneg2.ch` to drive the Linkbot 8 inches *backward*, instead of forward, at the speed of 1.5 inches per second. Plot the distance versus time. What is the equation of motion for the robot?
8. A Linkbot-I is configured as a two-wheel robot with wheels attached to joints 1 and 3. The radius of each wheel is 1.75 inches. The robot is placed in an X-Y coordinate system at the coordinate (0, 3). Write a program `recorddistanceoffset3.ch` to drive the Linkbot 8 inches forward at the speed of 1.5 inches per second. Record the distance as the Linkbot travels with a time interval of 0.1 second. Plot the distance versus time as shown in the figure below. What is the equation of motion with the linear relation shown in the figure?



9. Modify the program `recorddistanceoffset3.ch` developed in Exercise 8 as the program `recorddistanceoffset4.ch` by replacing the statement

## 9.2. Move a Two-Wheel Robot with the Specified Time

```
robot.recordDistanceOffset(offset);
```

with the statement

```
robot.driveDistance(offset, radius);
```

## 9.2 Move a Two-Wheel Robot with the Specified Time

### 9.2.1 Control a Linkbot-I with the Speed and Time Input from the User Using the Function `scanf()`

In Section 9.1.2 we learned how to set the speed and distance of a Linkbot-I with user input. In this section, we will see that we can also set the speed and time of a Linkbot-I's motion with user input.

**Problem Statement:**

A Linkbot-I is configured as a two-wheel robot with wheels attached to joints 1 and 3. The radius of each wheel is 1.75 inches. Write a program `drivetime_p.ch` to accept the user input of speed and time for moving the robot using the member function `driveTime()`.

```
/* File: drivetime_p.ch
   Move a two-wheel robot with the user specified radius of wheels, speed, and time. */
#include <linkbot.h>
CLinkbotI robot;
double radius;           // the radius of the two wheels of the robot in inches
double speed;            // the speed in inches per second for a two-wheel robot
double time;             // time for the movement

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

printf("Enter the radius of the two wheels in inches\n");
scanf("%lf", &radius);

printf("Enter the speed of the two-wheel robot in inches per second\n");
scanf("%lf", &speed);
/* set the speed for a two-wheel robot */
robot.setSpeed(speed, radius);

printf("Enter the time in seconds for the two-wheel robot to drive\n");
scanf("%lf", &time);
/* rotate joints 1 and 3 for the specified 'time' */
robot.driveTime(time);
```

Program 9.8: Using the input function `scanf()` to specify the speed and time.

In Program 8.3, the member function `moveTime()` is used to move joints of a robot for a user defined amount of time. The direction of the motion depending on the sign of the speed specified for each joint.

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Program 9.8 uses the member function **driveTime()** to drive a Linkbot-I forward or backward depending on the joint speed for joint 1 or the speed specified by the member function **setSpeed()**. The general syntax of the function **driveTime()** is

```
robot.driveTime(seconds);
```

The argument, `seconds`, defines how long each joint will be moved in seconds. The robot moves forward if the speed for joint 1 is positive. The robot moves backward if the speed for joint 1 is negative.

The function **scanf()** is used to obtain the values for the variables `radius`, `speed`, and `time`. For a review on how to use **scanf()**, see Section 5.3.

An interactive execution of Program 9.8 is shown below.

```
Enter the radius of the wheels in inches
1.75
Enter the speed of the two-wheel robot in inches per second
1
Enter the time in seconds for the two-wheel robot to drive
10
```

For a Linkbot-I configured as a two-wheel robot with the radius of 1.75 inches for wheels, the above execution will move the Linkbot at the speed of 1 inch per second for 10 seconds.

 Do Exercise 1 on page 140.

### 9.2.2 Get the Moved Distance Based on the Specified Speed and Time

In Section 9.1.3 we learned how to get the actual distance traveled by a Linkbot using **getDistance()**. This distance was compared with the distance specifically given to the program to determine the error in distance. In this section the function **getDistance()** will be used to determine the distance traveled by a Linkbot-I when a distance is not specifically given in the program.

#### Problem Statement:

A Linkbot-I is configured as a two-wheel robot with wheels attached to joints 1 and 3. The radius of each wheel is 1.75 inches. Write a program `getdistance.ch` to drive the robot forward 5.5 seconds at the speed of 2.5 inches per second. The program shall measure the distance that the robot has driven.

The distance to drive can be calculated using the formula

$$d = speed * t$$

with the specified speed and time  $t$ .

## 9.2. Move a Two-Wheel Robot with the Specified Time

```

/* File: getdistance.ch
   Get the distance driven in the specified speed and time using robot.getDistance() */
#include <linkbot.h>
CLinkbotI robot;
double speed = 2.5;           // speed in inches/second
double radius = 1.75;         // radius of the wheel
double time = 5.5;           // 5.5 seconds
double distance;             // distance traveled

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* set the robot speed */
robot.setSpeed(speed, radius);

/* rotate joints 1 and 3 for the specified 'time' */
robot.driveTime(time);

/* get the distance driven */
robot.getDistance(distance, radius);

printf("The distance driven is %.2lf inches.\n", distance);
printf("The distance to drive is %.2lf inches in theory.\n", speed*time);

```

Program 9.9: Get the distance of a two-wheel robot based on the specified speed and time using **angle2distance()**.

Program 9.3 used the member function **driveDistance()** to drive the Linkbot-I for a specified distance. Program 9.9 is very similar to Program 9.3. The only difference in Program 9.9 is that the member function **driveTime()** is used to drive the Linkbot-I for a specified period of time. Because a distance was not specifically given to the program, the actual distance traveled is obtained using the function **getDistance()**. A theoretical distance is calculated using the variables **speed** and **time**, for comparison to the actual distance moved.

When Program 9.9 is executed, the following output will be displayed in the input/output pane

```

The distance driven is 13.78 inches.
The distance to drive is 13.75 inches in theory.

```

 Do Exercise 2 on page 140.

### 9.2.3 Plot Distances versus Time for a Two-Wheel Linkbot-I with the Specified Speed and Time

In Section 9.1.6 we recorded and plotted distance versus time for a specified distance. In this section we will record and plot distance versus time for a specified speed. To do this we can use the member functions **recordDistanceBegin()** and **recordDistanceEnd()** that were introduced in Section 9.1.6. These functions are versatile and can be used to record distance data for a Linkbot performing many different kinds of motions.

#### Problem Statement:

A Linkbot-I is configured as a two-wheel robot with wheel attached to joints 1 and 3. The radius of each wheel is 1.75 inches. Write a program **recordspecifytime.ch** to drive

## 9.2. Move a Two-Wheel Robot with the Specified Time

the Linkbot-I for 16 seconds at the speed of 2.5 inches per second. Record the distance as the Linkbot-I moves with a time interval of 0.1 second. Plot the distance versus time.

```
/* File: recordspecifytime.ch
   Record time and distances, plot the acquired data */
#include <linkbot.h>
#include <chplot.h>
CLinkbotI robot;
double speed = 2.5;           // speed in 1.5 inches/seconds
double radius = 1.75;         // radius of the wheel in inches
double timeInterval = 0.1;    // time interval in 0.1 second
double time = 16;             // total travel time
int numDataPoints;           // number of data points recorded
robotRecordData_t timedata, distances; // recorded time and distances
CPlot plot;                  // plotting class

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* set the robot speed to 'speed' */
robot.setSpeed(speed, radius);

/* begin recording time and distance */
robot.recordDistanceBegin(JOINT1, timedata, distances, radius, timeInterval);

/* drive the robot for the specified 'time' */
robot.driveTime(time);

/* end recording time and distance */
robot.recordDistanceEnd(JOINT1, numDataPoints);

/* plot the data */
plot.mathCoord();
plot.title("Distance versus time");
plot.label(PLOT_AXIS_X, "Time (seconds)");
plot.label(PLOT_AXIS_Y, "Distance (inches)");
plot.data2DCurve(timedata, distances, numDataPoints);
plot.plotting();
```

Program 9.10: Plotting the distance of a Linkbot-I versus time for a two-wheel robot with a specified time.

In Program 9.6 we recorded data for a Linkbot moving forward for 16 seconds using **driveDistance()**. Program 9.10 is very similar to Program 9.6. The difference is that **driveTime()** now we use to drive a Linkbot-I forward for 16 seconds. Even though a different movement function was used, **recordDistanceBegin()** and **recordDistanceEnd()** can still be used to collect data on this movement.

When a two-wheel robot moves at the speed of 2.5 inches per second, the relation between the distance ( $d$ ) and time ( $t$ ) in Figure 9.5 can be formulated by the following linear equation.

$$d = 2.5t \quad (9.4)$$

Similarly, if we change the statement

```
robot.setSpeed(speed, radius);
```

in Program 9.10 to

## 9.2. Move a Two-Wheel Robot with the Specified Time

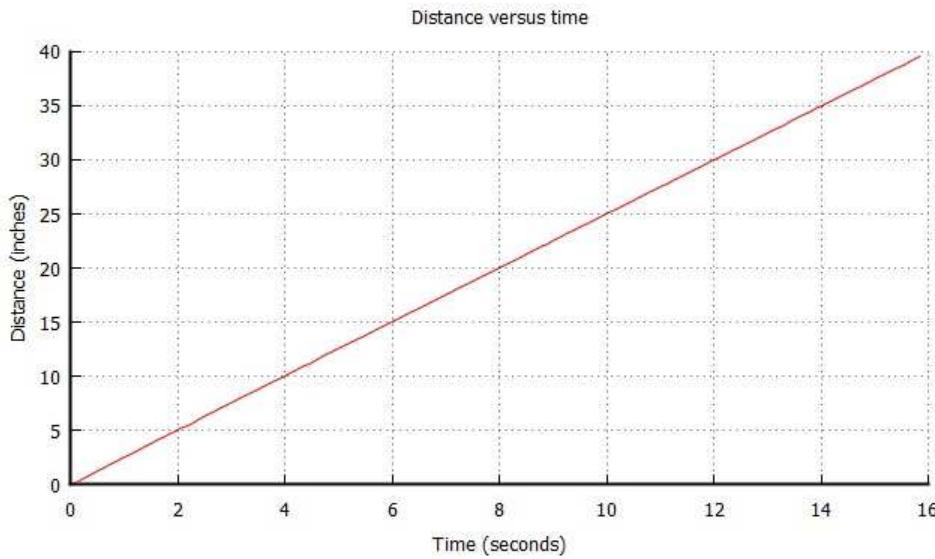


Figure 9.5: The plot for the distance versus time from Program 9.10.

```
robot.setSpeed(-speed, radius);
```

to drive the Linkbot-I in the opposite direction. The plot generated by such a program recordspecifytimeneg.ch is shown in Figure 9.6. The relation between the distance ( $d$ ) and time ( $t$ ) in Figure 9.6 can be formulated by the following equation.

$$d = -2.5t \quad (9.5)$$

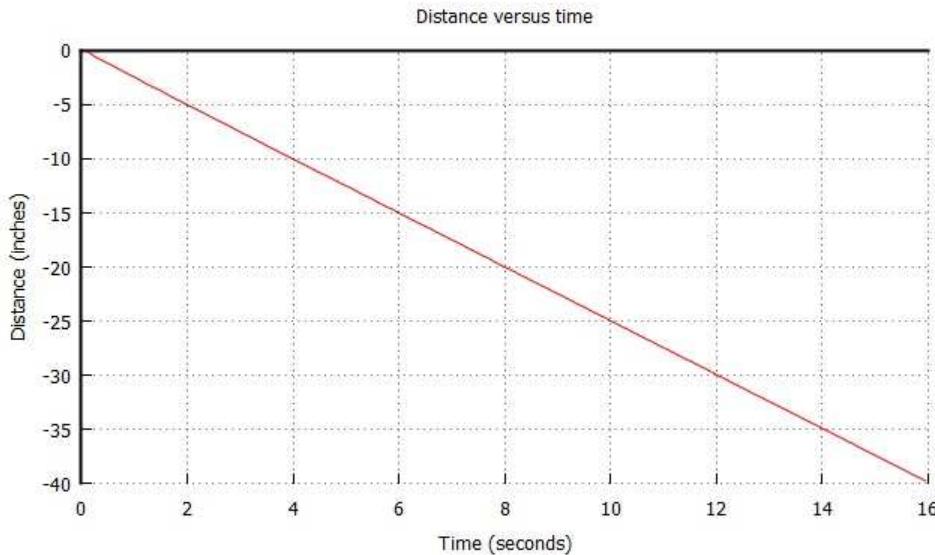


Figure 9.6: The plot for the distance versus time for a Linkbot-I moving in the negative direction from the program recordspecifytimeneg.ch with a specified time .

Do Exercise 3 on page 140.

## 9.2. Move a Two-Wheel Robot with the Specified Time

**9.2.4 Summary**

1. Call the **CLinkbotI** member function

```
robot.driveTime(time);
```

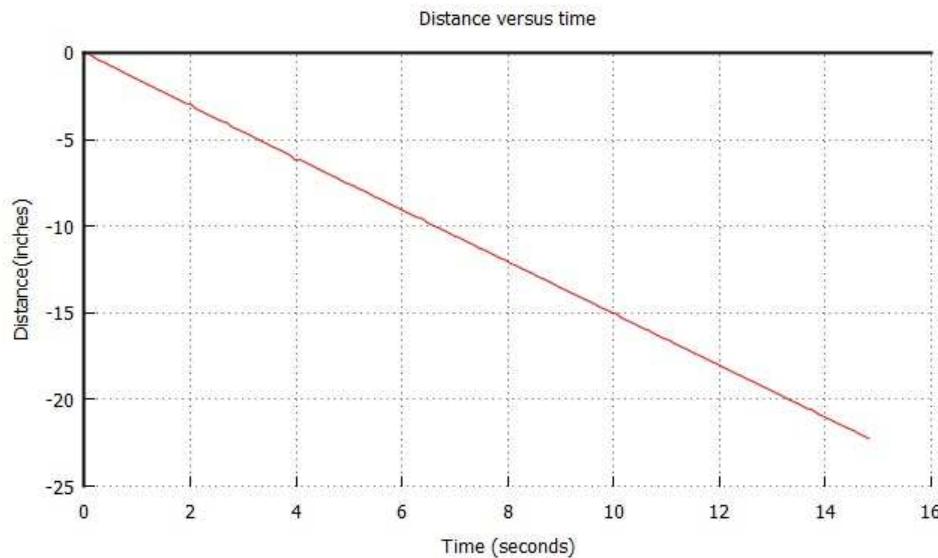
to drive a Linkbot-I for a specified time rather than a specified distance.

**9.2.5 Terminology**

**robot.driveTime()**.

**9.2.6 Exercises**

1. A Linkbot-I is configured as a two-wheel robot with wheels attached to joints 1 and 3. The radius of each wheel is 1.75 inches. Use the program `drivetime_p.ch` in Program 9.8 to make the Linkbot-I move 12 inches in 5 seconds (Note that the speed is defined as the distance divided by the time).
2. A Linkbot-I is configured as a two-wheel robot with wheels attached to joints 1 and 3. The radius of each wheel is 1.75 inches. Write a program `getdistance3.ch` to drive the robot for 4.5 seconds at the speed of 3.2 inches per second. The program shall measure the distance that the robot has driven.
3. A Linkbot-I is configured as a two-wheel robot with wheels attached to joints 1 and 3. The radius of each wheel is 1.75 inches. Write a program `recordspecifytime2.ch` to drive the Linkbot backward for 15 seconds at the speed of 1.5 inches per second by the member function **driveTime()**. Record the distance as the Linkbot travels with a time interval of 0.1 second. Plot the distance versus time as shown in the figure below. What is the equation for the linear relation shown in the figure?



## 9.3 Use Different Units for Speed, Radius, and Distance

The arguments of member functions `setSpeed()` and `driveDistance()` of the `CLinkbotI` class as well as functions `distance2angle()` and `angle2distance()` involve speed, radius, and distance. They are typically used in programs in the following format.

```
robot.setSpeed(speed, radius);
robot.driveDistance(distance, radius);
distance = angle2distance(radius, angle);
angle = distance2angle(radius, distance);
```

We can use different units for speed, radius, and distance conveniently to control a Linkbot-I so long as they are consistent using the same unit for length. Samples of consistent units for speed, radius, and distance are shown in Table 9.1.

Table 9.1: The commonly used units for speed, radius, and distance.

| Speed  | Radius | Distance | Description |
|--------|--------|----------|-------------|
| cm/s   | cm     | cm       | centimeters |
| m/s    | m      | m        | meters      |
| inch/s | inch   | inch     | inches      |
| foot/s | foot   | foot     | feet        |

### Problem Statement:

A Linkbot-I is configured as a two-wheel robot with wheels attached to joints 1 and 3. The radius of each wheel is 4.445 centimeters. Write a program `recorddistancecm.ch` to drive the Linkbot for 20 centimeters at the speed of 6.5 centimeters per second. Record the distance as the Linkbot moves with a time interval of 0.1 second. Plot the distance versus time.

### 9.3. Use Different Units for Speed, Radius, and Distance

```

/* File: recorddistancecm.ch
   Record time and distances, plot the acquired data, using centimeters */
#include <linkbot.h>
#include <chplot.h>
CLinkbotI robot;
double speed = 6.5;           // speed in 6.5 centimeters/seconds
double radius = 4.445;        // radius of the wheel in centimeters
double distance = 20;         // distance in centimeters
double timeInterval = 0.1;    // time interval in 0.1 second
int numDataPoints;           // number of data points recorded
robotRecordData_t timedata, distances; // recorded time and distances
CPlot plot;                  // plotting class

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* set the robot speed */
robot.setSpeed(speed, radius);

/* begin recording time and distance */
robot.recordDistanceBegin(JOINT1, timedata, distances, radius, timeInterval);

/* drive the specified distance based on the radius of the wheels */
robot.driveDistance(distance, radius);

/* end recording time and distance */
robot.recordDistanceEnd(JOINT1, numDataPoints);

/* plot the data */
plot.mathCoord();
plot.title("Distance versus time");
plot.label(PLOT_AXIS_X, "Time (seconds)");
plot.label(PLOT_AXIS_Y, "Distance (centimeters)");
plot.data2DCurve(timedata, distances, numDataPoints);
plot.plotting();

```

Program 9.11: Plotting the distance of a Linkbot-I versus time for a two-wheel robot with the specified distance in centimeters.

Program 9.11 is nearly identical to Program 9.6. The only difference is the values for `speed`, `radius`, and `distance` are all in centimeters instead of inches. Because all these values have consistent length units, they can be used as arguments of the functions `setSpeed()`, `driveDistance()`, `distance2angle()`, and `angle2distance()` without error.

When a two-wheel robot moves at the speed of 6.5 centimeters per second, the relation between the distance ( $d$ ) and time ( $t$ ) in Figure 9.7 can be formulated by the following linear equation.

$$d = 6.5t \quad (9.6)$$

 Do Exercises 1, 2, and 3 on page 143.

#### 9.3.1 Summary

1. The values for speed, radius, and distance can be expressed in centimeters, meters, inches, or feet as long as the units used for length are consistent.

### 9.3. Use Different Units for Speed, Radius, and Distance

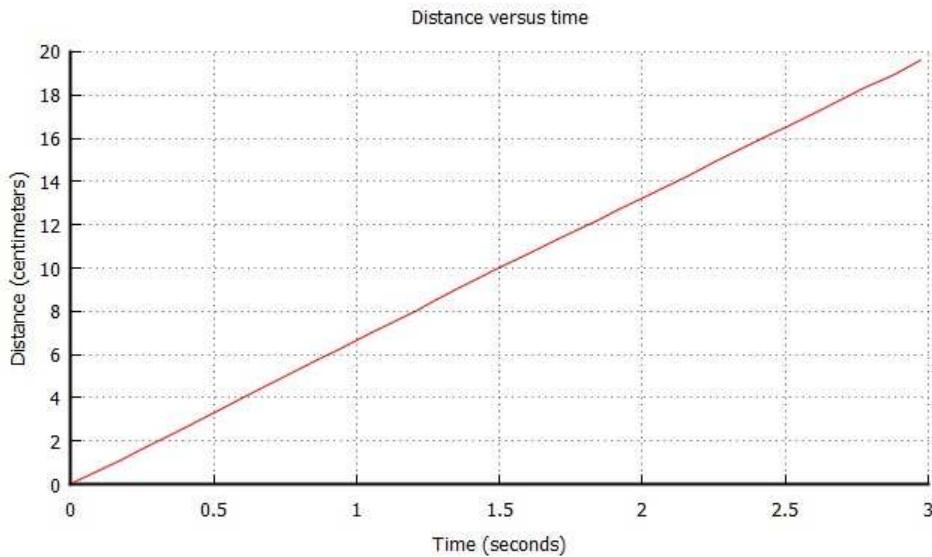


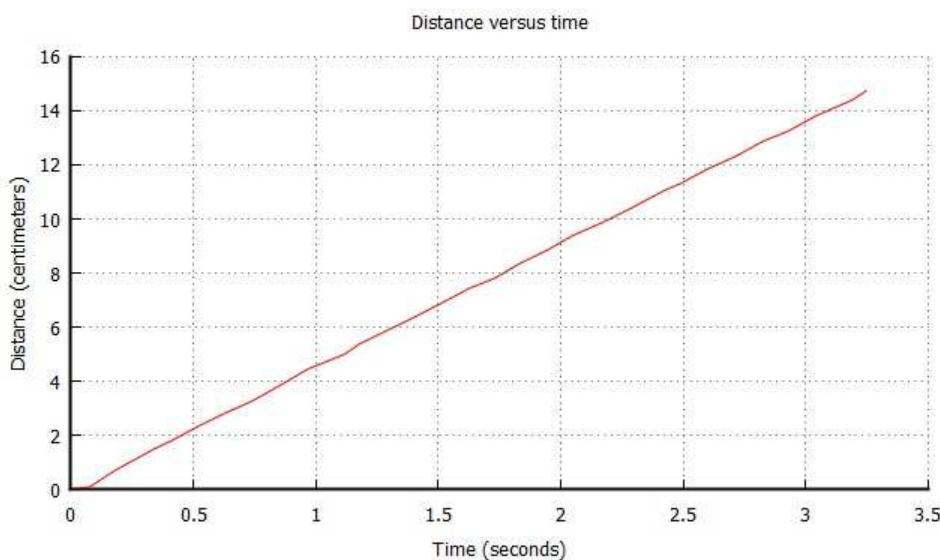
Figure 9.7: The plot for the distance versus time from Program 9.11.

#### 9.3.2 Terminology

different length units, consistent length units.

#### 9.3.3 Exercises

1. A Linkbot-I is configured as a two-wheel robot with wheels attached to joints 1 and 3. The radius of each wheel is 4.445 centimeters. Write a program `recorddistancecm2.ch` to drive the Linkbot 15 centimeters at the speed of 4.5 centimeters per second. Record the distance as the Linkbot-I travels with a time interval of 0.1 second. Plot the distance versus time as shown in the figure below. What is the equation for the linear relation shown in the figure?



9.3. Use Different Units for Speed, Radius, and Distance

2. Modify the program `drivedistance_p.ch` in Program 9.2 as the program `drivedistancecm_p.ch` so that the user can enter the radius of wheels in centimeters, speed in centimeters per second, and distance in centimeters to drive a Linkbot-I configured as a two-wheel robot. Test your program by entering the radius of the wheel of your Linkbot, speed of 5 centimeters per second, and distance of 12 centimeters.
3. Modify the program `drivetime_p.ch` in Program 9.8 as the program `drivetimecm_p.ch` so that the user can enter the radius of wheels, speed in centimeters per second, and time in seconds to drive a Linkbot-I configured as a two-wheel robot. Test your program by entering the radius of the wheel of your Linkbot, speed of 5 centimeters per second, and time of 6 seconds.

---

---

## CHAPTER 10

---

# Sensory Information for a Linkbot

In this chapter, we will learn how to control the settings of various sensors on a Linkbot. We will also learn how to retrieve sensory input from a single Linkbot. The types of sensory information available to a Linkbot pertain to the LED, buzzer, accelerometer, and remaining battery charge. As was mentioned in Section 8.2 the ability to acquire sensory information in real time makes it possible for a robot to interact with its environment or with human users.

### 10.1 Set and Get the LED Color by Name Using the Data Type **string\_t**

In Section 3.5 we learned how to set the LED color using a color name. In this section we will learn how to also get the LED color of a Linkbot using a color name. The ability to change the LED color with a computer program opens up the possibility of adding visual effects to a Linkbot choreography. Program 10.1 gives an example of how to set and get the LED color of a Linkbot using the member functions **setLEDColor()** and **getLEDColor()**.

10.1. Set and Get the LED Color by Name Using the Data Type **string\_t**

```
/* File: color.ch
   Set and get the LED color by name */
#include <linkbot.h>

CLinkbotI robot;
string_t color;

robot.connect();

robot.setLEDColor("magenta");
robot.delaySeconds(2);
robot.setLEDColor("green");
robot.delaySeconds(2);
robot.setLEDColor("blue");
robot.delaySeconds(2);
robot.setLEDColor("purple");
robot.delaySeconds(2);
robot.setLEDColor("aqua");
robot.delaySeconds(2);
robot.setLEDColor("orange");
robot.delaySeconds(2);
robot.setLEDColor("pink");      // pink
robot.delaySeconds(2);
robot.setLEDColor("hotPink");  // hot pink
robot.delaySeconds(2);
robot.setLEDColor("deepPink"); // deep pink
robot.getLEDColor(color);
printf("The current color: %s\n", color);
```

Program 10.1: Setting and getting the LED color for a Linkbot-I using a color name.

Program 10.1 uses the **CLinkbotI** member function **setLEDColor()**, which was introduced in Section 3.5, to change the LED color using a color name. The line

```
string_t color;
```

declares a variable of **string\_t** type, which is used to retrieve the name of the LED color. **string\_t** is a special data type used in Ch for strings. A **string\_t** data type consists of any combination of letters or numbers, surrounded by quotation marks. For example, the line

```
robot.setLEDColor("red");
```

uses a **string\_t** data type with the value “red” as the argument to set the LED color to red. The next line

```
robot.delaySeconds(2);
```

pauses the program in order to allow the LED to shine red for two seconds. The following lines

```
robot.setLEDColor("green");
robot.delaySeconds(2);
```

changes the LED color to green for a duration of two seconds. Program 10.1 continues to use **setLEDColor()** to change the LED color to blue, purple, aqua, orange, then three different shades of pink. The first seven colors match the default colors for lines and points in the Ch plot. As was mentioned in Section 3.5, Appendix C lists the 139 color names available for changing the LED color of a Linkbot. If a name other than those listed in Appendix C is used, **setLEDColor()** will print an error message to the input/output panel of ChIDE.

## 10.2. Set and Get the LED Color by RGB Values

It is also possible to get the name of the LED color. The **CLinkbotI** member function **getLEDColor()** is used retrieve the name of the current LED color. Only 137 color names are available for use with **getLEDColor()**, and there are many more than 137 colors in existence. Therefore whenever the current LED color is not a color that is listed in Appendix C, the member function **getLEDColor()** finds and returns the name of the color closest to it. In Program 10.1, the line

```
robot.getLEDColor(color);
```

passes the name of the most recent LED color through its argument of the member function **getLEDColor()**. Since the most recent color set by **setLEDColor()** is deep pink, the value of the argument **color** will be “deepPink” after **getLEDColor()** is called. The final line

```
printf("The current color: %s\n", color);
```

prints the following message to the input/output pane:

```
The current color: deepPink
```

The conversion specifier "%s%" is used to print the value of the variable **color** of the string type.

 Do Exercise 1 on page 147.

### 10.1.1 Summary

1. Call the **CLinkbotI** member function

```
robot.getLEDColor(color);
```

to get the LED color for a Linkbot.

### 10.1.2 Terminology

**robot.getLEDColor()**.

### 10.1.3 Exercises

1. Write a program **color2.ch** to command a Linkbot-I in the following sequence. Change the LED color to green, move the Linkbot forward 360 degrees, change the LED color to yellow, wait for 1 second, move the Linkbot backward 360 degrees, and finally change the LED color to red. Obtain the current color of the LED.

## 10.2 Set and Get the LED Color by RGB Values

In Section 10.1 we learned how to set and get the LED color of a Linkbot by using a color name. In this section we will learn how to change the LED color of a Linkbot using RGB values. We will also learn how to receive data from the Linkbot about the red, green, and blue values of the LED color currently displayed.

A Linkbot uses the RGB color model to control the color of its LED. The **RGB color model** is an additive color model, in which the three primary light colors red, green, and blue are added together in various ways to produce a broad array of colors. The RGB color model is commonly used in cameras, television, and computer monitors to detect, store, and display images. Generally, each of the three primary colors, red, green, and blue, can vary in intensity. The possible values for the intensity of each color range from 0, which

## 10.2. Set and Get the LED Color by RGB Values

is an absence of a primary color, to 255, which is the full intensity of a primary color. Figure 10.1 shows the different ways the primary colors can combine to make the secondary colors as well as white. The values of the intensities of the red, green, and blue color components is listed by each color. A few of the rules for RGB values are as follows

1. If all RGB values are equal, then the color is a gray tone.
2. If all RGB values are 0, the color is black (an absence of light).
3. If all RGB values are 255, the color is white.

The **CLinkbotI** class uses the member function **setLEDColorRGB()** to change the LED color of a Linkbot. This member function has the following general syntax

```
robot.setLEDColorRGB(r, g, b);
```

The argument **r** indicates the amount of red color you want the LED to have, and can be any integer value from 0 to 255. This range of integer values also applies to the arguments **g** for green and **b** for blue. The **CLinkbotI** class uses the member function **getLEDColorRGB()** to retrieve the RGB values of the current LED color. This function has the general syntax

```
robot.getLEDColorRGB(r, g, b);
```

where the arguments **r**, **g**, and **b** return the current intensity values of the primary color components. Program 10.2 shows how to set and get the Led color of a Linkbot-I using RGB values.

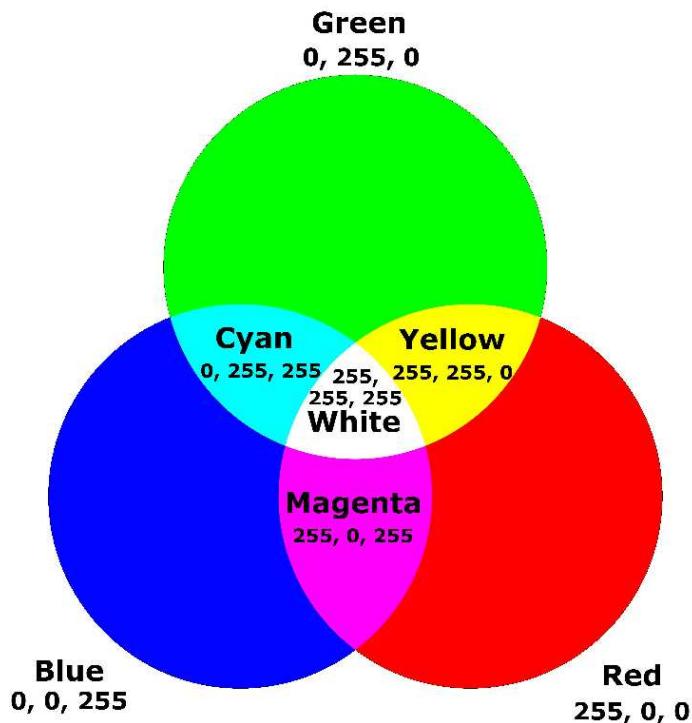


Figure 10.1: The relationship between colors in the RGB color model.

## 10.2. Set and Get the LED Color by RGB Values

```

/* File: colorrgb.ch
   Set and get the LED color by RGB */
#include <linkbot.h>

CLinkbotI robot;
int r, g, b;

robot.connect();
robot.setLEDColorRGB(255, 0, 0);           // red
robot.delaySeconds(2);
robot.setLEDColorRGB(0, 255, 0);           // green
robot.delaySeconds(2);
robot.setLEDColorRGB(0, 0, 255);           // blue
robot.delaySeconds(2);
robot.setLEDColorRGB(255, 255, 0);           // yellow
robot.delaySeconds(2);
robot.setLEDColorRGB(160, 32, 240);           // purple
robot.delaySeconds(2);
robot.setLEDColorRGB(255, 192, 203);           // pink
robot.delaySeconds(2);
robot.setLEDColorRGB(255, 105, 180);           // hot pink
robot.delaySeconds(2);
robot.setLEDColorRGB(255, 20, 147);           // deep pink

robot.getLEDColorRGB(r, g, b);
printf("The RGB value for the current color: %d %d %d\n", r, g, b);

```

Program 10.2: Setting and getting the LED color for a Linkbot-I using RGB values.

Program 10.2 is similar to Program 10.1 in that it shows how to set and get the LED color of a Linkbot-I. In Program 10.2, however, setting and getting the LED color is done using the RGB color model. The first line of the program

```
int r, g, b;
```

declares three **int** type variables **r**, **g**, and **b** to hold the red, green, and blue color values of the LED. These variables will be used to retrieve the LED color values from the Linkbot-I. After the variable **robot** is connected to a Linkbot-I, the following line

```
robot.setLEDColorRGB(255, 0, 0);           // red
```

sets the LED color to red using the **CLinkbotI** member function **setLEDColorRGB()**. Since this function is first used in Program 10.2 to set the LED to red, the value of the argument **r** is 255. This gives the full intensity of the red color component. Since no green or blue is needed in the color mix, the arguments **g** and **b** are both 0, specifying an absence of these colors. After the LED is set to red, the next line

```
robot.delaySeconds(2);
```

pauses the program for 2 seconds. This controls the length of time that the LED continues to shine red. The following line

```
robot.setLEDColorRGB(0, 255, 0);           // green
```

changes the LED to green by setting the argument **g** to 255 while setting both the arguments **r** and **b** to 0. This gives the green color component its full intensity while red and blue have zero intensity. The program is then paused for 2 seconds using the member function **delaySeconds()**, to allow the LED to shine green until the next color change. The line

```
robot.setLEDColorRGB(0, 0, 255);           // blue
```

## 10.2. Set and Get the LED Color by RGB Values

Changes the LED to blue by setting the argument `b` to full intensity while setting the arguments `r` and `g` to zero intensity. After the LED is changed to blue, the program is paused once again for 2 seconds before the next color change. The LED color is not limited to the primary colors red, green, and blue. For instance, the line

```
robot.setLEDColorRGB(255, 255, 0); // yellow
```

mixes red and green to make yellow by setting the values of both `r` and `g` to their full intensity while setting the value of `b` to zero intensity. In addition to mixing primary colors at full intensity, it is possible to mix the primary color components at various intermediate values. For example, the line

```
robot.setLEDColorRGB(255, 192, 203); // pink
```

mixes all three primary colors at intermediate intensities necessary to make the LED pink. Furthermore, by changing the intensities of some of the primary components it is possible to make different shades of pink. For example, Program 10.2 proceeds to change the LED to hot pink and then to deep pink by changing the values of `g` and `b` while keeping `r` at full intensity. The LED is also changed to purple by increasing the intensity of blue while decreasing the intensity of red. The following line

```
robot.getLEDColorRGB(r, g, b);
```

uses the **CLinkbotI** member function **getLEDColorRGB()** to retrieve the red, green, and blue components of the current LED color. Since the last color the LED is set to is deep pink, the values returned in this case are 255 for `r`, 20 for `g`, and 147 for `b`. The final **printf()** statement outputs the following content to the console.

```
The RGB value for the current color: 255, 20, 147
```

 Do Exercises 1 on page 150.

### 10.2.1 Summary

1. Call the **CLinkbotI** member function

```
robot.setLEDColorRGB(r, g, b);
```

to set the color of the LED on a Linkbot.

2. Call the **CLinkbotI** member function

```
robot.getLEDColorRGB(r, g, b);
```

to get the red, green, and blue values of the current LED color.

### 10.2.2 Terminology

**robot.setLEDColorRGB()**, **robot.getLEDColorRGB()**, RGB color model.

### 10.2.3 Exercises

1. Write a program `colorrgb2.ch` that takes user input for the R, G, and B color values of the LED. Then set the LED of a Linkbot-I using these user specified values.

## 10.3 Set the Buzzer Frequency of a Linkbot

In this section, we will learn how to set the buzzer frequency of a Linkbot. We will also learn how to start the buzzer, stop the buzzer, and make the buzzer sound for a specified length of time. A Linkbot's buzzer can be set to an integer value, which indicates the frequency of the buzzer in hertz (Hz). In terms of sound, hertz is defined as

$$1 \text{ Hertz} = \frac{1 \text{ vibration}}{\text{second}}$$

The frequency of a sound determines its pitch. The more vibrations per second, the higher the frequency. And the higher the frequency, the higher the buzzer will sound. The lower the frequency, the lower the buzzer will sound. Although it is possible to use any integer value to set the frequency, generally only frequencies between 20 Hz and 20,000 Hz can be heard by the human ear. Learning how to control the buzzer of a Linkbot enables the user to program a Linkbot to make music.

### 10.3.1 Set the Buzzer to a Specified Frequency

Program 10.3 demonstrates the basics of how to turn the buzzer on at a specified frequency and how to turn it off.

```
/* File: buzzer.ch
   Make a buzz with the frequency 450 for 1 second */
#include <linkbot.h>
CLinkbotI robot;
int freq = 450;           // frequency for the buzz.

robot.connect();
robot.setBuzzerFrequencyOn(freq); // set the buzzer on
robot.delaySeconds(1);          // make a buzz for 1 second
robot.setBuzzerFrequencyOff();  // set the buzzer off
```

Program 10.3: Setting the buzzer frequency for a Linkbot-I.

The line

```
int freq = 450;           // frequency for the buzz.
```

declares a variable `freq` of `int` type and assigns it the value 450. This will be the frequency of the buzz in hertz. After the program connects to a Linkbot, the line

```
robot.setBuzzerFrequencyOn(freq); // set the buzzer on
```

sets the buzzer of the Linkbot to a frequency of 450 Hz and then turns it on. This is done using the `CLinkbotI` member function `setBuzzerFrequencyOn()`. The argument `freq` indicates the desired buzzer frequency. The next line

```
robot.delaySeconds(1);          // make a buzz for 1 second
```

pauses the program to allow the buzzer to sound for one second. The final program statement

```
robot.setBuzzerFrequencyOff();  // set the buzzer off
```

uses the `CLinkbotI` member function `setBuzzerFrequencyOff()` to turn off the buzzer.

 Do Exercise 1, on page 155.

## 10.3. Set the Buzzer Frequency of a Linkbot

**10.3.2 Set the Buzzer Multiple Times Using a while Loop with a User Specified Frequency**

It is also possible to change the frequency of the buzzer to different values, as specified by user input. The frequency can be changed as many times as a user wants within a single program. To do this, we will use a control structure called a loop to control the flow of the program.

```
/* File: buzzer2.ch
   Make a buzz with the frequency specified by the user */
#include <linkbot.h>
CLinkbotI robot;
int freq;
string_t answer = "yes";      /* "yes" to continue, others to quit */

robot.connect();
while(answer == "yes") {
    printf("Please input the frequency for the buzzer\n");
    scanf("%d", &freq);
    robot.setBuzzerFrequencyOn(freq);
    robot.delaySeconds(1);
    robot.setBuzzerFrequencyOff();
    printf("Would you like to enter another frequency? Type yes or no.\n");
    scanf("%s", &answer);
}
```

Program 10.4: Using the function `scanf()` and a **while** loop to set the buzzer frequency multiple times.

Program 10.4 asks a user to input a frequency, sounds the buzzer at that frequency, and repeats this until the user is done entering frequencies. The line

```
int freq;
```

declares a variable `freq` of type **int** to hold the user entered frequency. The next line

```
string_t answer = "yes";      /* "yes" to continue, others to quit */
```

declares a variable `answer` of type **string.t** and initializes it with the string "yes". **string.t** is a standard data type used for strings in Ch. The variable `answer` will be used to determine whether or not to continue asking the user for frequency values. The commands in Program 10.4 that take in user input and control the buzzer are repeated using a **while** loop. A **loop** is a sequence of statements which is specified once but which may be carried out multiple times in succession. A loop can be an effective way of determining at run time how many times to repeat a sequence of statements. A **while** loop repeats this sequence until the loop condition is no longer true. The general syntax of a **while** loop is

```
while(condition) {
    /* code */
}
```

where the argument `condition` specifies the loop condition. A **loop condition** expression must be true in order to enter and then repeat the **while** loop. In the case of Program 10.4 the expression `answer == "yes"` is used as the loop condition. Each time the sequence of statements is about to execute, the value of `answer` is compared to the value specified in the loop condition. When the variable `answer` has the value "yes", the loop condition evaluates as true and the program can enter and repeat the loop. **Entering** a **while** loop refers to the first time the code sequence inside the loop is executed. If the loop condition is false before the program gets to the loop, then the loop will not be entered. For instance,

## 10.3. Set the Buzzer Frequency of a Linkbot

if the variable `answer` in Program 10.4 initially had the value "no" then the program would not enter the loop at all. After entering a loop, the loop repeats until the loop condition is false. This is called **exiting** the **while** loop. In the case of Program 10.4, when the variable `answer` has any value other than "yes" the loop condition expression evaluates as false and the program will exit the loop. In general, the argument condition can have the value of `true` or 1, `false` or 0, or it can be a mathematical expression that evaluates as `true` or `false`.

Inside the **while** loop of program 10.4, the lines

```
printf("Please input the frequency for the buzzer\n");
scanf("%d", &freq);
```

prompt the user to input a frequency, and stores the input in the variable `freq`. The next lines

```
robot.setBuzzerFrequencyOn(freq);
robot.delaySeconds(1);
robot.setBuzzerFrequencyOff();
```

sound the buzzer at the frequency specified by the user input for one second, then the lines

```
printf("Would you like to enter another frequency? Type yes or no.\n");
scanf("%s", &answer);
```

asks the user if they want to enter another frequency. The user's answer is stored in the variable `answer`. As long as the user enters `yes`, then the loop condition `answer == "yes"` is true and the loop will repeat. Once the user enters `no` then the loop condition will be false and the loop will not repeat. The program will then finish executing. When program 10.4 is run, the buzzer can be set at a new frequency as many times as the user wants. The program also finishes when the user decides to quit.

 Do Exercise 2, on page 155.

### 10.3.3 Change the Buzzer Frequency a Predetermined Number of Times

In Section 10.3.2 we learned that **while** loops are valuable for deciding how many times to repeat a sequence of statements at runtime. In this section we will learn that **while** loops are also useful for repeating a sequence of statements for the number of times determined ahead of time by the programmer. Program 10.5 demonstrates how to use a **while** loop to increase the buzzer frequency a predetermined number of times.

```
/* File: buzzer3.ch
   Make buzzes with the frequencies from 1 to 10000 */
#include <linkbot.h>
CLinkbotI robot;
int freq = 1;

robot.connect();
while (freq<10000) {
    printf("frequency is %d\n", freq);
    robot.setBuzzerFrequencyOn(freq);
    robot.delaySeconds(0.05);
    robot.setBuzzerFrequencyOff();
    freq = freq + 1;
}
```

Program 10.5: Gradually increasing the buzzer frequency using a **while** loop.

Program 10.5 increases the buzzer frequency of a Linkbot-I by 1 Hz every 50 milliseconds until the frequency of the buzzer reaches 9,999 Hz. The line

### 10.3. Set the Buzzer Frequency of a Linkbot

```
int freq = 1;
```

declares a variable of **int** type and assigns it a value of 1. This is the starting frequency of the Linkbot's buzzer. The statement

```
while (freq<10000)
```

establishes a **while** loop with `freq<10000` as the loop condition. This loop condition will be true as long as the variable `freq` has a value less than 10,000 Hz. The loop will repeat until the variable `freq` is equal to or greater than 10,000 Hz, which will make the loop condition false. Inside the **while** loop, the line

```
printf("frequency is %d\n", freq);
```

prints the current frequency of the buzzer to the console. The following lines

```
robot.setBuzzerFrequencyOn(freq);
robot.delaySeconds(0.05);
robot.setBuzzerFrequencyOff();
```

sets the buzzer to the current frequency value, sounds the buzzer for 0.05 seconds, and then turns it off. The final line

```
freq = freq + 1;
```

increases the value of the buzzer frequency by 1 Hz. Overall, the **while** loop in this program will repeat 9,999 times, each time buzzing at the current frequency for 50 milliseconds and then increasing the frequency by 1 Hz. Even though the buzzer is turned off during each repetition, a very small amount of time passes before the buzzer turns on again. The time elapsed can be measured in microseconds. Because this amount of time is so small, the human ear does not detect it. This makes the buzzer sound like it is on the entire time that the frequency is increasing.

 Do Exercise 3, on page 155.

#### 10.3.4 Summary

1. Call the **CLinkbotI** member function

```
robot.setBuzzerFrequencyOn(freq);
```

to turn on the buzzer of a Linkbot at a specified frequency.

2. Call the **CLinkbotI** member function

```
robot.setBuzzerFrequencyOff();
```

to turn off the buzzer of a Linkbot.

3. Use a **while** loop to repeat a sequence of statements multiple times in succession while the loop condition is true.

#### 10.3.5 Terminology

`robot.setBuzzerFrequencyOn()`, `robot.setBuzzerFrequencyOff()`, loop, **while** loop, loop condition, entering a loop, exiting a loop.

## 10.4. Get the Accelerometer Data

**10.3.6 Exercises**

1. Write a program `buzzer4.ch`, which will be based off of program `color2.ch` from Exercise 1 on page 147. Make the following change to the code: after changing the LED color to yellow, make the Linkbot buzz at a frequency of 350 Hz for one second. Then move the Linkbot-I backward 360 degrees.
2. Write a program `buzzer5.ch` using a **while** loop that repeats the following sequence of commands. Prompt the user to enter a frequency value. Set the buzzer to that user specified value for 1 second, then set the buzzer to half of that user specified frequency value for another second. Then ask the user if they want to enter another value.
3. Write a program `buzzer6.ch` that plays all the odd-valued frequencies from 1 Hz to 4999 Hz on the buzzer of a Linkbot-I. Use a **while** loop to accomplish this.

## 10.4 Get the Accelerometer Data

In this section we will learn how to read the accelerometer data of a Linkbot-I. An **accelerometer** is a type of sensor that measures the acceleration, or g-force, experienced by an object such as a robot. Accelerometers have many important applications in robotics. Because an accelerometer can sense g-forces in real time, it is useful in analyzing the way a robot moves. For example, an accelerometer can be used in a guidance system to help a robot determine the ideal path to perform a task. Accelerometers are commonly used to help robots to navigate different types of terrain and aid robots in collision detection. Consequently, it is a useful skill to be able to program a robot to receive, process, and respond to accelerometer data in real time.

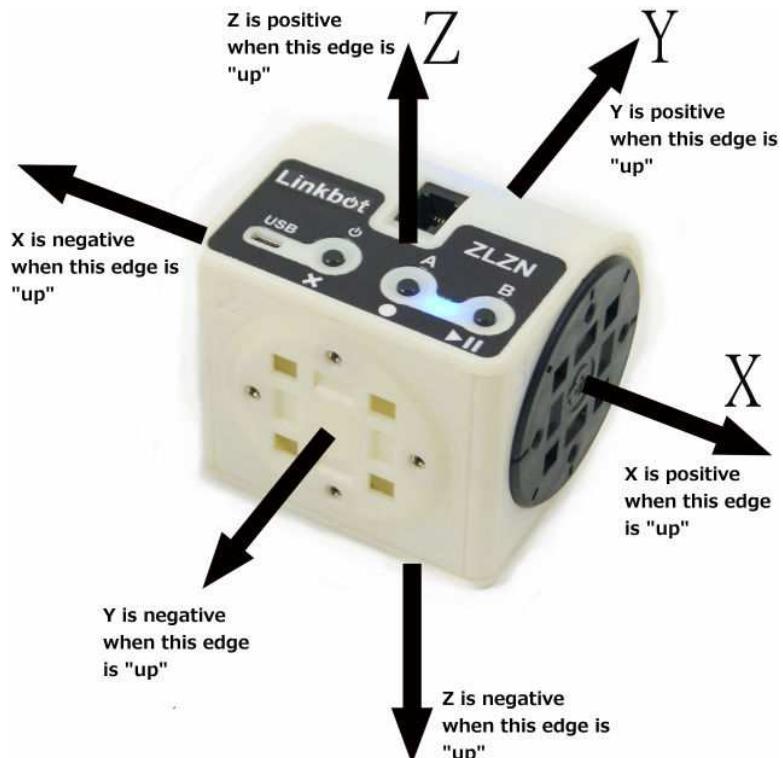


Figure 10.2: The X, Y, and Z directions of the accelerometer.

## 10.4. Get the Accelerometer Data

The Linkbot accelerometer measures the magnitude and direction of g-forces along the X, Y, and Z axes. Figure 10.2 shows the positive and negative directions of the X, Y, and Z axes as detected by the accelerometer of a Linkbot-I. These axes are the same for a Linkbot-L. This accelerometer can detect all the free falls, bumps, and tilt angles of a Linkbot. The accelerometer helps to connect two Linkbots through BumpConnect, by detecting the collision of the Linkbots. The accelerometer can also be used to control a Linkbot using the accelerometer readings of another Linkbot.

The values of the X, Y, and Z components and magnitude of the accelerometer for a Linkbot can be viewed via the Sensors Panel as shown in Figure 2.11 on page 18. Program 10.6 shows how to program a Linkbot-I to retrieve the X, Y, and Z components of the data from its accelerometer. While running Program 10.6, be sure to hold the Linkbot and move or tilt it in different directions.

```
/* File: getaccelerometer.ch
   get the accelerometer data */
#include <linkbot.h>

CLinkbotI robot;
double x, y, z;

/* Connect to the robot */
robot.connect();

while(1) {
    robot.getAccelerometerData(x, y, z);
    printf("Accelerometer: x: %lf y: %lf z: %lf\n", x, y, z);
    robot.delaySeconds(1);
}
```

Program 10.6: Getting the accelerometer data of a Linkbot-I using the function **getAccelerometerData()**.

The line

```
double x, y, z;
```

declares three variables of type **double**, x, y, and z, to hold the values of the X, Y, and Z components of the accelerometer data. After connecting to the Linkbot, the statement

```
while(1)
```

starts a **while** loop with a loop condition of 1. This condition will always be true, so the loop will repeat until the Linkbot is turned off or the user presses the **Stop** button on the debug bar in ChIDE. Inside the **while** loop, the line

```
robot.getAccelerometerData(x, y, z);
```

retrieves the current X, Y, and Z components of the accelerometer data using the **CLinkbotI** member function **getAccelerometerData()**. After this member function is called, the arguments x, y, and z will hold the values of the X, Y, and Z components of acceleration. The next two lines

```
printf("Accelerometer: x: %lf y: %lf z: %lf\n", x, y, z);
robot.delaySeconds(1);
```

print the X, Y, and Z values of acceleration to the console, and delay the program for one second before repeating the **while** loop. The sequence of statements inside the loop will repeatedly get accelerometer data from the Linkbot-I and print this data to the console as long as Program 10.6 continues running.

An application of the accelerometer data will be illustrated by a robot relay race in section 11.8.1 on page 191.

 Do Exercises 1, and 2 on page 157.

## 10.5. Get the Battery Voltage

**10.4.1 Summary**

1. Call the **CLinkbotI** member function

```
robot.getAccelerometerData(x, y, z);
```

to get the X, Y, and Z component values from the accelerometer of a Linkbot-I.

**10.4.2 Terminology**

**robot.getAccelerometerData()**, accelerometer.

**10.4.3 Exercises**

1. Connect a Linkbot-I to BaroboLink. Click on the “Sensors” tab and look at sliders under ”Accelerometer Data”. Move the Linkbot into a position where X equals 1, while Y and Z are both approximately zero. Then, move the Linkbot into a position where Y equals 1 while X and Z are both approximately zero. Finally, move the Linkbot into a position where Z equals 1 while X and Y are both approximately zero.
2. Run Program 10.6 and move the Linkbot-I into the positions described in Exercise 1.

## 10.5 Get the Battery Voltage

In this section, we will learn how to read the battery voltage of a Linkbot-I. It is useful to have the ability to monitor how much battery life is left on a Linkbot before it needs to be recharged. Program 10.7 shows how to check the remaining battery voltage of a Linkbot-I.

```
/* File: getbattery.ch
   get the battery voltage */
#include <linkbot.h>

CLinkbotI robot;
double v;

/* Connect to the robot */
robot.connect();

robot.getBatteryVoltage(v);
printf("Battery voltage is %lf\n", v);
```

Program 10.7: Getting the battery voltage of a Linkbot-I using the function **getBatteryVoltage()**.

Program 10.7 retrieves the battery voltage of a Linkbot-I. The line

```
double v;
```

declares a variable v of type **double**. This variable will be used to hold the voltage value. After the program connects to a Linkbot, the line

```
robot.getBatteryVoltage(v);
```

## 10.5. Get the Battery Voltage

gets the voltage of the battery using the **CLinkbotI** member function **getBatteryVoltage()**. After this function is called, the argument *v* will have the voltage value of the Linkbot's battery. This value is then printed to the console by the statement below.

```
printf("Battery voltage is %lf\n", v);
```

The maximum voltage of a Linkbot's lithium-ion battery pack is 4.2 volts. The battery dies when it reaches a voltage of about 3.3 volts, and the Linkbot needs to be recharged. Figure 10.3 shows how a fully charged battery of a Linkbot discharges over time. This graph was obtained by running Program 10.8. Some of the programming techniques used in Program 10.8 are beyond the scope of this book. Just keep in mind that Program 10.8 measures the battery voltage of a Linkbot-I every 5 minutes until the battery dies. The data is stored in a separate file, which is used to generate the graph after all measurements are taken. Between measurements, joints 1 and 3 of the Linkbot were rotated forward at the maximum speed of 240 degrees per second. This rotation of joints 1 and 3 simulates a constant workload, in order to give a better idea of how the battery will discharge under heavy use.

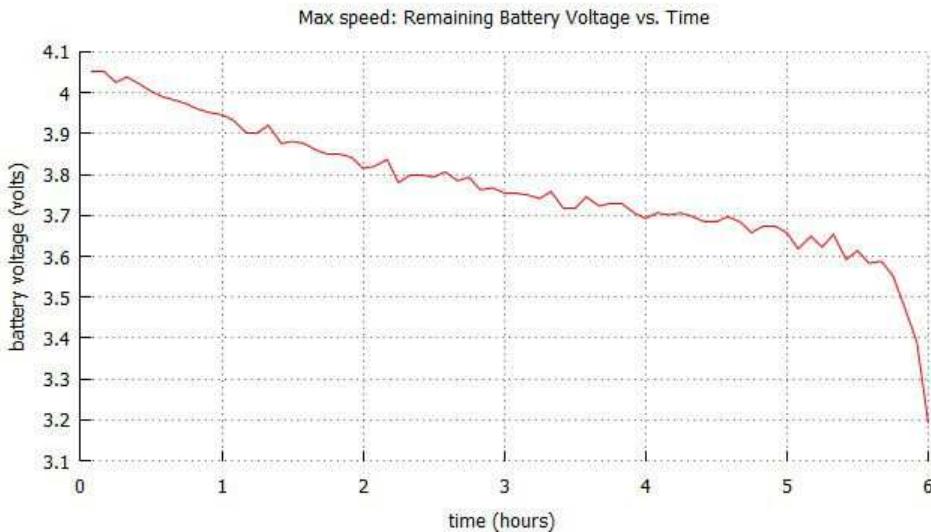


Figure 10.3: The discharge profile of a Linkbot-I battery over time.

Under this workload, the Linkbot-I battery lasts about 6 hours. Notice that the discharging pattern is not linear. The battery discharges slowly over a period of about 5.7 hours, then the voltage drops off quickly in the remaining half hour.

## 10.5. Get the Battery Voltage

```

/* File: batterytest.ch
   Get the battery voltage every 5 minutes and store it in a file until the battery
   dies. Then plot voltage vs. time from the file. */
#include <linkbot.h>
#include <chplot.h>
#include <stdio.h>

CLinkbotI robot;
CPlot plot;
double time = 300; // 5 minutes == 5 * 60 seconds == 300 seconds.
double hour = 3600.0; //1 hour == 1 * 60 minutes * 60 seconds == 3600 seconds.
double totalTime = 0; // a variable to keep track of the total time in seconds.
double voltage = 4.2; // a starting value for v, so that the program enters the
                     //while loop.
double speed=240; // max joint speed(deg/s).
string_t filename = "voltage.txt"; //The file used to store the data.
FILE * stream; // this will be the file stream.

robot.connect();
robot.resetToZero();

//Set joints to maximum speed
robot.setJointSpeeds(speed,NaN,speed);

stream = fopen("voltage.txt", "w"); //Open the file stream
if(stream == NULL) // If file stream does not open successfully,
{                  // then exit the program.
    printf("Error: cannot open 'voltage.txt'\n");
    exit(-1);
}

// repeat the following until v < 3.3, when battery should die.
while (voltage >= 3.3){

    // moveTime() for 5 minutes
    robot.moveTime(time);

    // add 5 minutes to total time
    totalTime = totalTime + (time/hour);

    // get the battery voltage
    robot.getBatteryVoltage(voltage);

    // store time and voltage values in a file
    fprintf(stream, "%lf %lf\n", totalTime, voltage);

}
fclose(stream);

plot.mathCoord();
plot.title("Max speed: Remaining Battery Voltage vs. Time");
plot.label(PLOT_AXIS_X, "time (hours)");
plot.label(PLOT_AXIS_Y, "battery voltage (volts)");
plot.dataFile("voltage.txt");
plot.plotting();

```

Program 10.8: Plotting the discharge of a Linkbot battery over time.

## 10.5. Get the Battery Voltage

Do Exercise 1, and 2 on page 160.

### 10.5.1 Summary

1. Call the **CLinkbotI** member function

```
robot.getBatteryVoltage(v);
```

to get the battery voltage of a Linkbot-I.

### 10.5.2 Terminology

**robot.getBatteryVoltage()**.

### 10.5.3 Exercises

1. Write a program `getbattery2.ch` to get the battery voltage of a Linkbot-I, and then calculate the percent of the battery voltage remaining. Print both the voltage and the voltage percent to the console.
2. Write a program `getbattery3.ch` using a **while** loop to get the battery voltage of a Linkbot-I every 5 minutes until the battery is fully discharged. Each time you get the voltage, print it to the console, along with the amount of time in seconds that has passed since the program started. In between voltage measurements, move joints 1 and 3 of the Linkbot-I for 5 minutes.

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## CHAPTER 11

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# Writing Programs to Control Multiple Individual Linkbots

## 11.1 Control Multiple Linkbots Using the Motion Control Panel

A computer can connect to multiple Linkbots as described in section 2.2 in Chapter 2. The Motion Control Panel can be used to control multiple Linkbots, one at a time. If a computer is connected to multiple Linkbots, an individual Linkbot can be selected to be controlled by picking the ZigBee serial number of the Linkbot from the drop down menu labeled as “Select a robot to control” underneath the tabs as shown in Figure 2.12 on page 20.

 Do Exercise 1 on page 161.

### 11.1.1 Summary

1. Connect to multiple Linkbots from a computer through the BaroboLink and control one Linkbot at a time through the Motion Control Panel.

### 11.1.2 Terminology

Motion Control Panel.

### 11.1.3 Exercises

1. Work with your partner to connect a computer to two Linkbots. Control the connected two Linkbots using a Linkbot Control Panel or BaroboLink on the computer.

## 11.2. Control Multiple Linkbots Using a Program

## 11.2 Control Multiple Linkbots Using a Program

In Chapter 6 we learned how to control multiple Linkbots in a group with identical movements simultaneously. In this chapter we will learn how to control multiple Linkbots in the same program, but they will have different movements at different times. Although it is efficient to control multiple robots using a single group, there will be times when it is preferable for robots to move independently within the same program.

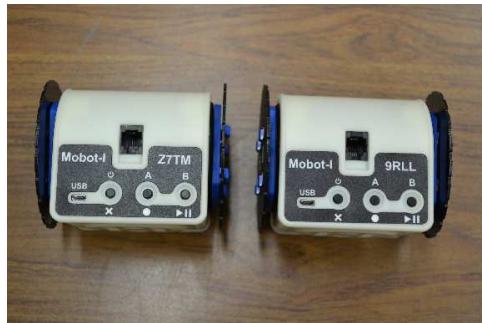


Figure 11.1: Control two modules of Linkbot-I.

```
/* File: twomodules.ch
   Control two robots sequentially. */
#include <linkbot.h>
CLinkbotI robot1, robot2;

/* connect to robots. */
robot1.connect();
robot2.connect();

/* move to the zero position for robot1 and robot2 sequentially. */
robot1.resetToZero();
robot2.resetToZero();

/* move joints 1 and 3 for robot1 */
robot1.move(360, NaN, -360);

/* move joints 1 and 3 for robot2 */
robot2.move(360, NaN, -360);
```

Program 11.1: Controlling two modules of Linkbot-I in a program.

Recall that Program 3.2 on page 35 moves a single Linkbot-I forward by 360 degrees. Program 11.1 moves two Linkbots forward by 360 degrees, in the same manner as Program 3.2. But each Linkbot-I moves at a different time. The line

```
CLinkbotI robot1, robot2;
```

declares a separate variable for each Linkbot. Then the lines

```
robot1.connect();
robot2.connect();
```

### 11.3. Blocking versus Non-Blocking Functions

connects the two variables to Linkbots sequentially. This means `robot2` does not start to connect until `robot1` has finished connecting. The subsequent commands to reset the joints of each Linkbot to zero also execute sequentially. The first of the next two lines

```
robot1.move(360, NaN, -360);
robot2.move(360, NaN, -360);
```

moves `robot1` forward 360 degrees first. Only when `robot1` has finished moving does `robot2` start moving forward 360 degrees.

You can run the program `twomodules.ch` in Program 11.1 to control two Linkbot-Is and monitor their joint angles on the Motion Control Panel, showing one Linkbot-I at a time.

 Do Exercise 1 on page 163.

#### 11.2.1 Exercises

1. Write a program `twomodules2.ch` to control two Linkbot-Is. The program will move joints 1 and 3 of the first Linkbot-I to 90 degrees. Then, it will move the joints of the second Linkbot-I the same amount as the first one.

#### 11.2.2 Summary

1. The commands

```
robot1.move(360, NaN, -360);
robot2.move(360, NaN, -360);
```

move `robot1` forward 360 degrees first. When `robot1` has finished moving, then `robot2` starts moving.

#### 11.2.3 Terminology

independent movements, sequential commands.

## 11.3 Blocking versus Non-Blocking Functions

All of the functions that have been introduced so far have been blocking functions. A **blocking function** is a function that must complete its execution before the next line of code can start executing. The previous program demonstrated how blocking functions work. The use of blocking functions is fine if the programmer intends for independent motions to execute sequentially. But a programmer may want to command Linkbots in independent motions simultaneously. In this section we will learn how to achieve this effect using non-blocking functions.

Run the programs in these sections in ChIDE in debug mode using the command `Next`.

## 11.3. Blocking versus Non-Blocking Functions

```
/* File: block.ch
   Use the blocking function moveJoint(). */
#include <clinkbot.h>
CLinkbotI robot;

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* rotate joint 1 by 360 degrees first, then joint 2 by 30 degrees */
robot.moveJoint(JOINT1, 360);
robot.moveJoint(JOINT3, 30);
```

Program 11.2: A program using all blocking functions.

Program 11.3 demonstrates the use of blocking functions on the same Linkbot. The line

```
robot.moveJoint(JOINT1, 360);
```

rotates joint 1 of the Linkbot-I by 360 degrees first. Only after joint 1 has completed its rotation does the line

```
robot.moveJoint(JOINT3, 30);
```

rotate joint 3 by 30 degrees. The execution of these two functions is sequential.

```
/* File: nonblocka.ch
   Use the non-blocking function moveJointNB(). */
#include <clinkbot.h>
CLinkbotI robot;

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* rotate joint 1 by 360 degrees and joint 3 by 180 degrees at the same time
   till the movement for joint 3 is finished. */
robot.moveJointNB(JOINT1, 360);
robot.moveJoint(JOINT3, 180);
```

Program 11.3: Using the non-blocking function **moveJointNB()**.

Program 11.3 demonstrates non-blocking functions. A **non-blocking function** does not prevent the execution of the next line of code. In other words, the next line of code can begin execution before the non-blocking function has finished its execution. This way both lines of code can execute simultaneously, as long as their actions do not overlap. The non-blocking function introduced in Program 11.3 is the **CLinkbotI** member function **moveJointNB()**. The general syntax of this function is

```
robot.moveJointNB(id, angle);
```

The argument **id** specifies the joint to move. The argument **angle** is the final position of the joint angle relative to its current position. The function **moveJointNB()** moves a Linkbot-I in the same way as the function **moveJoint()** does. But when **moveJointNB()** is used, the next line of code starts its execution before **moveJointNB()** has finished executing. A non-blocking version of a member function for motion has the suffix **NB**. In Program 11.3 the line

### 11.3. Blocking versus Non-Blocking Functions

```
robot.moveJointNB(JOINT1, 360);
```

starts rotating joint 1 by 360 degrees relative to its current position. Immediately the next line

```
robot.moveJoint(JOINT3, 180);
```

begins rotating joint 3 by 180 degrees relative to its current position. As a result, joints 1 and 3 will rotate simultaneously until joint 3 has finished rotating.

In Program 11.3, Joint 1 will not be able to complete the full rotation of 360 degrees before the program finishes its execution.

Since the code will continue to run after calling a non-blocking function, it is sometimes desirable to wait until certain Linkbot motions have finished. For example, a program may command joint 1 to rotate 360 degrees. If that rotation has not yet completed, and the next line of code commands the same joint in a different motion, then that next line would need to be delayed. Program 11.4 demonstrates how to do this.

```
/* File: nonblockb.ch
Use the function moveJointWait() to wait for the completion of
a joint movement. */
#include <linkbot.h>
CLinkbotI robot;

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* rotate joint 1 for 360 degrees and joint 3 for 720 degrees at the same time.
   till the movement for joint 1 is finished, then move joint 1 by 30 degrees */
robot.moveJointNB(JOINT1, 360);
robot.moveJointNB(JOINT3, 720);
robot.moveJointWait(JOINT1);
robot.moveJoint(JOINT1, 30);
robot.moveJointWait(JOINT3);
```

Program 11.4: Using the function **moveJointWait()** to wait for the completion of a joint movement from **moveJoint()**.

Program 11.4 makes use of the **CLinkbotI** member function **moveJointWait()**. This function pauses the program until the specified joint has finished its motion. The syntax of the function **moveJointWait()** is

```
robot.moveJointWait(id);
```

The argument **id** specifies the joint for which you want to pause the program until its current motion is completed. This command only applies to the joint number for the specific Linkbot-I it is used on. In Program 11.4 the lines

```
robot.moveJointNB(JOINT1, 360);
robot.moveJointNB(JOINT3, 720);
```

command the Linkbot-I to move joint 1 by 360 degrees and joint 3 by 720 degrees simultaneously. The next line

```
robot.moveJointWait(JOINT1);
```

commands the program to pause until joint 1 has finished moving 360 degrees relative to its starting position. The next line of the program will not begin execution until joint 1 has finished moving. Note, however, that joint 3 will still be in the process of rotating 720 degrees when the program resumes execution. The next line

## 11.3. Blocking versus Non-Blocking Functions

```
robot.moveJoint(JOINT1, 30);
```

will rotate joint 1 by 30 degrees at the same time that joint 3 continues its 720 degree rotation. After joint 1 finishes its 30 degree rotation, the final line

```
robot.moveJointWait(JOINT3);
```

pauses the program until joint 3 has finished rotating 720 degrees. This last line of the code ensures that joint 3 will be able to complete its full 720 degree rotation before the program finishes execution.

 Do Exercises 1 and 2 on page 167.

There are times when it may be desirable to wait for all joints of a specific Linkbot to finish moving. Program 11.5 shows how this can be accomplished.

```
/* File: nonblockc.ch
   Use the function moveWait(). */
#include <linkbot.h>
CLinkbotI robot;

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* rotate joint 1 for 360 degrees and joint 3 for 720 degrees at the same time.
   till the movement for all joints is finished, then move joint 1 by 30 degrees */
robot.moveJointNB(JOINT1, 360);
robot.moveJointNB(JOINT3, 720);
robot.moveWait();
robot.moveJoint(JOINT1, 30);
```

Program 11.5: Using the function **moveWait()** to wait for the completion of all joint movement.

The **CLinkbotI** member function that will pause the program until certain motions are complete is **moveWait()**. The syntax of this function is

```
robot.moveWait();
```

The function **moveWait()** has no argument. It pauses the program until all joints of a specific Linkbot-I have finished rotating. As in the previous program, the statements

```
robot.moveJointNB(JOINT1, 360);
robot.moveJointNB(JOINT3, 720);
```

rotate joint 1 by 360 degrees and joint 3 by 720 degrees simultaneously. The next statement

```
robot.moveWait();
```

pauses the program until both joint 1 and joint 3 have finished rotating. The last statement

```
robot.moveJoint(JOINT1, 30);
```

rotates joint 1 by 30 degrees. Since this last statement uses a blocking function, joint 1 is able to complete its 30 degree rotation before the program finishes execution.

 Do Exercise 3 on page 167.

## 11.3. Blocking versus Non-Blocking Functions

**11.3.1 Summary**

1. Call the non-blocking **CLinkbotI** member function

```
robot.moveJointNB(id, angle);
```

to move a joint with the specified angle relative to its current position. The next line of code will begin execution before the joint has finished its rotation.

2. Call the non-blocking **CLinkbotI** member function

```
robot.moveJointWait(id);
```

to pause the program until a specific joint of a specific Linkbot has finished rotating.

3. Call the non-blocking **CLinkbotI** member function

```
robot.moveWait();
```

to pause a program until all joints of a specific Linkbot have finished rotating.

**11.3.2 Terminology**

**robot.moveJointNB()**, **robot.moveJointWait()**, **robot.moveWait()**, blocking function, non-blocking function.

**11.3.3 Exercises**

1. In Program 11.3, the motion for the rotation of 360 degrees for joint 1 will not be able to complete before the program exits. Modify Program 11.3 as a new program **nonblocka2.ch** by adding the following function call at the end of the program.

```
robot.moveJointWait(JOINT1);
```

Run programs **nonblocka.ch** and **nonblocka2.ch** while monitoring the joint angle for joint 1 on the Motion Control Panel in BaroboLink to see the different motions.

2. Write a program **nonblockb2.ch** to move joint 1 of a Linkbot-I to 360 degrees and joint 3 to 180 degrees at the same time using the member function **moveJointNB()**. Once both joints 1 and 3 finish the motion, move joint 3 to 45 degrees.
3. Write a program **nonblockc2.ch** to move joint 1 of a Linkbot-I by 360 degrees and joint 3 by 180 degrees at the same time using the member function **moveJointNB()**. Once joint 3 finishes the motion, move joint 3 by another 45 degrees. Make sure all motions complete before the program ends (Hints: need **moveWait()** at the end of the program).

## 11.4. Synchronize the Motion of Multiple Linkbots

In the previous section we learned how to rotate joints 1 and 3 on a single Linkbot in different ways simultaneously. It is also possible to command multiple Linkbots in independent motions simultaneously using non-blocking functions. The motions of two Linkbot-Is are considered to be synchronized if they are distinct but simultaneous.

```
/* File: movenb.ch
   Control two robots with motions simultaneously using non-blocking functions. */
#include <linkbot.h>
CLinkbotI robot1, robot2;

/* connect to robots. */
robot1.connect();
robot2.connect();

/* move to the zero position at the same time. */
robot1.resetToZeroNB();
robot2.resetToZeroNB();

/* wait for both robot to finish their movements through resetToZeroNB() */
robot1.moveWait();
robot2.moveWait();

/* move joints 1 and 3 for both robots at the same time using moveNB() */
robot1.moveNB(180, NaN, -180);
robot2.moveNB(360, NaN, -360);
/* wait for both robots to finish their movements through moveNB() */
robot1.moveWait();
robot2.moveWait();

/* move joints 1 and 3 for both robots at the same time using moveNB() */
robot1.moveNB(-360, NaN, 360);
robot2.moveNB(-360, NaN, 360);
/* wait for both robots to finish their movements through moveNB() */
robot1.moveWait();
robot2.moveWait();

/* hold the position after the program exits */
robot1.holdJointsAtExit();
robot2.holdJointsAtExit();
```

Program 11.6: Synchronize the motion of multiple Linkbots using non-blocking functions **resetToZeroNB()** and **moveNB()**, and **moveWait()**.

In Program 11.6 multiple Linkbots are moved simultaneously using the non-blocking **CLinkbotI** member functions **resetToZeroNB()** and **moveNB()**. The general syntax of the function **resetToZeroNB()** is

```
robot.resetToZeroNB();
```

The function **resetToZeroNB()** has no argument. This function allows multiple Linkbots to reset their joints to the zero position at the same time instead of one at a time. The lines

```
robot1.resetToZeroNB();
robot2.resetToZeroNB();
```

## 11.4. Synchronize the Motion of Multiple Linkbots

reset `robot1` and `robot2` to the zero position simultaneously. The next two lines

```
robot1.moveWait();  
robot2.moveWait();
```

pauses the program until both `robot1` and `robot2` have finished resetting to the zero position. The next lines

```
robot1.moveNB(180, NaN, -180);  
robot2.moveNB(360, NaN, -360);
```

moves `robot1` forward by 180 degrees and `robot2` forward by 360 degrees at the same time using `moveNB()`. The syntax of this function is

```
robot.moveNB(angle1, NaN, angle3);
```

The function `moveNB()` moves a Linkbot in the same way that `move()` does, except that it is non-blocking. This allows two Linkbot-Is to move both joints 1 and 3 relative to their current positions simultaneously. The arguments `angle1` and `angle3` correspond to joint 1 and 3 and specify the joint angle to move both joints relative to their current positions. Since joint 2 of a Linkbot-I cannot be moved, the second argument has the value `Nan`.

The next two lines call `moveWait()` on `robot1` and `robot2` to allow both to finish their motions before continuing. After that, the lines

```
robot1.moveNB(-360, NaN, 360);  
robot2.moveNB(-360, NaN, 360);
```

move both `robot1` and `robot2` backward by 360 degrees simultaneously. Then `moveWait()` is called on both Linkbots to allow them to finish moving backward. The final lines

```
robot1.holdJointsAtExit();  
robot2.holdJointsAtExit();
```

command `robot1` and `robot2` to hold their poses when the program exits.

 Do Exercises 1 and 2 on page 172.

So far we used non-blocking functions to move joints 1 and 3 of multiple Linkbots relative to their current positions. We can also use non-blocking functions to move the joints of multiple Linkbots to their absolute positions.

### Problem Statement:

Write a program `movetonb.ch` to start the motions of two Linkbot-Is at the same time. It rotates joint 1 to 180 degrees and joint 3 to -180 degrees for the first Linkbot-I, joint 1 to 360 degrees and joint 3 to -360 degrees for the second Linkbot-I. Then, it moves joint 1 of both Linkbot-Is by 90 degrees. Next it moves joint 1 of both Linkbot-Is to 720 degrees.

## 11.4. Synchronize the Motion of Multiple Linkbots

```

/* File: movetonb.ch
   Control two robots with motions simultaneously using non-blocking functions. */
#include <linkbot.h>
CLinkbotI robot1, robot2;

/* connect to robots. */
robot1.connect();
robot2.connect();

/* move to the zero position at the same time. */
robot1.resetToZeroNB();
robot2.resetToZeroNB();

/* wait for both robot to finish their movements through resetToZeroNB() */
robot1.moveWait();
robot2.moveWait();

/* move joints 1 and 3 for both robots at the same time using moveNB() */
robot1.moveToNB(180, NaN, -180);
robot2.moveToNB(360, NaN, -360);
/* wait for both robots to finish their movements through moveNB() */
robot1.moveWait();
robot2.moveWait();

/* move joint 1 for both robots at the same time using moveJointNB() */
robot1.moveJointNB(JOINT1, 90);
robot2.moveJointNB(JOINT1, 90);
/* wait for both robots to finish their movements through moveJointNB() */
robot1.moveJointWait(JOINT1);
robot2.moveJointWait(JOINT1);

/* move joint 1 for both robots at the same time using moveJointToNB() */
robot1.moveJointToNB(JOINT1, 720);
robot2.moveJointToNB(JOINT1, 720);
/* wait for both robots to finish their movements through moveJointNB() */
robot1.moveJointWait(JOINT1);
robot2.moveJointWait(JOINT1);

```

Program 11.7: Synchronize the motion of multiple Linkbots using non-blocking functions **moveToNB()**, **moveJointToNB()**, and **moveJointNB()**.

Program 11.7 moves joints 1 and 3 of multiple Linkbot-Is to different absolute positions simultaneously. This is accomplished using the non-blocking **CLinkbotI** member functions **moveToNB()** and **moveJointToNB()**. The general syntax of the function **moveToNB()** is

```
robot.moveToNB(angle1, NaN, angle3);
```

This function uses arguments `angle1` and `angle3` to store the joint angle values for joints 1 and 3, respectively. The function **moveToNB()** moves joints 1 and 3 of a Linkbot-I to their absolute positions. It is the non-blocking counterpart of the function **moveTo()** that was introduced in Section 7.2. In Program 11.7, the lines

```

robot1.moveToNB(180, NaN, -180);
robot2.moveToNB(360, NaN, -360);

```

moves `robot1` forward to an absolute position of 180 degrees and moves `robot2` forward to an absolute joint position of 360 degrees. Both Linkbot-Is perform these motions simultaneously. The next two lines

## 11.4. Synchronize the Motion of Multiple Linkbots

call **moveWait()** to pause the program until `robot1` and `robot2` finish their motions. The next lines

```
robot1.moveJointNB(JOINT1, 90);
robot2.moveJointNB(JOINT1, 90);
```

move joint 1 of `robot1` and `robot2` simultaneously 90 degrees relative to their current positions. The next two lines use **moveJointWait()** on both Linkbots to pause the program until both have finished their motions.

The next lines

```
robot1.moveJointToNB(JOINT1, 720);
robot2.moveJointToNB(JOINT1, 720);
```

move joint 1 of both `robot1` and `robot2` simultaneously to the absolute position of 720 degrees using the function **moveJointToNB()**. The syntax of this function is

```
robot.moveJointToNB(id, angle);
```

The argument `id` specifies the joint angle to move. The argument `angle` specifies the absolute position to move the joint. The function **moveJointToNB()** is the non-blocking counterpart of the function **moveJointTo()**, which was introduced in section 7.4. It rotates a single joint of a Linkbot to its absolute position and allows the next line of code to execute before the joint finishes its rotation.

Finally, **moveJointWait()** is used on both Linkbots to pause the program until both have finished their 720 degree rotations.

 Do Exercise 3 on page 172.

### 11.4.1 Summary

1. Call the non-blocking **CLinkbotI** member function

```
robot.resetToZeroNB();
```

on multiple Linkbot-Is to simultaneously reset their joints to the zero position.

2. Call the non-blocking **CLinkbotI** member function

```
robot.moveNB(angle1, NaN, angle3);
```

on multiple Linkbot-Is to simultaneously move them by different degrees relative to their current joint angle positions.

3. Call the non-blocking **CLinkbotI** member function

```
robot.moveToNB(angle1, NaN, angle3);
```

on multiple Linkbot-Is to simultaneously move them to by different degrees to their absolute joint angle positions.

4. Call the non-blocking **CLinkbotI** member function

```
robot.moveJointToNB(id, angle);
```

on multiple Linkbots to simultaneously move single joints by different degrees to their absolute joint angle positions.

## 11.5. Move Multiple Linkbots with Specified Distances or Joint Angles

**11.4.2 Terminology**

**robot.resetToZeroNB()**, **robot.moveNB()**, **robot.moveToNB()**, **robot.moveJointToNB()**.

**11.4.3 Exercises**

1. Modify the program `movenb.ch` in Program 11.6 as a new program `nomovewait.ch` by removing the last two `moveWait()` statements. How will the motion change?
2. Write a program `movenb2.ch` using member functions `moveJoint()` and `moveJointNB()` to move joints 1 and 3 by 360 degrees at the same time.
3. Write a program `movetonb2.ch` with the synchronized motions for both Linkbot-Is. It first rotates joints 1 and 3 to 360 degrees. Then, rotate joint 1 by 90 degrees. Finally, rotate joint 3 to 720 degrees.

## 11.5 Move Multiple Linkbots with Specified Distances or Joint Angles

In section 9.1, we learned how to drive a Linkbot-I with the specified speed and distance using the member function `driveDistance()`. In some applications, we need to drive multiple Linkbots at the same time. A non-blocking member function `driveDistanceNB()` can be used to drive multiple Linkbot-Is synchronously.

Special consideration may need to be given to when it is more appropriate to use a blocking or a non-blocking function to drive a particular Linkbot. In addition, the programmer must pay attention to whether some of the final functions are time based. If this is the case, then either the last function must be blocking or a waiting function such as `moveWait()` must be added to wait for the completion of the motion for a non-blocking function. How to drive two Linkbots simultaneously will be illustrated by solving the following problem and corresponding Program 11.8.

**Problem Statement:**

Two Linkbot-Is are configured as two-wheel robots, as shown in Figure 11.2. The radii of the wheels are 1.75 inches. Write a program `drivedistancenb.ch` for two Linkbots racing in the following manner. Both Linkbots will drive from a starting line at different times. The first Linkbot drives for 24 inches at the speed of 1.5 inches per second. Then 8 seconds after the first Linkbot has left the starting line, the second Linkbot races for 24 inches at the speed of 3 inches per second.



Figure 11.2: Two two-wheel drive vehicles.

## 11.5. Move Multiple Linkbots with Specified Distances or Joint Angles

When two Linkbot-Is are placed on a starting line, make sure to press both buttons A and B together for each Linkbot to reset the wheels to the zero positions before running the program, as described in Section 2.1.3. Therefore, two Linkbots will drive at the same starting position.

```
/* File: drivendistancenb.ch
Drive two two-wheeled robots with different speeds continuously
with specified distances. */
#include <linkbot.h>
CLinkbotI robot1, robot2;
double radius1=1.75; // the radius of the two wheels of robot1 in inches
double radius2=1.75; // the radius of the two wheels of robot2 in inches
double speed1=1.5, speed2=3; // speed of robots in inches per second
double distance1=24, distance2=24; // the travelled distances for robot1 and robot2
double delaytime=8; // delay time in seconds for robot2

/* connect to robots and move to the zero position at the same time. */
robot1.connect();
robot2.connect();
robot1.resetToZeroNB();
robot2.resetToZeroNB();
robot1.moveWait();
robot2.moveWait();

/* set the speed for robot1 */
robot1.setSpeed(speed1, radius1);
/* set the speed for robot2 */
robot2.setSpeed(speed2, radius2);

/* robot1 drives for 'distance1'
'delaytime' seconds later, robot2 drives for 'distance2' while robot1 also drives */
robot1.driveDistanceNB(distance1, radius1);
robot2.delaySeconds(delaytime);
robot2.driveDistance(distance2, radius2);
robot1.moveWait(); // wait till robot1 drove 'distance1'
```

Program 11.8: Driving multiple Linkbots with specified distances using **driveDistanceNB()**.

Program 11.8 drives two Linkbots by specified distances simultaneously. The lines

```
double radius1=1.75; // the radius of the two wheels of robot1 in inches
double radius2=1.75; // the radius of the two wheels of robot2 in inches
```

declare two variables of **double** type and assign them both the wheel radius value of 1.75 inches. The next line

```
double speed1=1.5, speed2=3; // speed of robots in inches per second
```

declares two variables of type **double** and assigns them two different speeds in inches per second. Note that the speed of the second Linkbot-I is twice the speed of the first. Then the next two lines

```
double distance1=24, distance2=24; // the traveled distances for robot1 and robot2
double delaytime=8; // delay time in seconds for robot2
```

declare two variables **distance1** and **distance2** of type **double** and assign them with distances of 24 inches. Note that the distances for both robots are the same. Another variable **delaytime** of type **double** is also declared, and assigned a value of 8 seconds. This will be used to delay the start of **robot2** for 8 seconds after **robot1** starts moving.

## 11.5. Move Multiple Linkbots with Specified Distances or Joint Angles

The next six lines of code connect both `robot1` and `robot2` to Linkbots and reset both to the zero position. The program is paused by calling `moveWait()` for both `robot1` and `robot2` until both have finished resetting. Then the next two lines

```
robot1.setSpeed(speed1, radius1);
robot2.setSpeed(speed2, radius2);
```

sequentially sets the speeds of `robot1` and `robot2`. The following line

```
robot1.driveDistanceNB(distance1, radius1);
```

drives the `robot1` for a specific distance `distance1` with the radius of `radius1`. This is done using the **CLinkbotI** member function `driveDistanceNB()`. The syntax of the member function `driveDistanceNB()` is as follows.

```
robot.driveDistanceNB(distance, radius);
```

The line

```
robot2.delaySeconds(delaytime);
```

delays the start of `robot2` for 8 seconds after `robot1` starts moving. Since `robot1` has a total movement distance of 24 inches, however, it will only be half way through its movement when `robot2` starts to move. This makes the choice of `driveDistanceNB()` appropriate for `robot1`. The next line

```
robot2.driveDistance(distance2, radius2);
```

drives `robot2` forward for 24 inches at 3 inches per second. `robot2` is the last Linkbot in the program to begin moving, and its motion depends on a specified distance and speed. Thus the choice of a blocking function is appropriate for `robot2`. After `robot2` has completed its motion, the line

```
robot1.moveWait(); // wait till robot1 moved 'distance1'
```

is included to make sure that `robot1` has completed its motion before the program finishes execution. In this case, since both robots drive the same distance of 24 inches. This synchronization statement may not be critical. However, if the traveling `distance2` for `robot2` is less than that for `robot1`, say 16 inches, without the last statement `robot1.moveWait()`, when `robot2` finishes its motion and the program exits. By then, `robot1` would drive only 16 inches, instead of 24 inches.

The distance traveled by two Linkbot-Is is the same. Since the speed of the second Linkbot-I is twice as fast as the first one, both Linkbot-Is shall stop at the same finishing line at the same time. For the first robot, the time to drive 24 inches can be calculated as follows.

$$t = \frac{distance}{v} = \frac{24}{1.5} = 16 \text{ seconds}$$

The time for the second robot to drive 24 inches can be calculated as follows.

$$t = \frac{distance}{v} = \frac{24}{3} = 8 \text{ seconds}$$

 Do Exercises 1 and 2 and on page 175.

There are also similar non-blocking member functions

```
robot.driveForwardNB(angle);
robot.driveBackwardNB(angle);
robot.turnLeftNB(angle, radius, trackwidth);
robot.turnRightNB(angle, radius, trackwidth);
```

to roll forward, roll backward, turn left, and turn right a Linkbot-I, respectively. Programs `driveforwardnb.ch` and `turnleftnb.ch` illustrate how to use these non-blocking member functions. These two programs are distributed along with other sample programs.

 Do Exercises 3 and 4 and on page 175.

## 11.5. Move Multiple Linkbots with Specified Distances or Joint Angles

**11.5.1 Summary**

1. Call the non-blocking **CLinkbotI** member function

```
robot.driveDistanceNB(distance, radius);
```

to drive a Linkbot-I for the specified distance. The lines of code following the non-blocking member function will begin execution before the specified distance has reached.

2. Call the non-blocking **CLinkbotI** member functions **driveForwardNB()**, **driveBackward()**, **turnLeftNB()**, and **turnRightNB()** to roll forward, roll backward, turn left, and turn right a Linkbot-I, respectively. The lines of code following the non-blocking member function will begin execution before the specified angle has reached.

**11.5.2 Terminology**

**robot.driveDistanceNB()**, **robot.driveForwardNB()**, **robot.driveBackwardNB()**, **robot.turnLeftNB()**, and **robot.turnRightNB()**.

**11.5.3 Exercises**

1. Two Linkbot-Is are configured as two-wheel robots, as shown in Figure 11.2. The radii of the wheels are 1.75 inches. Write a program **drivedistancenb2.ch** for two Linkbots racing in the following manner. Both Linkbots will drive from a starting line at different times. The first Linkbot drives for 12 inches at the speed of 1.2 inches per second. Then 5 seconds after the first Linkbot has left the starting line, the second Linkbot races for 12 inches at the speed of 2.4 inches per second.
2. Two Linkbot-Is are configured as two-wheel robots. The radii of the wheels for the first Linkbot-I are 1.75 inches. The radii of the wheels for the second Linkbot-I are 2 inches. Write a program **drivedistancenb3.ch** for two Linkbot-Is racing in the following manner. Two Linkbots will drive from a starting line at the same time at the same speed of 1.5 inches per second for 20 inches.
3. Two Linkbot-Is are configured as two-wheel robots. The radii of the wheels for the first Linkbot-I are 1.75 inches. The radii of the wheels for the second Linkbot-I are 2 inches. Write a program **driveforwardnb2.ch** for two Linkbot-Is racing in the following manner. Two Linkbots will roll forward for 720 degrees from a starting line at the same time at the same joint speed of 45 degrees per second. You can set the joint speed of a Linkbot-I by the member function **setJointSpeeds()** and using the member functions **driveForwardNB()** and **driveForward()** to roll two Linkbots at the same time in RoboSim. What is the distance traveled by each Linkbot-I.
4. Two Linkbot-Is are configured as two-wheel robots. The radii of the wheels for both Linkbot-Is are 1.75 inches. The track width of the Linkbot-I is 3.69 inches. Write a program **turnleftnb2.ch** for two Linkbot-Is moving in the following manner simultaneously. The joint speeds for Linkbot-Is are set to 45 degrees per second. Two Linkbots will roll forward for 360 degrees from a starting line at the same time. Next, the first robot turns left 90 degrees and the second robot turns right 90 degrees. Then, both robots roll forward for 360 degrees. Finally, both robots drive back to the originally positions along the same paths as shown in Figure 11.3.

## 11.6. Plot Recorded Distances and Time for Multiple Linkbots

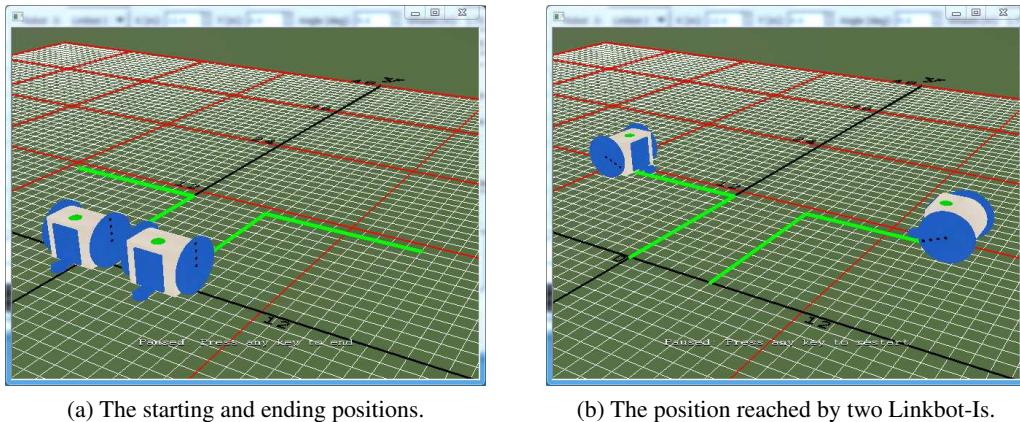


Figure 11.3: The trajectories for two Linkbot-Is.

## 11.6 Plot Recorded Distances and Time for Multiple Linkbots

In Section 9.1.6 we learned how to record and plot distance versus time for a single Linkbot-I with a specified speed and distance. In this section we will learn how to do this for two Linkbot-Is in synchronous motion with a specified speed and distance or joint angle. The ability to receive and process real time data from multiple sources is valuable for comparing the performance of multiple robots. Program 11.9 extends the concepts learned from Program 9.6, except that plotting is done for multiple Linkbot-Is and non-blocking functions are used.

### Problem Statement:

Two Linkbot-Is are configured as two-wheel robots, as shown in Figure 11.2 on page 172. The radii of the wheels are 1.75 inches. Write a program `recorddistancesdist.ch` to drive the first robot at the speed of 1.5 inches per second for 24 inches. After 8 seconds delay, the second robot drives at the speed of 3 inches per second for 24 inches. Record the distances as the robots travel with a time interval of 0.1 second. Plot the distances for both robots versus time.

## 11.6. Plot Recorded Distances and Time for Multiple Linkbots

```

/* File: recorddistancesdist.ch
Record time and distances using driveDistance(),
Delay 8 seconds for robot2. The equations of motions are
    d = 1.5t
    d = 3(t-8)
Plot the acquired data for two robots */
#include <linkbot.h>
#include <chplot.h>
CLinkbotI robot1, robot2;
double speed1=1.5, speed2=3; // speeds of robots in inches per second
double radius1=1.75, radius2=1.75; // the radii of two wheels of robot1 and 2
double distance1=24, distance2=24; // the travelled distances for robot1 and robot2
double delaytime=8; // delay time for robot2
double timeInterval = 0.1; // time interval in 0.1 second
int numDataPoints1, numDataPoints2; // number of data points recorded
robotRecordData_t timedata1, distances1; // recorded time and distances for robot1
robotRecordData_t timedata2, distances2; // recorded time and distances for robot2
CPlot plot; // plotting class

/* connect to robots and move to the zero position at the same time. */
robot1.connect(); robot2.connect();
robot1.resetToZeroNB(); robot2.resetToZeroNB();
robot1.moveWait(); robot2.moveWait();

/* set the speeds for robot1 and robot2 */
robot1.setSpeed(speed1, radius1);
robot2.setSpeed(speed2, radius2);

/* disable record data shift and begin recording time and distance */
robot1.disableRecordDataShift();
robot2.disableRecordDataShift();
robot1.recordDistanceBegin(JOINT1, timedata1, distances1, radius1, timeInterval);
robot2.recordDistanceBegin(JOINT1, timedata2, distances2, radius2, timeInterval);

/* robot1 drives for 'distance1'
'delaytime' seconds later, robot2 drives for 'distance2' while robot1 also drives */
robot1.driveDistanceNB(distance1, radius1);
robot2.delaySeconds(delaytime);
robot2.driveDistance(distance2, radius2);
robot1.moveWait(); // wait till robot1 moved 'distance1'

/* end recording time and distance */
robot1.recordDistanceEnd(JOINT1, numDataPoints1);
robot2.recordDistanceEnd(JOINT1, numDataPoints2);

/* plot the data */
plot.mathCoord();
plot.title("Distances versus time");
plot.label(PLOT_AXIS_X, "Time (seconds)");
plot.label(PLOT_AXIS_Y, "Distances (inches)");
plot.data2DCurve(timedata1, distances1, numDataPoints1);
plot.legend("Distance for robot 1", 0);
plot.data2DCurve(timedata2, distances2, numDataPoints2);
plot.legend("Distance for robot 2", 1);
plot.plotting();

```

Program 11.9: Recording the distances of two Linkbot-Is and plotting the distances versus time. The distances for both robots are specified.

## 11.6. Plot Recorded Distances and Time for Multiple Linkbots

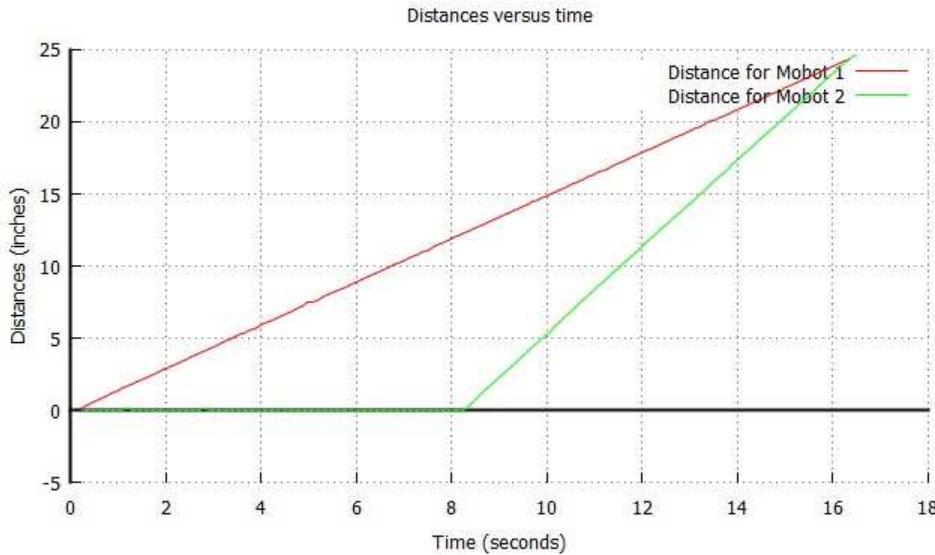


Figure 11.4: The plot for the distances of two Linkbot-Is versus time from Programs 11.9, 11.11, and 11.13.

The member function **recordDistanceBegin()** described in Section 9.1.6 can be used to record the time and distances for a robot. By default, only data points collected while the Linkbot-I is in motion will be stored in the second argument for the time and the third argument for the distance of the function **recordDistanceBegin()** for later use. Any data collected before the Linkbot-I starts moving or after it has stopped will be discarded. Effectively, the recorded data is shifted. Since we want to compare the distance versus time for both Linkbot-Is over the entire 16 second time period, we want to include the data points for `robot2` in the first 8 seconds even when it is standing still. Thus we do not want to shift the data, since we do not want the program to discard those data points. The default shifting of the recorded data can be disabled by the member function **disableRecordDataShift()**. The general syntax for the function **disableRecordDataShift()** is

```
robot.disableRecordDataShift();
```

Similarly, the shifting can be enabled by **enableRecordDataShift()**. The general syntax for the function **enableRecordDataShift()** is

```
robot.enableRecordDataShift();
```

The two lines

```
robot1.disableRecordDataShift();
robot2.disableRecordDataShift();
```

in Program 11.9 disable the shifting for recording data for both `robot1` and `robot2`. The two lines

```
robot1.recordDistanceBegin(JOINT1, timedata1, distances1, radius1, timeInterval);
robot2.recordDistanceBegin(JOINT1, timedata2, distances2, radius2, timeInterval);
```

initiate the recording of time and distance data from joint 1 of both `robot1` and `robot2`. Then `robot1` and `robot2` are commanded to drive the same way they were commanded in Program 11.8. After both `robot1` and `robot2` finished their movement, the lines

```
robot1.recordDistanceEnd(JOINT1, numDataPoints1);
robot2.recordDistanceEnd(JOINT1, numDataPoints2);
```

## 11.6. Plot Recorded Distances and Time for Multiple Linkbots

stop the recording of time and distance data from joint 1 of both `robot1` and `robot2`. At this time, `timedata1`, `distances1` and `numDataPoints1` will hold the time data points, the distance data points, and the total number of data points collected for `robot1`. In addition, the variables `timedata2`, `distances2`, and `numDataPoints2` will hold the time data points, the distance data points, and the total number of data points collected for `robot2`.

The plotting of data for both Linkbot-Is will occur in a similar manner as in previous sections. Data for both Linkbot-Is will be plotted on the same graph. The title as well as the x-axis and y-axis labels will be the same as in Program 9.6. The **CPlot** member function **data2Curve()**, however, will need to be called twice. The line

```
plot.data2DCurve(timedata1, distances1, numDataPoints1);
```

plots the data for `robot1`. The next line

```
plot.legend("Distance for robot 1", 0);
```

creates a legend entry for `robot1` using the **CPlot** member function **legend()**. This function has the syntax

```
plot.legend(legend, num);
```

The argument `legend` is a string with the label you want for a particular data set. The argument `num` indicates the number of the data set corresponding to that label. The reason for starting with the number 0 is beyond the scope of this book. In the case of plotting multiple data sets, it is sufficient to remember to start legend entries with the number 0. When the graph is generated, Ch will automatically print the graph with the legend entries starting with the number 1. Each entry of the legend will show a different color which corresponds to the data of a particular Linkbot. The next two lines

```
plot.data2DCurve(timedata2, distances2, numDataPoints2);
plot.legend("Distance for robot 2", 1);
```

plots the data for `robot2` and creates a corresponding legend entry. The final graph is generated by calling the **CPlot** member function **plotting()**. The resulting graph of distance versus time for both Linkbot-Is can be seen in Figure 11.4.

The first robot drives at the speed of 1.5 inches per second. The relation between the distance ( $d$ ) and time ( $t$ ) in Figure 11.4 for the first robot can be formulated by the following linear equation.

$$d = 1.5t \quad (11.1)$$

The second robot drives at the speed of 3 inches per second and starts to drive 8 seconds later. The relation between the distance ( $d$ ) and time ( $t$ ) in Figure 11.4 for the second robot can be formulated by the following linear equation.

$$d = 3(t - 8) \quad (11.2)$$

The intersection point  $(t, d) = (16, 24)$  of two straight lines in Figure 11.4 satisfies both equations (11.1) and (11.2). The coordinates of the intersection point are the time and location when two robots have traveled the same distance. In algebra,  $(t, d) = (16, 24)$  is called the solution of the system of two linear equations (11.1) and (11.2).

 Do Exercise 1 on page 180.

### 11.6.1 Summary

1. Call the **CLinkbotI** member function

```
robot.disableRecordDataShift();
```

## 11.6. Plot Recorded Distances and Time for Multiple Linkbots

to disable the shifting of the recorded data.

2. Call the **CLinkbotI** member function

```
robot.enableRecordDataShift();
```

to enable the shifting of the recorded data.

3. Call the **CPlot** member function

```
plot.legend(legend, num);
```

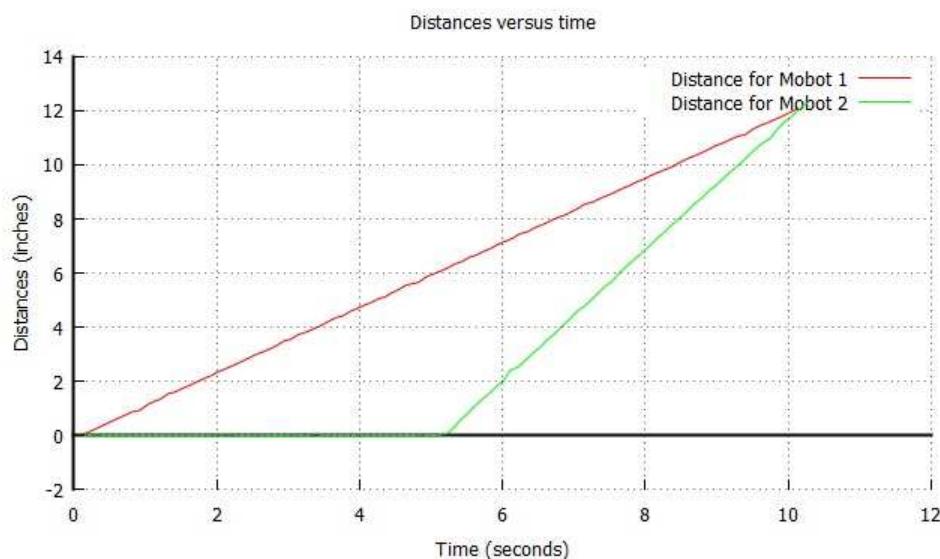
to create a legend entry for an individual Linkbot when plotting data for multiple Linkbots. Remember that the argument `num` should start with the number 0 for the first legend entry.

### 11.6.2 Terminology

**robot.disableRecordDataShift()**, **robot.enableRecordDataShift()**, **plot.legend()**, legend entry, multiple data sets.

### 11.6.3 Exercises

1. Two Linkbot-Is are configured as two-wheel robots. The radii of the wheels are 1.75 inches. Write a program `recorddistancesdist2.ch` to control two Linkbot-Is with the following motions. The first robot drives at the speed of 1.2 inches per second for 12 inches. The 5 seconds after the first robot drives, the second robot drives at the speed of 2.4 inches per second for 12 inches. Record the distances and time during the motion of both robots. Plot the distances versus time as shown in the figure below. What are the equations for the linear relations shown in the figure? Verify that the point  $(t, d) = (10, 12)$  is the solution for the two equations of the linear relations.



## 11.7 Move Multiple Linkbots with Specified Time

In Section 9.2, we learned how to drive a single Linkbot for a specified time using **driveTime()**. In some applications, we need to move multiple Linkbots synchronously for a specified time, using non-blocking functions. The following problem and corresponding Program 11.10 demonstrate how this is done.

**Problem Statement:**

Two Linkbot-Is are configured as two-wheel robots as shown in Figure 11.2 on page 172. The radii of the wheels are 1.75 inches. Write a program **drivetimenb.ch** for two Linkbots racing in the following manner. Both Linkbots will drive from a starting line at different times. The first Linkbot drives for 16 seconds at the speed of 1.5 inches per second. Then 8 seconds after the first Linkbot has left the starting line, the second Linkbot races at the speed of 3 inches per second for 8 seconds.

```
/* File: drivetimenb.ch
Drive two two-wheeled robots with different speeds continuously
with a specified time. */
#include <linkbot.h>
CLinkbotI robot1, robot2;
double radius1=1.75; // the radius of the two wheels of robot1 in inches
double radius2=1.75; // the radius of the two wheels of robot2 in inches
double speed1=1.5, speed2=3; // speed of robots in inches per second
double time1=16; // motion time in seconds for robot1
double delaytime=8; // delay time in seconds for robot2
double time2=8; // motion time in seconds for robot2

/* connect to robots and move to the zero position at the same time. */
robot1.connect();
robot2.connect();
robot1.resetToZeroNB();
robot2.resetToZeroNB();
robot1.moveWait();
robot2.moveWait();

/* set the speed for robot1 */
robot1.setSpeed(speed1, radius1);
/* set the speed for robot2 */
robot2.setSpeed(speed2, radius2);

/* robot1 drives first for a total of 'time1' seconds. 'delaytime' seconds later,
   robot2 drives for 'time2' seconds while robot1 also drives */
robot1.driveTimeNB(time1);
robot2.delaySeconds(delaytime);
robot2.driveTime(time2);
robot1.moveWait(); // wait till robot1 moved 'time1' seconds
```

Program 11.10: Moving multiple Linkbots with specified times using **driveTimeNB()**.

Similar to Program 11.8, Program 11.10 sets the movement state for joints 1 and 3 of multiple Linkbots simultaneously. The lines

```
double radius1=1.75; // the radius of the two wheels of robot1 in inches
double radius2=1.75; // the radius of the two wheels of robot2 in inches
```

## 11.7. Move Multiple Linkbots with Specified Time

declare two variables of **double** type and assigns them both the wheel radius value of 1.75 inches. The next line

```
double speed1=1.5, speed2=3; // speed of robots in inches per second
```

declares two variables of type **double** and assigns them two different speeds in inches. Note that the speed of the second Linkbot-I is twice the speed of the first. Then the next three lines

```
double time1=16; // motion time in seconds for robot1
double delaytime=8; // delay time in seconds for robot2
double time2=8; // motion time in seconds for robot2
```

declare two variables **time1** and **time2** of type **double** and assigns them two different motion times in seconds. Note that the motion time for second Linkbot-I is half the motion time for the first. Another variable **delaytime** of type **double** is also declared, and assigned a value of 8 seconds. This will be used to delay the start of **robot2** for 8 seconds after **robot1** starts moving.

The next six lines of code connect both **robot1** and **robot2** to Linkbots and resets both to the zero position. Then the next two lines

```
robot1.setSpeed(speed1, radius1);
robot2.setSpeed(speed2, radius2);
```

sequentially sets the speeds of **robot1** and **robot2**. The following line

```
robot1.driveTimeNB(time1);
```

sets the movement state of **robot1** for a specific time. This is done using the **CLinkbotI** member function **driveTimeNB()**. The syntax of this function is

```
robot.driveTimeNB(seconds);
```

The argument **seconds** specifies the length of time in seconds to drive the joints of the robot. The direction of the motion for each joint is determined by the speed of the joint.

Since the speeds for both robots are positive. the **robot1** starts moving forward for 16 seconds at 1.5 inches per second. The member function **driveTimeNB()** is the non-blocking counterpart of the function **driveTime()**. It moves joints 1 and 3 of a Linkbot, but it allows the next line of code to execute before it finishes doing so. Therefore the next line of code

```
robot2.delaySeconds(delaytime);
```

delays the start of **robot2** for 8 seconds after **robot1** starts moving. Since **robot1** has a total movement time of 16 seconds, however, it will only be half way through its movement when **robot2** starts to move. This makes the choice of **driveTimeNB()** appropriate for **robot1**. The next line

```
robot2.driveTime(time2);
```

drives **robot2** forward for 8 seconds at 3 inches per second. **robot2** is the last Linkbot in the program to begin moving, and its motion depends on a specific time. Thus the choice of a blocking function is appropriate for **robot2**. After **robot2** has completed its motion, the line

```
robot1.moveWait(); // wait till robot1 moved time1 seconds
```

is included to make sure that **robot1** has completed its motion before the program finishes execution.

Since the speed of the second Linkbot-I is twice as fast as the first one, both Linkbot-Is shall stop at the same finishing line at the same time. The distance traveled by two Linkbot-Is is the same. For the first robot, the distance can be calculated as follows.

$$distance = v * t = 1.5 * 16 = 24 \text{ inches}$$

## 11.7. Move Multiple Linkbots with Specified Time

The distance for the second robot can be calculated as follows.

$$distance = v * t = 3 * 8 = 24 \text{ inches}$$

There is also a non-blocking function to move a single joint for a specified time. The **CLinkbotI** member function **moveJointTimeNB()** has the following general syntax

```
robot.moveJointTimeNB(id, seconds);
```

The argument **id** indicates the joint to move. The argument **seconds** specifies the length of time in seconds to keep the joint in motion. If in Program 11.10 we changed the line

```
robot1.driveTimeNB(time1);
```

to

```
robot1.moveJointTimeNB(JOINT1, time1);
```

then only joint 1 of **robot1** would move for 16 seconds at 1.5 inches per second. Since **moveJointTimeMB()** is non-blocking, the next subsequent lines of code will execute simultaneously.

 Do Exercises 1 and 2 on page 186.

Section 9.2.3 deals with the plotting of distance versus time with a specified speed and time. We can also plot distances versus time with a specified speed and time for two Linkbots. Similar to Programs 11.8 and 11.9, Program 11.10 can be modified to add the data acquisition and plotting code to display the distances versus time. Program 11.11 is very similar to Program 11.9, except that the movement states for both Linkbot-Is are set for a specified time using the member functions **driveTimeNB()** and **driveTime()**. The lines of code moving robots are the same as those from Program 11.10. The plot generated by Program 11.11 looks identical to that generated by Program 11.9, as shown in Figure 11.4. The distances of two Linkbots and time are related by the equations (11.1) and (11.2) as described on page 179.

## 11.7. Move Multiple Linkbots with Specified Time

```

/* File: recorddistancesTime.ch
Record time and distances using driveTime(),
Delay 8 seconds for robot2. The equations of motions are
    d = 1.5t
    d = 3(t-8)
plot the acquired data for two robots */
#include <linkbot.h>
#include <chplot.h>
CLinkbotI robot1, robot2;
double speed1=1.5, speed2=3; // speeds of robots in inches per second
double radius1=1.75, radius2=1.75; // the radii of two wheels of robot1 and 2
double time1=16, time2=8; // motion time in seconds for robot1 and robot2
double delaytime=8; // delay time for robot2
double timeInterval = 0.1; // time interval in 0.1 second
int numDataPoints1, numDataPoints2; // number of data points recorded
robotRecordData_t timedata1, distances1; // recorded time and distances for robot1
robotRecordData_t timedata2, distances2; // recorded time and distances for robot2
CPlot plot; // plotting class

/* connect to robots and move to the zero position at the same time. */
robot1.connect(); robot2.connect();
robot1.resetToZeroNB(); robot2.resetToZeroNB();
robot1.moveWait(); robot2.moveWait();

/* set the speeds for robot1 and robot2 */
robot1.setSpeed(speed1, radius1);
robot2.setSpeed(speed2, radius2);

/* disable record data shift and begin recording time and distance */
robot1.disableRecordDataShift();
robot2.disableRecordDataShift();
robot1.recordDistanceBegin(JOINT1, timedata1, distances1, radius1, timeInterval);
robot2.recordDistanceBegin(JOINT1, timedata2, distances2, radius2, timeInterval);

/* robot1 drives first for a total of 'time1' seconds. 'delaytime' seconds later,
   robot2 drives for 'time2' seconds while robot1 also drives */
robot1.driveTimeNB(time1);
robot2.delaySeconds(delaytime);
robot2.driveTime(time2);
robot1.moveWait(); // wait till robot1 moved 'time1' seconds

/* end recording time and distance */
robot1.recordDistanceEnd(JOINT1, numDataPoints1);
robot2.recordDistanceEnd(JOINT1, numDataPoints2);

/* plot the data */
plot.mathCoord();
plot.title("Distances versus time");
plot.label(PLOT_AXIS_X, "Time (seconds)");
plot.label(PLOT_AXIS_Y, "Distances (inches)");
plot.data2DCurve(timedata1, distances1, numDataPoints1);
plot.legend("Distance for robot 1", 0);
plot.data2DCurve(timedata2, distances2, numDataPoints2);
plot.legend("Distance for robot 2", 1);
plot.plotting();

```

Program 11.11: Recording the distances of two Linkbot-Is and plotting the distances versus time. The movement states of the Linkbot-Is are set with a specified time.

## 11.7. Move Multiple Linkbots with Specified Time

 Do Exercises 3 and 4, on page 194.

If the speeds of two robots are the same, the two lines for distances versus time shall be parallel. We can change

```
double speed1=1.5, speed2=3; // speeds of mobots in inches per second
```

in Program 11.11 to

```
double speed1=1.5, speed2=1.5; // speeds of mobots in inches per second
```

and save the new program as `recordparalleltime.ch`. This program is distributed along with other sample programs. In this program, the speed for the second robot is the same as the first one, 1.5 inches per second. When the program is executed, it will display the output as shown in Figure 11.5.

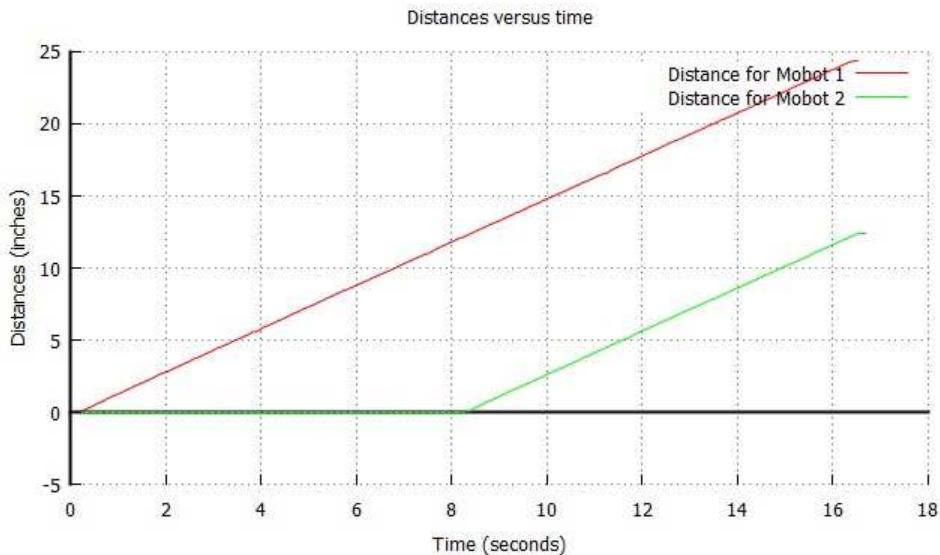


Figure 11.5: The plot for the distances of two Linkbot-Is moving at the same speed.

 Do Exercise 5 on page 187.

### 11.7.1 Summary

1. Call the non-blocking **CLinkbotI** member function

```
robot.driveTimeNB(seconds);
```

to move joints of a Linkbot for the specified time in seconds. The lines of code following the non-blocking member function will begin execution before the specified time in seconds has elapsed.

2. Call the non-blocking **CLinkbotI** member function

```
robot.moveJointTimeNB(id, seconds);
```

to move one joint of a Linkbot-I for a specified time. The lines of code following the non-blocking member function will begin execution before the specified time in seconds has elapsed.

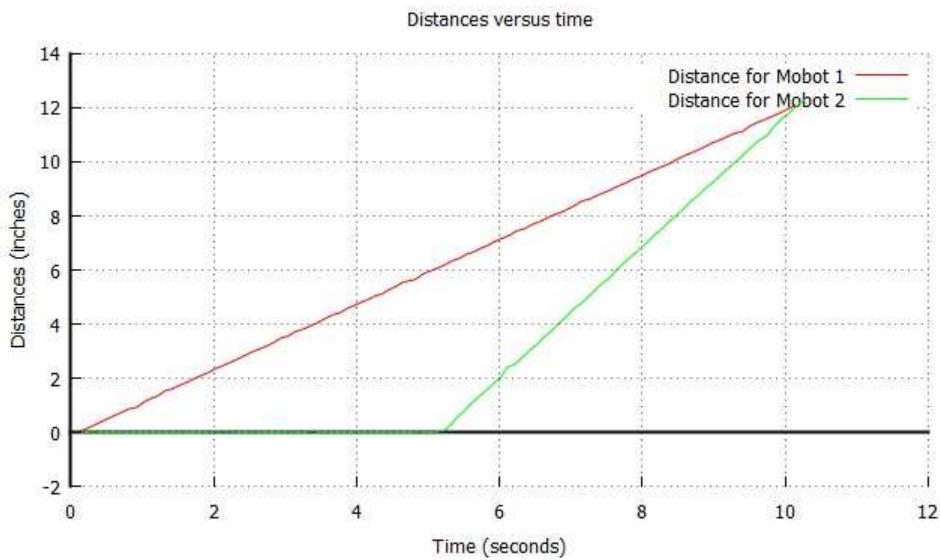
## 11.7. Move Multiple Linkbots with Specified Time

**11.7.2 Terminology**

`robot.driveTimeNB()`, `robot.moveJointTimeNB()`.

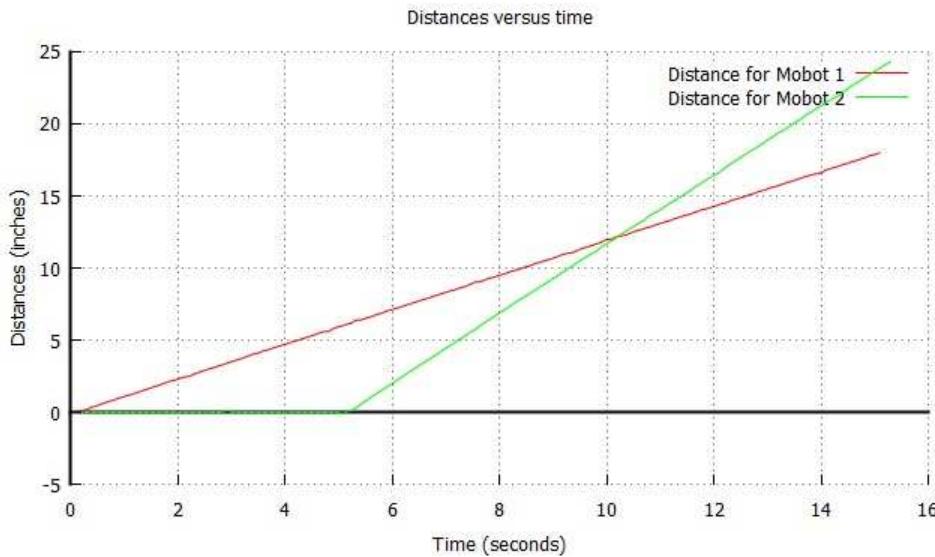
**11.7.3 Exercises**

- Two Linkbot-Is are configured as two-wheel robots. The radii of the wheels are 1.75 inches. Write a program `drivetimeNb2.ch` for two Linkbot-Is racing in the following manner. Two Linkbot-Is will drive from a starting line at different times. The first Linkbot-I drives for 10 seconds at the speed of 1.2 inches per second. Then 5 seconds after the first Linkbot-I has left the starting line, the second Linkbot-I races at the speed of 2.4 inches per second for 5 seconds.
- Two Linkbot-Is are configured as two-wheel robots. The radii of the wheels for the first Linkbot-I are 1.75 inches. The radii of the wheels for the second Linkbot-I are 2 inches. Write a program `drivetimeNb3.ch` for two Linkbot-Is racing in the following manner. Two Linkbots will drive from a starting line at the same time at the same speed of 1.5 inches per second for 10 seconds.
- Two Linkbot-Is are configured as two-wheel robots. The radii of the wheels are 1.75 inches. Write a program `recorddistancetimes2.ch` to control two Linkbot-Is with the following motions. The first robot drives at the speed of 1.2 inches per second. Then 5 seconds later, the second robot drives at the speed of 2.4 inches per second. Then 5 seconds later, both robots stop. Record the distances and time during the motion of both robots. Plot the distances versus time as shown in the figure below. What are the equations for the linear relations shown in the figure? Verify that the point  $(t, d) = (10, 12)$  is the solution for the two equations of the linear relations.

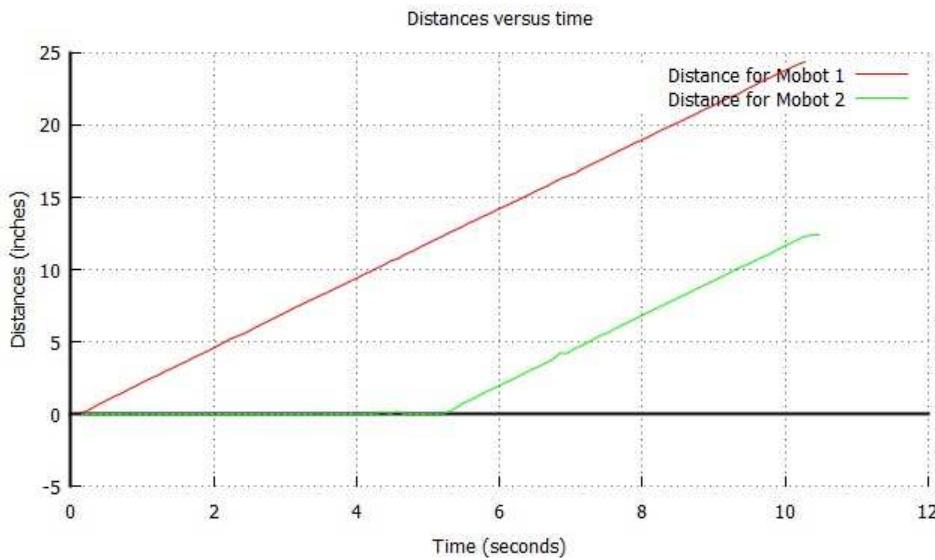


- Two Linkbot-Is are configured as two-wheel robots. The radii of the wheels are 1.75 inches. Write a program `recorddistancetimes3.ch` to control two robots with the following motions. The first robot drives at the speed of 1.2 inches per second for 15 seconds. The 5 seconds after the first robot drives, the second robot drives at the speed of 2.4 inches per second for 10 seconds. Both robots stop at the same time. Record the distances and time during the motion of both robots. Plot the distances versus time as shown in the figure below.

## 11.8. Move Multiple Linkbots Forever



5. Two Linkbot-Is are configured as two-wheel robots. The radii of the wheels are 1.75 inches. Write a program `recordparalleltime2.ch` to control two robots with the following motions. Both robots drive at the same speed of 2.4 inches per second. The first robot drives first. Then 5 seconds later, the second robot drives. Then 5 seconds later, both robots stop. Record the distances and time during the motion of both robots. Plot the distances versus time as shown in the figure below.



## 11.8 Move Multiple Linkbots Forever

In some situations, moving a robot for a specified time may not be desirable. In addition to moving joints with a specified time, a robot can be moved indefinitely with the member function `driveForeverNB()`. The motion problem for two two-wheel drive vehicles, as shown in Figure 11.2 on page 172 and described in section 11.7, can be solved using this function.

## 11.8. Move Multiple Linkbots Forever

```

/* File: driveforevernb.ch
Drive two two-wheeled robots with different speeds continuously
with a specified time using drivForeverNB(). */
#include <linkbot.h>
CLinkbotI robot1, robot2;
double radius1=1.75; // the radius of the two wheels of robot1 in inches
double radius2=1.75; // the radius of the two wheels of robot2 in inches
double speed1=1.5, speed2=3; // speed of robots in inches per second
double time=16; // motion time in seconds for robot1
double delaytime=8; // delay time for robot2

/* connect to robots and move to the zero position at the same time. */
robot1.connect();
robot2.connect();
robot1.resetToZeroNB();
robot2.resetToZeroNB();
robot1.moveWait();
robot2.moveWait();

/* set the speed for robot1 */
robot1.setSpeed(speed1, radius1);
/* set the speed for robot2 */
robot2.setSpeed(speed2, radius2);

/* robot1 drives first, 'delaytime' seconds later, robot2 drives.
Both robots drive for 'time-delaytime' seconds at the same time.
Then, both robots stop */
robot1.driveForeverNB();
robot2.delaySeconds(delaytime);
robot2.driveForeverNB();
robot2.delaySeconds(time-delaytime);
robot1.holdJoints();
robot2.holdJoints();

```

Program 11.12: Moving multiple Linkbots with specified times using **driveForeverNB()**.

In Program 11.12, the variable `time` of type **double** is declared and assigned a value of 16 seconds. Since motion states for both Linkbots will not be set for a specific time, the variable `time` will be used to calculate delay. The **CLinkbotI** member function **driveForeverNB()** has the general syntax

```
robot.driveForeverNB();
```

Unlike the function **driveTimeNB()**, the function **driveForeverNB()** will move joints of the robot indefinitely. In other words, joints 1 and 3 of the Linkbot-I will move until another function call changes the joint states. **driveForeverNB()** is a non-blocking function, which means that the next line of code will start to execute immediately afterward. The line

```
robot1.driveForeverNB();
```

starts moving `robot1` forward at a speed of 1.5 inches per second. The resulting movement is the same as in Program 11.10, except that there is no time limit. Whereas in Program 11.10 `robot1` was commanded to move forward for only 16 seconds, in Program 11.12 `robot1` will continue moving forward until the movement state is changed. The next line of code calls the member function **delaySeconds()** to delay execution of the next line of code for 8 seconds, as in Program 11.10. The following line

```
robot2.driveForeverNB();
```

## 11.8. Move Multiple Linkbots Forever

starts moving `robot2` forward at a speed of 3 inches per second. As it is for `robot1`, the motion time for `robot2` is also unlimited. At this point both `robot1` and `robot2` will be moving forward simultaneously. Since the movement state of `robot2` has been set using a non-blocking function, the next program statement

```
robot2.delaySeconds(time-delaytime);
```

is called to delay the execution of the next line of code for `time-delaytime` seconds, which equals 8 seconds.

You can hold all joint angles of a Linkbot by calling the member function **holdJoints()**. The general syntax of this function is

```
robot.holdJoints();
```

The lines

```
robot1.holdJoints();
robot2.holdJoints();
```

hold joints 1 and 3 of `robot1` and `robot2`. This will stop the motion of both `robot1` and `robot2`. Both Linkbots will hold their current positions as the program finishes execution, until they run out of power or are turned off manually.

As in Program 11.10, the speed of the second Linkbot-I is twice as fast as the first one. Both Linkbot-Is shall stop at the same finishing line at the same time, and the distance traveled by two Linkbot-Is is the same.

There is also a non-blocking function to move a single joint for an indefinite period of time. The **CLinkbotI** member function **moveJointForeverNB()** has the following general syntax

```
robot.moveJointForeverNB(id);
```

The argument `id` indicates the joint to move. Since this function is non-blocking, the next line of code will execute simultaneously.

 Do Exercises 1 and 2 on page 194.

Similar to Programs 11.8 and 11.9, and Programs 11.10 and 11.11, Program 11.12 can be modified to add the data acquisition and plotting code to display the distances versus time. Program 11.13 is very similar to Program 11.11, except that the movement states for both Linkbot-Is are set for a specified time using the member function **driveForeverNB()**. The lines of code moving robots are the same as those from Program 11.12. The plot generated by Program 11.13 looks identical to that generated by Programs 11.9 and 11.11, as shown in Figure 11.4. The distances of two Linkbots and time are also related by the equations (11.1) and (11.2) as described on page 179.

## 11.8. Move Multiple Linkbots Forever

```

/* File: recorddistances.ch
Record time and distances, plot the acquired data for two robots.
The equations of motions are
    d = 1.5t
    d = 3(t-8)
*/
#include <linkbot.h>
#include <chplot.h>
CLinkbotI robot1, robot2;
double speed1=1.5, speed2=3; // speeds of robots in inches per second
double radius1=1.75, radius2=1.75; // the radii of two wheels of robot1 and 2
double time=16; // motion time in seconds for robot1
double delaytime=8; // delay time for robot2
double timeInterval = 0.1; // time interval in 0.1 second
int numDataPoints1, numDataPoints2; // number of data points recorded
robotRecordData_t timedata1, distances1; // recorded time and distances for robot1
robotRecordData_t timedata2, distances2; // recorded time and distances for robot2
CPlot plot; // plotting class

/* connect to robots and move to the zero position at the same time. */
robot1.connect(); robot2.connect();
robot1.resetToZeroNB(); robot2.resetToZeroNB();
robot1.moveWait(); robot2.moveWait();

/* set the speeds for robot1 and robot2 */
robot1.setSpeed(speed1, radius1);
robot2.setSpeed(speed2, radius2);

/* disable record data shift and begin recording time and distance */
robot1.disableRecordDataShift();
robot2.disableRecordDataShift();
robot1.recordDistanceBegin(JOINT1, timedata1, distances1, radius1, timeInterval);
robot2.recordDistanceBegin(JOINT1, timedata2, distances2, radius2, timeInterval);

/* robot1 drives first, 'delaytime' seconds later, robot2 drives.
Both robots drive for 'time-delaytime' seconds at the same time.
Then, both robots stop */
robot1.driveForeverNB();
robot2.delaySeconds(delaytime);
robot2.driveForeverNB();
robot2.delaySeconds(time-delaytime);
robot1.holdJoints();
robot2.holdJoints();

/* end recording time and distance */
robot1.recordDistanceEnd(JOINT1, numDataPoints1);
robot2.recordDistanceEnd(JOINT1, numDataPoints2);

/* plot the data */
plot.mathCoord();
plot.title("Distances versus time");
plot.label(PLOT_AXIS_X, "Time (seconds)");
plot.label(PLOT_AXIS_Y, "Distances (inches)");
plot.data2DCurve(timedata1, distances1, numDataPoints1);
plot.legend("Distance for robot 1", 0);
plot.data2DCurve(timedata2, distances2, numDataPoints2);
plot.legend("Distance for robot 2", 1);
plot.plotting();

```

Program 11.13: Recording the distances of two Linkbot-Is and plotting the distances versus time.

## 11.8. Move Multiple Linkbots Forever

 Do Exercises 3 and 4 on page 194.

Similar to the program `recordparalleltime.ch` which generates Figure 11.5, the program `recordparallel.ch` generates the same output using the member function `driveForeverNB()`. This program is distributed along with other sample programs.

 Do Exercise 5 on page 194.

### 11.8.1 A Baton Passing Robot Relay Race

An application of using multiple robots can be illustrated by a robot relay race. In this example, accelerometer data as described in section 10.4 is used to detect the motion of a robot.

#### An Application Example:

Write a program `batonpass.ch` to simulate the passing of a baton in a relay race using two two-wheel robots configured and oriented as shown in Figure 11.6. Both robots begin with red LEDs. When the first robot begins to move, its LED changes to green, while the second robot remains stationary with a red LED. The first robot should be able to travel any distance to reach the second. When the first robot runs into the second one, the accelerometer of the second robot responds to the bump. The first robot then stops and changes its LED back to red as the second robot begins traveling forward with a green LED for 6 inches.



Figure 11.6: Passing a baton in a relay race with two robots.

## 11.8. Move Multiple Linkbots Forever

```

/* File: batonpass.ch
   Pass a baton (green light) in a relay race with two Linkbot-Is using accelerometer data. */
#include <linkbot.h>
CLinkbotI robot1, robot2;
double distance=6;      // the distance of 6 inches to drive forward
double radius=1.75;    // the radius of 1.75 inches of the two wheels of the robot
double x, y1, y2, z; // accelerometer values in x, y, and z components

/* connect to robots and move to the zero position at the same time. */
robot1.connect();        robot2.connect();
robot1.resetToZeroNB();  robot2.resetToZeroNB();
robot1.moveWait();       robot2.moveWait();

robot1.setLEDColor("red");
robot2.setLEDColor("red");
robot1.driveForeverNB();
robot1.setLEDColor("green");

/* while the y component of the accelerometer does not change, keep reading it. */
robot2.getAccelerometerData(x, y1, z);
y2=y1;
while(abs(y2-y1)<0.03) {
    robot2.getAccelerometerData(x, y2, z);
}
robot2.setLEDColor("green");
robot2.driveDistanceNB(distance, radius);
robot1.holdJoints();
robot1.setLEDColor("red");
robot2.moveWait();
robot2.setLEDColor("red");

```

Program 11.14: Passing a baton (green light) in a relay race with two robots using the accelerometer data.

When the first robot runs into the second one, the y component of the accelerometer of the second robot as shown in Figure 10.2 should change. We can use this information to control the motion and LED colors of both robots accordingly.

Program 11.14 use two variables `y1` and `y2` to keep the y components of the accelerometer for the second robot at different time for comparison. Program 11.14 first set the LED colors of two Linkbot-Is to red using the member function `setLEDColor()`. The statements

```

robot1.driveForeverNB();
robot1.setLEDColor("green");

```

then move the first robot forward and set its LED color to green. The lines

```

robot2.getAccelerometerData(x, y1, z);
y2=y1;

```

obtain the accelerometer data for the second robot and make sure the variables `y1` and `y2` contain the same value for the y component of the accelerometer before the comparison is made. The `while` loop

```

while(abs(y2-y1)<0.03) {
    robot2.getAccelerometerData(x, y2, z);
}

```

monitors the change of the y component of the accelerometer of the second robot. The mathematics function `abs()` returns the absolute value of its argument. For example, `abs(1.5)` returns 1.5 and `abs(-1.5)` also returns 1.5. Due to the noise, the difference expression  $y2 - y1$  could be negative or positive at each reading

## 11.8. Move Multiple Linkbots Forever

of the accelerometer data. The condition expression  $\text{abs}(y2 - y1) < 0.03$  uses the function **abs()** to obtain the absolute value of the difference between the values of the two variables `y1` and `y2`. When the second robot is not bumped, the absolute value for the difference for each reading of the accelerometer should be less than 0.03. In this case, the **while** loop keeps reading the accelerometer and pass the `y` component to the variable `y2` for comparison. When the second robot is bumped by the first robot, the result `abs(y2-y1)` should be greater than 0.03. The control of the flow of the program will move to the following statements

```
robot2.setLEDColor("green");
robot2.driveDistanceNB(distance, radius);
robot1.holdJoints();
robot1.setLEDColor("red");
```

The above statements will set the LED color of the second robot to green, move the second robot for the specified `distance` and at the same time hold the first robot, and change the LED color of the first robot to red. The next statements

```
robot2.moveWait();
robot2.setLEDColor("red");
```

will wait for the second robot to finish its motion before its color is changed to red and the program exits.

 Do Exercises 6, and 7 on page 194.

### 11.8.2 Summary

1. Call the non-blocking **CLinkbotI** member function

```
robot.driveForeverNB();
```

to move joints of a Linkbot, for an unlimited amount of time. The following lines of code begin execution immediately before the statement containing **driveForeverNB()** has finished executing.

2. Call the non-blocking **CLinkbotI** member function

```
robot.moveJointForeverNB(id);
```

move a joint of a Linkbot, for an unlimited amount of time. The following lines of code begin execution immediately before the statement containing **moveJointForeverNB()** has finished executing.

3. Call the **CLinkbotI** member function

```
robot.holdJoints();
```

to relax all joint of a Linkbot.

4. Call the function

```
abs(x)
```

to get the absolute value of its argument `x`.

## 11.8. Move Multiple Linkbots Forever

**11.8.3 Terminology**

**robot.driveForeverNB()**, **robot.moveJointForeverNB()**, absolute value, **abs()**.

**11.8.4 Exercises**

1. Write a program `driveforevernb2.ch` to control two Linkbot-Is with the following motions. The first Linkbot drives joints 1 and 3 continuously until the second Linkbot-I finishes rotating forward by 360 degrees.
2. Two Linkbot-Is are configured as two-wheel robots. The radii of the wheels are 1.75 inches. (a) Write a program `driveforevernb3.ch` to control two Linkbot-Is with the following motions. The first Linkbot drives at the speed of 1.2 inches per second. 5 seconds later, the second Linkbot drives at the speed of 2.4 inches per second. 5 seconds later, both Linkbots stop.
3. Modify the program `recorddistancetime2.ch` developed in Exercise 3 on page 186 as the program `recorddistances2.ch` using the member function **driveTimeNB()**.
4. Modify the program `recorddistancetime3.ch` developed in Exercise 4 on page 186 as the program `recorddistances3.ch` using the member functions **driveTimeNB()** and **driveForeverNB()**.
5. Modify the program `recordparalleltime2.ch` developed in Exercise 5 on page 187 as the program `recordparallel2.ch` using the member functions **driveTimeNB()** and **driveForeverNB()**.
6. Modify Program 11.14 as the program `batonpass2.ch` to simulate the passing of a baton in a relay race using two robots as shown in Figure 11.6. Change the **while** in Program 11.14 to the code below

```
printf("y1 = %lf\n", y1);
while(abs(y2-y1)<0.03) {
    robot2.getAccelerometerData(x, y2, z);
    printf("y2 inside the while loop = %lf\n", y2);
}
printf("y2 after the while loop = %lf\n", y2);
```

to watch the y component of the accelerometer for the second robot before and when it is bumped by the first robot. Also modify the program so that when the second robot is bumped by the first robot, the buzzer will be set on with the frequency of 450 till the second robot drives for 8 inches to reach its finish line.

7. Write a program `batonpass3.ch` to simulate the passing of a baton in a relay race using three robots as shown in Figure 11.7. All robots begin with red LEDs. When the first robot begins to move, its LED changes to green, while the second and third robots remain stationary with red LEDs. The first and second robots should be able to travel any distance to reach the next. When the first robot runs into the second one, the the accelerometer of the second robot responds to the bump. The first robot then stops and changes its LED back to red as the second robot begins travelling forward with a green LED. The second robot travels to run into the third robot, passes the baton (the second robot LED turns red and the third robot LED turns green), and the third robot carries the baton for 6 inches to the finish and then changes its LED back to red. You may view the video `batonpass.mp4` distributed along with other C-STEM videos.

## 11.9. Plot Recorded Distances and Time for Multiple Linkbots with an Offset for the Distance



Figure 11.7: Passing a baton in a relay race with three robots.

## 11.9 Plot Recorded Distances and Time for Multiple Linkbots with an Offset for the Distance

In Section 9.1.7 we learned how to record and plot distance versus time for a single Linkbot-I with a specified speed and distance with an offset. In this section we will learn how to plot the distances versus time for two Linkbot-Is with an offset for the distance of a robot through an application example.

### Problem Statement:

Two Linkbot-Is are configured as two-wheel robots, as shown in Figure 11.2 on page 172. The radii of the wheels are 1.75 inches. The first robot is placed in an X-Y coordinate system at the coordinate (0, 6). The second robot is placed at (6, 0). Write a program `recorddistancesoffset.ch` to move the first robot at the speed of 1.5 inches per second for 12 seconds. After 4 seconds delay, the second robot moves at the speed of 3 inches per second. Both robots move together for 8 seconds. Record the distances as the robots travel with a time interval of 0.1 second. Plot the distances for both robots versus time.

## 11.9. Plot Recorded Distances and Time for Multiple Linkbots with an Offset for the Distance

```

/* File: recorddistancesoffset.ch
   Record time and distances using driveTime(), with an offset distance by
       robot1.recordDistanceOffset(offset);
   Delay 4 seconds for robot2. The equations of motions are
       d = 6 + 1.5t
       d = 3(t-4)
   Plot the acquired data for two robots */
#include <linkbot.h>
#include <chplot.h>
CLinkbotI robot1, robot2;
double speed1=1.5, speed2=3; // speeds of robots in inches per second
double radius1=1.75, radius2=1.75; // the radii of two wheels of robot1 and robot2
double offset=6; // the offset for the distance of robot1
double time1=12, time2=8; // motion time in seconds for robot1 and robot2
double delaytime=4; // delay time for robot2
double timeInterval = 0.1; // time interval in 0.1 second
int numDataPoints1, numDataPoints2; // number of data points recorded
robotRecordData_t timedata1, distances1; // recorded time and distances for robot1
robotRecordData_t timedata2, distances2; // recorded time and distances for robot2
CPlot plot; // plotting class

/* connect to robots and move to the zero position at the same time. */
robot1.connect(); robot2.connect();
robot1.resetToZeroNB(); robot2.resetToZeroNB();
robot1.moveWait(); robot2.moveWait();

/* set the speeds for robot1 and robot2 */
robot1.setSpeed(speed1, radius1);
robot2.setSpeed(speed2, radius2);

/* set the offset of the distance for robot1 */
robot1.recordDistanceOffset(offset);

/* disable record data shift and begin recording time and distance */
robot1.disableRecordDataShift();
robot2.disableRecordDataShift();
robot1.recordDistanceBegin(JOINT1, timedata1, distances1, radius1, timeInterval);
robot2.recordDistanceBegin(JOINT1, timedata2, distances2, radius2, timeInterval);

/* robot1 drives first for a total of 'time1' seconds.
   'delaytime' seconds later, robot2 drives for 'time2' seconds while robot1 also drives */
robot1.driveTimeNB(time1);
robot2.delaySeconds(delaytime);
robot2.driveTime(time2);
robot1.moveWait(); // wait till robot1 moved 'time1' seconds
robot1.recordDistanceEnd(JOINT1, numDataPoints1);
robot2.recordDistanceEnd(JOINT1, numDataPoints2);

/* plot the data */
plot.mathCoord();
plot.title("Distances versus time");
plot.label(PLOT_AXIS_X, "Time (seconds)");
plot.label(PLOT_AXIS_Y, "Distances (inches)");
plot.data2DCurve(timedata1, distances1, numDataPoints1);
plot.legend("Distance for robot 1", 0);
plot.data2DCurve(timedata2, distances2, numDataPoints2);
plot.legend("Distance for robot 2", 1);
plot.plotting();

```

Program 11.15: Recording the distances of two Linkbot-Is and plotting the distances versus time with an offset for the distance of robot 1.

## 11.9. Plot Recorded Distances and Time for Multiple Linkbots with an Offset for the Distance

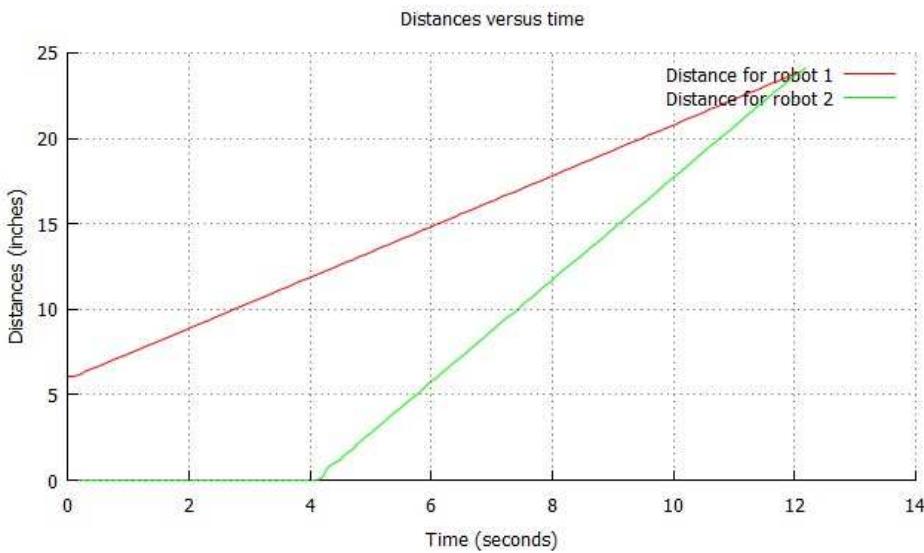


Figure 11.8: The plot for the distances of two Linkbot-Is versus time from Program 11.15.

Program 11.15 is written based on Program 11.11. We only changed the code

```
double time1=16, time2=8; // motion time in seconds for robot1 and robot2
double delaytime=8; // delay time for robot2
```

in Program 11.11 to

```
double offset=6; // the offset for the distance of robot1
double time1=12, time2=8; // motion time in seconds for robot1 and robot2
double delaytime=4; // delay time for robot2
```

in Program 11.15. In addition, we added the statement

```
robot1.recordDistanceOffset(offset);
```

for the offset of the distance for robot 1. The resulting graph of distance versus time for both Linkbot-Is is shown in Figure 11.8.

As shown in Figure 11.8, the relation between the distance ( $d$ ) and time ( $t$ ) for the first robot can be formulated by the following linear equation.

$$d = 6 + 1.5t \quad (11.3)$$

The second robot moves at the speed of 3 inches per second and starts to move 4 seconds later. The linear relation between the distance ( $d$ ) and time ( $t$ ) can be formulated by the equation.

$$d = 3(t - 4) \quad (11.4)$$

The intersection point  $(t, d) = (12, 24)$  of two straight lines in Figure 11.8 satisfies both equations (11.3) and (11.4). Physically, the first robot moves at the position 6 inches ahead of the second robot for 12 seconds and travels for 18 inches to reach the position 24 inches. The second robot moves at 6 inches behind the first robot after the first robot moved for 4 seconds. 8 seconds after the second robot moves, the second robot also reaches the position 24 inches. The total distance traveled by the second robot is 24 inches.

Do Exercise 1 on page 201.

## 11.9. Plot Recorded Distances and Time for Multiple Linkbots with an Offset for the Distance

**Problem Statement:**

The first robot is placed in an X-Y coordinate system at the coordinate (0, 6). The second robot is placed at (6, 0). Write a program `recorddistancesoffset2.ch` to move the first robot at the speed of 1.5 inches per second for 12 seconds and the second robot at the speed of 3 inches per second for 10 seconds. Both robots start to move at the same time. Record the distances as the robots travel with a time interval of 0.1 second. Plot the distances for both robots versus time.

The program `recorddistancesoffset2.ch` distributed along with the other programs in this book is the same as Program 11.15, except that the statements

```
robot1.driveTimeNB(time1);
robot2.delaySeconds(delaytime);
robot2.driveForeverNB(time2);
robot1.recordDistanceEnd(JOINT1, numDataPoints1);
robot2.recordDistanceEnd(JOINT1, numDataPoints2);
```

in Program 11.15 are changed to

```
robot1.driveTimeNB(time1);
robot2.driveTime(time2);
robot1.moveWait();
robot1.recordDistanceEnd(JOINT1, numDataPoints1);
robot2.recordDistanceEnd(JOINT1, numDataPoints2);
```

in the program `recorddistancesoffset2.ch` so that both robots 1 and 2 move at the same time. Since robot 1 moves for 12 seconds and robot 2 moves for 8 seconds, the statement

```
robot1.moveWait();
```

is used to wait till robot 1 has moved for 12 seconds before the statement

```
robot1.recordDistanceEnd(JOINT1, numDataPoints1);
```

is called to terminate the motion of robot 1. The plot from the program `recorddistancesoffset2.ch` is shown in Figure 11.9.

As shown in Figure 11.9, the linear relation between the distance ( $d$ ) and time ( $t$ ) for the first robot is as follows.

$$d = 6 + 1.5t \quad (11.5)$$

The linear relation between the distance ( $d$ ) and time ( $t$ ) for the second robot can be formulated as follows.

$$d = 3t \quad (11.6)$$

The intersection point  $(t, d) = (4, 12)$  of two straight lines in Figure 11.9 satisfies both equations (11.5) and (11.6). Physically, it means that 4 seconds after the motion starts for both robots 1 and 2, robot 1 has moved 8 inches and robot 2 have moved 12 inches. Because robot 1 is placed 4 inches ahead of robot 2, they both reach the position 12 inches.

 Do Exercise 2 on page 202.

The program `recorddistancesoffset22.ch` removed the statement

```
robot1.moveWait();
```

It generates the plot shown in Figure 11.10. In this case, the data recording for robot 1 only lasts for 8 seconds although robot 1 moves for 12 seconds.

The program `recorddistancesoffset23.ch` uses the following statements for motion synchronization.

## 11.9. Plot Recorded Distances and Time for Multiple Linkbots with an Offset for the Distance



Figure 11.9: The plot for the distances of two Linkbot-Is versus time from the program `recorddistancesoffset2.ch` without the time delay.



Figure 11.10: The plot for the distances of two Linkbot-Is versus time from the program `recorddistancesoffset22.ch` without the `moveWait()` statement.

## 11.9. Plot Recorded Distances and Time for Multiple Linkbots with an Offset for the Distance



Figure 11.11: The plot for the distances of two Linkbot-Is versus time from the program recorddistancesoffset23.ch.

```
robot1.driveTimeNB(time1);
robot2.driveTime(time2);
robot2.recordDistanceEnd(JOINT1, numDataPoints2);
robot1.moveWait();
robot1.recordDistanceEnd(JOINT1, numDataPoints1);
```

Once the motion for robot 2 finishes, the data recording is stopped while robot 1 is still moving. The program recorddistancesoffset23.ch generates the plot shown in Figure 11.11.

Do Exercise 3 on page 202.

You can call the member functions **driveTime()** and **driveTimeNB()** to move a Linkbot-I backward if the speed of a robot is negative. For example, the program recordinterceptoffset.ch, uses the statements below to move a Linkbot-I backward, with the generated plot shown in Figure 11.12.

```
robot1.setSpeed(-speed1, radius1); // negative speed for robot1
...
robot.driveTimeNB(time);
```

The program is distributed along with other sample programs,

Do Exercise 4 on page 203.

Instead of using the member functions **driveTime()** and **driveTimeNB()** with the specified time, the distances and time for multiple Linkbots with an offset for the distance can be solved using the member functions **driveDistance()** and **driveDistanceNB()** with the specified distance. Programs recorddistancesdistoffset.ch and recordinterceptdistoffset.ch demonstrate how to use these member functions with an offset for the distance. These programs are distributed along with other sample programs,

Do Exercises 5 and 6 on page 203

## 11.9. Plot Recorded Distances and Time for Multiple Linkbots with an Offset for the Distance

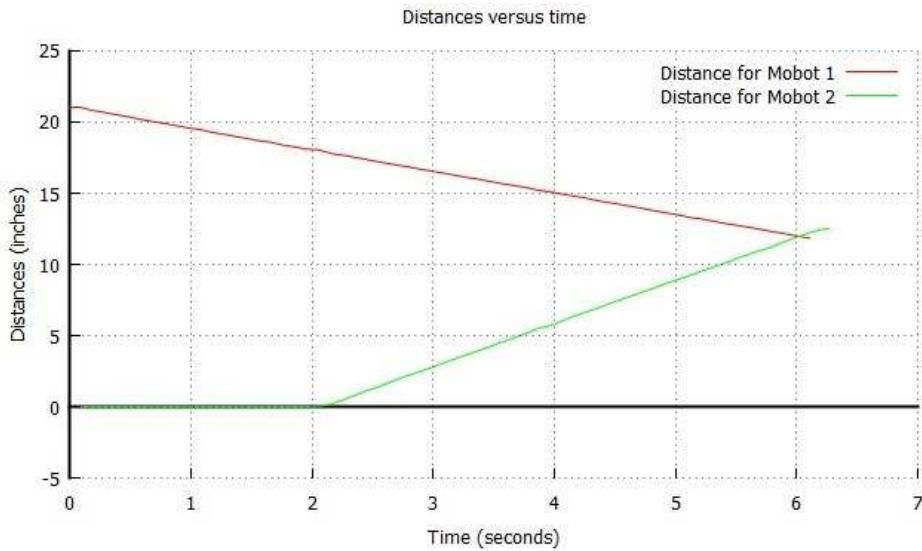


Figure 11.12: The plot for the distances of two Linkbot-Is versus time from the program recordinterceptoffset.ch.

### 11.9.1 Summary

- Plot the distances versus time for multiple robots with an offset for the distance.

### 11.9.2 Terminology

### 11.9.3 Exercises

- Two Linkbot-Is are configured as two-wheel robots. The radii of the wheels are 1.75 inches. The first robot is placed in an X-Y coordinate system at the coordinate (0, 6). The second robot is placed at (6, 0). Write a program recorddistancesoffset3.ch to drive the first robot at the speed of 1.2 inches per second for 15 seconds. After 5 seconds delay, the second robot drives at the speed of 2.4 inches per second. Both robots drive together for 10 seconds. Record the distances as the robots travel with a time interval of 0.1 second. Plot the distances versus time as shown in the figure below. What are the equations for the linear relations shown in the figure? Verify that the point  $(t, d) = (15, 24)$  is the solution for the two linear equations.

## 11.9. Plot Recorded Distances and Time for Multiple Linkbots with an Offset for the Distance

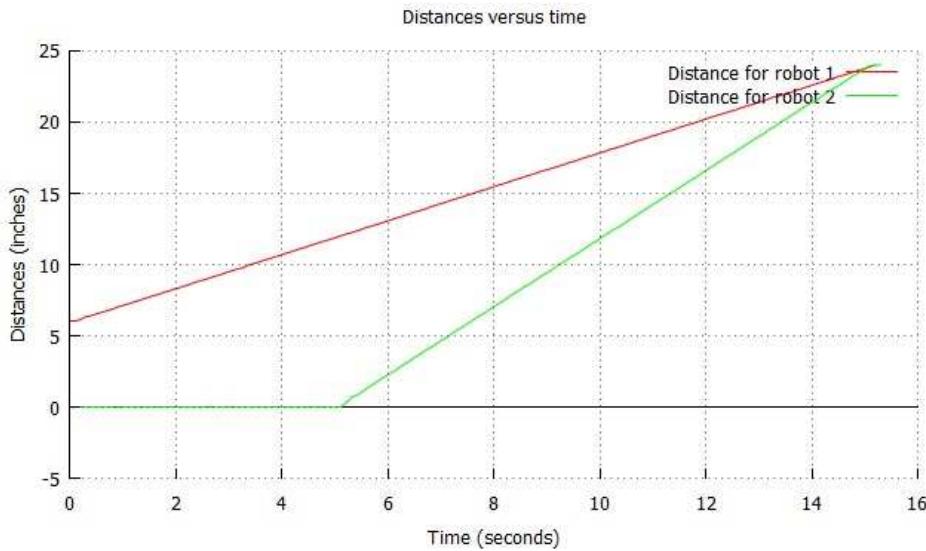
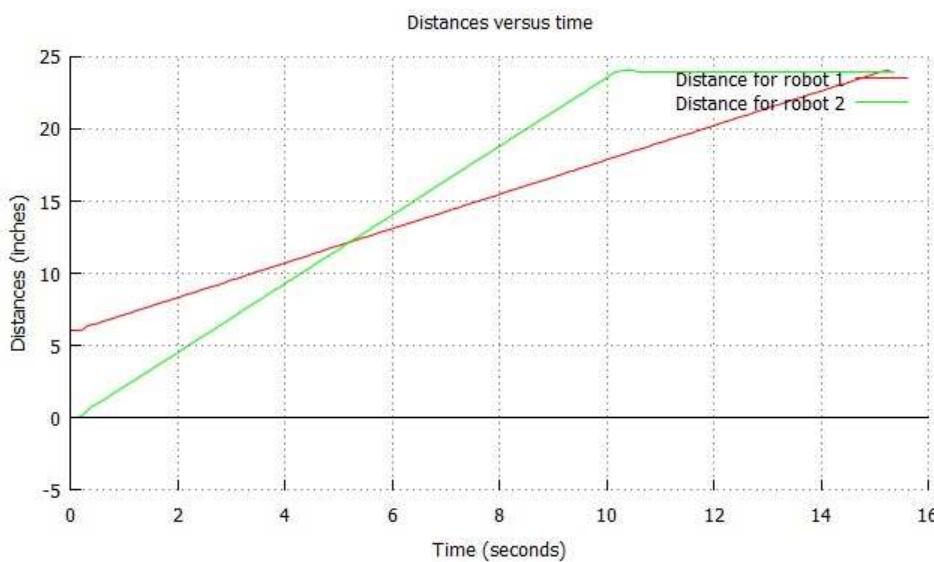


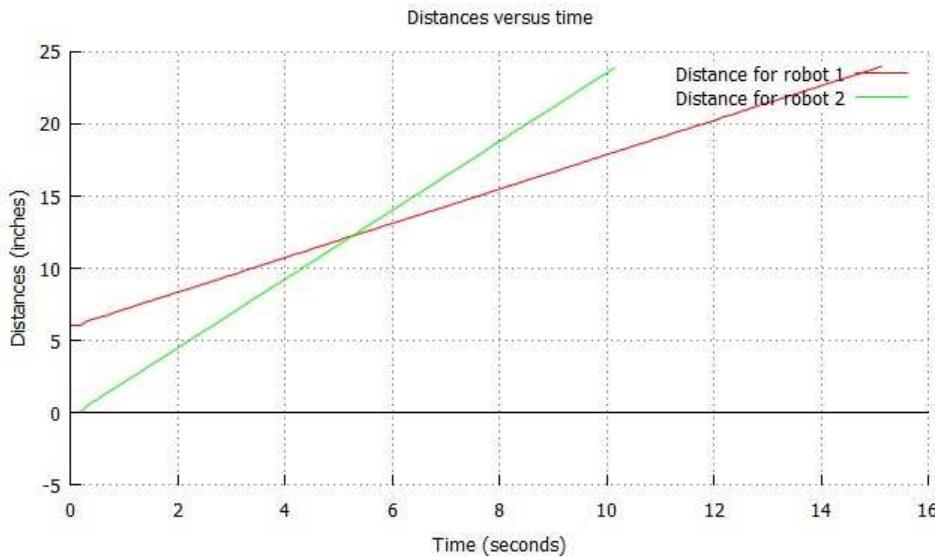
Figure 11.13: Two robots moving in the same direction.

2. Two Linkbot-Is are configured as two-wheel robots. The radii of the wheels are 1.75 inches. The first robot is placed in an X-Y coordinate system at the coordinate (0, 6). The second robot is placed at (6, 0). Write a program `recorddistancesoffset4.ch` to drive the first robot at the speed of 1.2 inches per second for 15 seconds. and the second robot at the speed of 2.4 inches per second for 10 seconds. Record the distances as the robots travel with a time interval of 0.1 second. Plot the distances versus time as shown in the figure below. What are the equations for the linear relations shown in the figure? Verify that the point  $(t, d) = (5, 12)$  is the solution for the two linear equations.



3. Modify the program `recorddistancesoffset4.ch` developed in Exercise 2 as `recorddistancesoffset43.ch` to produce a plot shown below.

## 11.9. Plot Recorded Distances and Time for Multiple Linkbots with an Offset for the Distance



- Two Linkbots are configured as two-wheel robots. The radii of the wheels are 1.75 inches. The first robot is placed in an X-Y coordinate system at the coordinate (0, 21). The second robot is placed at (6, 0). Write a program `recordinterceptoffset2.ch` to drive the first Linkbot backward using the member function `driveTimeNB()` at the speed of 1.5 inches per second for 6 seconds. Then 2 seconds after the first Linkbot drives, the second Linkbot drives forward at the speed of 3 inches per second for 4 seconds using the member function `driveTime()`. Record the distances as the robots travel with a time interval of 0.1 second. Plot the distances for both Linkbots versus time similar to the one shown in the figure below. What are the equations for the linear relations shown in the figure? Verify that the point  $(t, d) = (6, 12)$  is the solution for two linear equations.



Figure 11.14: Two robots moving in opposite directions.

- Write a program `recorddistancesdistoffset2.ch` using the member functions `driveDis-`

## 11.10. ‡ Copy Motions of a Controller Linkbot to a Controlled Linkbot

**tanceNB()** and **driveDistance()** to reproduce Figure 11.13 shown in Exercise 1.

6. Write a program `recordinterceptdistoffset2.ch` using the member functions **driveDistanceNB()** and **driveDistance()** to reproduce Figure 11.14 shown in Exercise 4.

## 11.10 ‡ Copy Motions of a Controller Linkbot to a Controlled Linkbot

### 11.10.1 Repeat Actions Using a **while** Loop

Another way to control multiple Linkbots with a single program is by making one Linkbot copy the actions of another Linkbot which is being controlled manually. In this section we will learn how to accomplish this with a **while** loop to help control the flow of the program.

```
/* File: copycat.ch
Copy the motion of the 1st robot to the 2nd robot by moving joints of
the 1st robot manually */
#include <linkbot.h>
CLinkbotI robot1, robot2;
double angle1, angle3;

/* connect to robots and move to the zero position at the same time. */
robot1.connect();
robot2.connect();
robot1.resetToZeroNB();
robot2.resetToZeroNB();
robot1.moveWait();
robot2.moveWait();

/* Set colors for robots. Use the green robot to control the red one */
robot1.setLEDColor("green");
robot2.setLEDColor("red");

/* relax all joints of robot1 */
robot1.relaxJoints();

printf("You can now move joints of robot1 manually to control robot2\n");
while(1) {
    /* get the 1st robot joint angles */
    robot1.getJointAngles(angle1, NaN, angle3);
    /* drive the 2nd robot to the same position of the 1st robot */
    /* replace robot2.jumpToNB() by robot2.moveToByTrackPosNB() in BaroboLink 1.6.9 */
    /* robot2.jumpToNB(angle1, NaN, angle3); */
    robot2.moveToByTrackPosNB(angle1, NaN, angle3);
}
```

Program 11.16: Copying motions of a controller Linkbot to a controlled Linkbot using the function **moveToByTrackPosNB()**.

Program 11.16 copies the motions of one Linkbot-I to another Linkbot-I. In order to distinguish between Linkbots, the statements

## 11.10. ‡ Copy Motions of a Controller Linkbot to a Controlled Linkbot

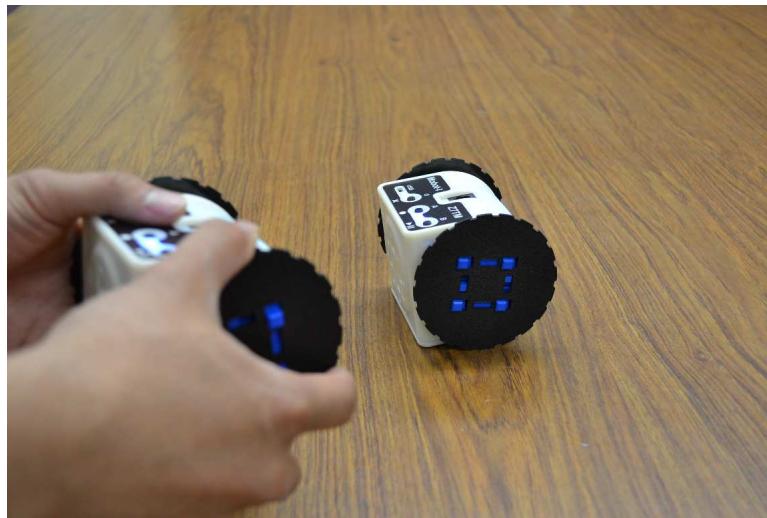


Figure 11.15: Copying the motion from one Linkbot to the other Linkbot.

```
robot1.setLEDColor("green");
robot2.setLEDColor("red");
```

sets the LED color of `robot1` to green and the LED color of `robot2` to red. The Linkbot-I with the green LED will control the Linkbot-I with the red LED. The next line

```
robot1.relaxJoints();
```

relaxes joints 1 and 3 of `robot1`. This allows the user to turn each joint freely. Finally, the lines

```
while(1) {
    /* get the 1st robot joint angles */
    robot1.getJointAngles(angle1, NaN, angle3);
    /* drive the 2nd robot to the same position of the 1st robot */
    robot2.moveToByTrackPosNB(angle1, NaN, angle3);
}
```

copy the joint angles of the manually controlled Linkbot-I to the other Linkbot-I. The commands to copy motions are repeated with the help of a **while** loop. Recall from Section 10.3.2 that a **while** loop repeats a sequence of statements multiple times until the loop condition expression is no longer true. In Program 11.16 the loop condition is 1, so it is always true. The loop repeats until either the user presses the Stop button on the debug bar in ChIDE or until the user turns the robot off. Inside the **while** loop, the first line of code

```
robot1.getJointAngles(angle1, NaN, angle3);
```

gets the angle values for joints 1 and 3 from the manually controlled `robot1`. The second line

```
robot2.moveToByTrackPosNB(angle1, NaN, angle3);
```

moves joints 1 and 3 of `robot2` to the absolute joint angle positions copied from `robot1`. The **CLinkbotI** member function **moveToByTrackPosNB()** has the general syntax

```
robot.moveToByTrackPosNB(angle1, NaN, angle3);
```

where `angle1` and `angle3` are the joint angle values used to drive joints 1 and 3 to their absolute joint angle positions. The member function **moveToByTrackPosNB()** is used instead of **moveToNB()** in this case because the joint positions of `robot2` are being tracked instead of joint speeds.

## 11.10. ‡ Copy Motions of a Controller Linkbot to a Controlled Linkbot

The function **moveToByTrackPosNB()** is non-blocking, so it allows the loop to repeat immediately instead of waiting for `robot2` to complete its action. The blocking version of this function is **moveToByTrackPos()**. For the position control, instead of velocity control, use the member function **moveToByTrackPos()**.

When you run Program 11.16, you may open the Motion Control Panel of the BaroboLink to watch the joint angles of the controlled robot.

 Do Exercise 1, 2, 3, and 4, on page 208.

We can also use sensor data from a controller Linkbot-I to determine the motion of a second Linkbot-I. Program 11.17 shows an example using accelerometer data from one Linkbot to control the motions of another Linkbot. You do not need to attach wheels to the controller Linkbot in order to run this program. The controlled Linkbot, however, will need wheels attached.

```
/* File: accelcontrol.ch
The accelerometer value for the 1st robot in green color will determine
the motion for the 2nd robot in red color. */
#include <linkbot.h>

CLinkbotI robot1, robot2;
double x, y, z;
int motorPower, motorOffset;

/* Connect to robots */
robot1.connect();
robot2.connect();

/* Set colors for robots. Use the green robot to control the red one */
robot1.setLEDColor("green");
robot2.setLEDColor("red");

/* relax all joints of robot2 */
robot2.relaxJoints();

while(1) {
    /* Get the accelerometer values */
    robot1.getAccelerometerData(x, y, z);
    /* Calculate forward-backward */
    motorPower = 200 * y;
    motorOffset = 50 * x;
    /* replace robot2.setJointPower() by robot2.moveJointByPowerNB() in BaroboLink 1.6.9
    robot2.setJointPower(JOINT1, -motorPower - motorOffset);
    robot2.setJointPower(JOINT3, motorPower - motorOffset);
    */
    robot2.moveJointByPowerNB(JOINT1, -motorPower - motorOffset);
    robot2.moveJointByPowerNB(JOINT3, motorPower - motorOffset);
}
```

Program 11.17: Using the accelerometer of one Linkbot to determine the motion of a second Linkbot.

Program 11.17 uses the X and Y component values of the controller Linkbot's accelerometer to calculate the joint motor power of the controlled Linkbot. This program works the same way that TiltDrive mode works between two Linkbots connected using BumpConnect. The line

```
int motorPower, motorOffset;
```

## 11.10. ‡ Copy Motions of a Controller Linkbot to a Controlled Linkbot

declares the variables of type **int**, **motorPower** and **motorOffset**. The value for the variable **motorPower** will be calculated using the Y component of acceleration and **motorOffset** will be calculated using the X component of acceleration from **robot1**. The difference between **motorPower** and **motorOffset** will determine the power of each joint motor of **robot2**. As in Program 11.16, the LED of **robot1** is set to green and the LED of **robot2** is set to red. Then the line

```
robot2.relaxJoints();
```

relaxes joints 1 and 3 of **robot2**. Since the accelerometer data of **robot1** is being used as the controlling input instead of manual wheel motions, **relaxJoints()** does not need to be called on **robot1**. Then, as in Program 11.16, a **while** loop is used to set the motor power of **robot2** using the accelerometer data of **robot1**. Since the loop condition equals 1, this loop will keep repeating until the user turns off the Linkbots or presses the Stop button on the ChIDE debug panel. Inside the **while** loop, the line

```
robot1.getAccelerometerData(x, y, z);
```

retrieves the X, Y, and Z components of the acceleration of **robot1**. The next lines

```
motorPower = 200 * y;
motorOffset = 50 * x;
```

use **y** from the accelerometer data to calculate **motorPower** and **x** to calculate **motorOffset**. The final two lines

```
robot2.moveJointByPowerNB(JOINT1, -motorPower - motorOffset);
robot2.moveJointByPowerNB(JOINT3, motorPower - motorOffset);
```

move joints by setting the motor power of joints 1 and 3 of **robot2** using the calculated difference between **motorPower** and **motorOffset**. This is done for each joint using the **CLinkbotI** member function **moveJointByPowerNB()**. The general syntax of this function is as follows

```
robot.moveJointByPowerNB(id, power);
```

The argument **id** specifies the joint to set the power. For a Linkbot-I this argument can have the values **JOINT1** or **JOINT3**. The argument **power** indicates the power at which to set the specified joint. This argument can have any integer value from -100 to 100.

To give an example of how the motion of **robot1** affects the motion of **robot2**, tilt **robot1** so that joint 1 is facing the floor. In this position, the X component of acceleration will be close to 1, and **motorOffset** will equal 100. The Y component of acceleration will be close to zero, so **motorPower** will equal zero. According to Program 11.17 the power of both joints 1 and 3 of **robot2** will be set to -60. As a result **robot2** will left turn. As **robot1** is gradually tilted back into a position where both joints 1 and 3 are facing outward, **robot2** will turn left more slowly until it stops. At this point the X component of acceleration will be close to zero. In a similar manner, if **robot1** is tilted so that joint 3 is facing the floor, **robot2** will turn right. Tilting **robot1** so that the curved part of the Linkbot is facing up makes the Y component of acceleration almost equal to 1. This will make **motorPower** equal 500. The X component will be close to zero in this position, so **motorOffset** will equal zero. Since the argument **power** can be no more than 100 and no less than -100, then the power of joint 1 of **robot2** will be rounded up to -100 and the power of joint 3 will rounded down to 100. As a result **robot2** will move forward quickly. Tilting **robot1** forward gradually until the curved part of this Linkbot is facing forward will make **robot2** move forward more slowly until it stops. Similarly, tilting **robot1** so that the curved part is facing the floor will make **robot2** move backward quickly.

When you run Program 11.17, you may open the Motion Control Panel of the BaroboLink to watch the joint angles of the controlled robot or the Sensors Panel to view the x, y, and z components of the accelerometer of the controlling robot.

 Do Exercises 5, 6, and 7 on page 5.

## 11.10.2 Summary

1. Call the **CLinkbotI** member function

```
robot.relaxJoints();
```

to relax all joints of a Linkbot.

2. Call the non-blocking **CLinkbotI** member function

```
robot.moveToByTrackPosNB(angle1, NaN, angle3);
```

to rotate the joint positions of a Linkbot-I to their absolute joint angle positions. The blocking version of this function is **moveToByTrackPos()**.

3. Call the **CLinkbotI** member function

```
robot.moveJointByPowerNB(id, power);
```

to move a joint by setting the power for the joint motor of a Linkbot-I.

## 11.10.3 Terminology

**robot.setLEDColor()**, **robot.relaxJoints()**, **robot.moveToByTrackPos()**, **robot.moveToByTrackPosNB()**, **robot.moveJointByPowerNB()**.

## 11.10.4 Exercises

1. What is the difference between **moveToByTrackPos()** and **moveTo()**?
2. Run the program `copycat.ch` in Program 11.16 to move the controlled Linkbot. Open the Motion Control Panel of the BaroboLink to watch the joint angles of the controlled robot.
3. Two group of students, each run the program `copycat.ch` in Program 11.16 in their own computers collaboratively using two controlled Linkbots controlled by two controller Linkbots to accomplish a common task. For example, race to see which controlled Linkbot crosses the finish line first or crosses an obstacle course first.
4. Write a program `copycat2.ch`, based on the program `copycat.ch` in Program 11.16, to copy the motion of the controller Linkbot-I to three controlled Linkbot-Is.
5. Run the program `accelcontrol.ch` in Program 11.17 to move the controlled Linkbot. Open the Motion Control Panel of the BaroboLink to watch the joint angles of the controlled robot, then open the Sensors Panel to view the x, y, and z components of the accelerometer of the controlling robot.
6. Write a program `accelcolor.ch` to use the accelerometer data of one Linkbot-I to set the LED color of another Linkbot-I. First, sound the buzzer of the first Linkbot at 450 Hz and set its LED to green. Then use a **while** loop to do the following multiple times in succession: Get the X, Y, and Z components of the accelerometer data. Then calculate the R, G, and B values using these components. And then finally set the LED using these RGB values.

## 11.10. ‡ Copy Motions of a Controller Linkbot to a Controlled Linkbot

7. Write a program `accelcontrol2.ch` based on the program `accelcontrol.ch` in Program 11.17. This program will drive the Linkbot forward and backward at half the speed of the original program but turn the Linkbot left or right at least twice as fast as the original program. To do this, change the power and offset as follows:

```
motorPower = 100 * y;  
motorOffset = 100 * x;
```

---

---

## CHAPTER 12

---

# Writing Programs to Control One or Multiple Groups of Linkbots

In Chapter 6, we learned how to control a group of Linkbots with identical movements. In Chapter 11, we learned how to control multiple individual Linkbots in synchronous motions. In this chapter, we will learn how to control multiple groups of Linkbots in synchronous motions. Many of the non-blocking **CLinkbot** member functions from Chapter 11 have **CLinkbotIGroup** counterparts. With these functions, choreographed synchronized motions can be achieved simply using a few lines of code.

### 12.1 Copy Motions from One Linkbot to Multiple Linkbots with Identical Movements

In Section 11.10 we learned how to copy the motions of one Linkbot to another. In this section we will extend Program 11.16 to copy the motions of one Linkbot to a group of Linkbots. The following program allows the user to control two Linkbot-Is simultaneously using a single Linkbot-I as a controller.

```
/* File: copycatgrouptwo.ch
One robot controls two robots, either individually or connected.
robot1 is the controller
*/
#include <linkbot.h>
CLinkbotI robot1, robot2, robot3;
CLinkbotIGroup group;

/* angles from robot1 */
double angle1, angle3;

group.addRobot(robot2);
group.addRobot(robot3);
```

## 12.1. Copy Motions from One Linkbot to Multiple Linkbots with Identical Movements

```

/* connect to robots and move to the zero position at the same time. */
robot1.connect();
group.connect();
robot1.resetToZeroNB();
group.resetToZeroNB();

robot1.moveWait();
group.moveWait();

/* relax all joints of robot1 */
robot1.relaxJoints();

printf("You can now move joints of robot1 to control robot2 and 3\n");
while(1){
    /* get joint angles of robot1 */
    robot1.getJointAngles(angle1, NaN, angle3);

    /* move robots in the group by the angles from robot1 */
    group.jumpToNB(angle1, NaN, angle3);
    /* group.moveToByPIDNB(angle1, NaN, angle3); */
}

```

Program 12.1: Copying motions of a controller Linkbot to a group of two controlled Linkbots.

You can run Program 12.1 to copy the motion of a Linkbot to two Linkbots in a group simultaneously. The **CLinkbotGroup** class includes non-blocking member functions that are similar to those in class **CLinkbotI**. Examples seen in Program 12.1 include **resetToZero()**, **moveWait()**, and **moveToByTrackPosNB()**. The **CLinkbotGroup** versions of these member functions move all the Linkbot-Is in a group identically, instead of only a single Linkbot-I.

In Program 12.1 **robot2** and **robot3** are added to **group**. This group is used to copy the motions of **robot1** to **robot2** and **robot3** simultaneously. The line

```
group.resetToZeroNB();
```

is similar to the preceding statement **robot1.resetToZeroNB()**. The only difference is that multiple Linkbot-Is are reset to the zero position using only one line of code. This non-blocking function allows the next line of code to execute simultaneously. The next two lines

```
robot1.moveWait();
group.moveWait();
```

pause the program until the joints of all Linkbots are finished resetting to zero. The statement **group.moveWait()** is similar to the previous line of code. The only difference is that **group.moveWait()** pauses the program for multiple Linkbot-Is using only one line of code. Once the joints of **robot1** are set to neutral, the loop

```

while(1){
    /* get joint angles of robot1 */
    robot1.getJointAngles(angle1, NaN, angle3);

    /* move robots in the group by the angles from robot1 */
    group.moveToByTrackPosNB(angle1, NaN, angle3);
}
```

copies the joint motions from the controller Linkbot-I to the Linkbot-Is in **group**. This **while** loop is similar to the **while** loop in Program 11.16. The key difference is the line

```
group.moveToByTrackPosNB(angle1, NaN, angle3);
```

## 12.2. Control Multiple Groups of Linkbots

which drives the joints of all the Linkbot-Is in `group` to the absolute joint angle position copied from `robot1`. Thus `robot2` and `robot3` will copy `robot1` in identical motions. Since **`moveToByTrackPosNB()`** is non-blocking, the loop will start to repeat before `robot2` and `robot3` have completed their motions.

 Do Exercises 1 and 2 on page 212.

### 12.1.1 Summary

1. Call the non-blocking **`CLinkbotIGroup`** member function

```
group.resetToZeroNB();
```

to reset joints 1 and 3 of all Linkbot-Is in a group to the zero position. The next line of code will begin executing before the function **`resetToZeroNB()`** has finished.

2. Call the non-blocking **`CLinkbotIGroup`** member function

```
group.moveWait();
```

to pause the program until all Linkbot-Is in the group have finished their motions.

3. Call the non-blocking **`CLinkbotIGroup`** member function

```
group.moveToByTrackPosNB(angle1, NaN, angle3);
```

to rotate the joint positions of all Linkbot-Is in a group to their absolute joint angle positions by tracking their positions. The next line of code will begin executing before the function **`moveToByTrackPosNB()`** has finished.

### 12.1.2 Terminology

`group.resetToZeroNB()`, `group.moveWait()`, `group.moveToByTrackPosNB()`.

### 12.1.3 Exercises

1. Run the program `copycatgrouptwo.ch` in Program 12.1 to copy the motion of a controller Linkbot to two controlled Linkbots.
2. Write a program `copycatgroupthree.ch`, based on the program `copycatgrouptwo.ch` in Program 12.1, to copy the motion of the controller Linkbot to three controlled Linkbots.

## 12.2 Control Multiple Groups of Linkbots

It is also possible for a single Linkbot-I to belong to multiple groups. Any command given to a group where a Linkbot is a part of that group will result in that Linkbot moving. Using multiple groups can help synchronize Linkbots in more complex patterns of movements.

## 12.2. Control Multiple Groups of Linkbots



Figure 12.1: Controlling multiple Linkbot groups.

## 12.2. Control Multiple Groups of Linkbots

```

/* File: groups.ch
   Control multiple robot groups simultaneously using the CLinkbotGroup class */
#include <linkbot.h>
CLinkbotI robot1, robot2, robot3, robot4;
CLinkbotIGroup groupA, groupB, groupC, groupD;
double radius = 1.75;           // radius of 1.75 inches
double trackwidth = 3.69; // the track width, the distance between two wheels

/* connect to the robots listed in the configuration file. */
robot1.connect();
robot2.connect();
robot3.connect();
robot4.connect();

/* add the robots to groups. The groups are organized as such:
   Group A: 1, 2, 3, 4
   Group B: 1, 2
   Group C: 3, 4
   Group D: 1, 2, 3 */
/* Group A */
groupA.addRobot(robot1);
groupA.addRobot(robot2);
groupA.addRobot(robot3);
groupA.addRobot(robot4);
/* Group B */
groupB.addRobot(robot1);
groupB.addRobot(robot2);
/* Group C */
groupC.addRobot(robot3);
groupC.addRobot(robot4);
/* Group D */
groupD.addRobot(robot1);
groupD.addRobot(robot2);
groupD.addRobot(robot3);

groupA.resetToZero();

/* make group B roll forward and group C roll backward at the same time */
groupB.driveForwardNB(360);
groupC.driveBackwardNB(360);
groupB.moveWait();
groupC.moveWait();

/* make all robots roll forward */
groupA.driveForward(360);

/* make robots 1 and 2 (Group B) turn left, and robots 3 and 4 (Group C) turn right. */
groupB.turnLeftNB(90, radius, trackwidth);
groupC.turnRightNB(90, radius, trackwidth);
groupB.moveWait();
groupC.moveWait();

/* make robot 4 roll forward
   while three robots in group D drive backward. */
groupD.driveBackwardNB(360);
robot4.driveForwardNB(360);
groupD.moveWait();
robot4.moveWait();

```

Program 12.2: A program with multiple groups.

## 12.2. Control Multiple Groups of Linkbots

Program 12.2 coordinates four Linkbot-Is using four different groups to perform independent, synchronous motions. All four Linkbot-Is are added to groupA using **addRobot()**. Then robot1 and robot2 are added to groupB. Similarly, robot3 and robot4 are added to groupC. Finally robot1, robot2, and robot3 are added to groupD. Then the line

```
groupA.resetToZero();
```

resets all Linkbot-Is to the zero position. Since all four Linkbot-Is are in groupA, there is no need to call **resetToZero()** on any of the other groups. The next line

```
groupB.driveForwardNB(360);
```

drives robot1 and robot2 forward 360 by degrees at the same time using the **CLinkbotIGroup** member function **driveForwardNB()**. The general syntax of this function is

```
group.driveForwardNB(angle);
```

where the argument **angle** specifies the amount to roll the wheels forward relative to their current positions. Since this function is non-blocking, the next line of code starts executing immediately. The next line

```
groupC.driveBackwardNB(360);
```

drives robot3 and robot4 backward 360 by degrees at the same time that robot1 and robot2 roll forward. The **CLinkbotIGroup** member function **driveBackwardNB()** has the following syntax

```
group.driveBackwardNB(angle);
```

where **angle** specifies the amount to roll the wheels relative to their current positions. Since both **driveForwardNB()** and **driveBackwardNB()** are non-blocking, the next two lines

```
groupB.moveWait();
groupC.moveWait();
```

are required to pause the program until groupB and groupC are done with their movements. Then the following line

```
groupA.driveForward(360);
```

drives all four Linkbot-Is forward by 360 degrees. The blocking version of the function is used in this case, since all four Linkbots have the same motion. The next line

```
groupB.turnLeftNB(90, radius, trackwidth);
```

causes robot1 and robot2 to turn left by 90 degrees at the same time. The **CLinkbotIGroup** member function **turnLeftNB()** has the following general syntax

```
group.turnLeftNB(angle, radius, trackwidth);
```

The argument **angle** specifies the amount to turn left. The argument **radius** specifies the radius of the two wheels. The argument **trackwidth** specifies the distance between the two wheels. The units must be the same for **radius** and **trackwidth**. Since **turnLeftNB()** is non-blocking, the next line of code

```
groupC.turnRightNB(90, radius, trackwidth);
```

will execute synchronously. Thus robot3 and robot4 will turn right by 90 degrees at the same time that robot1 and robot2 are turning left. The general syntax of the member function **turnRightNB()** is

```
group.turnRightNB(angle, radius, trackwidth);
```

## 12.2. Control Multiple Groups of Linkbots

The argument `angle` specifies the amount to turn right. The argument `radius` specifies the radius of the two wheels. The argument `trackwidth` specifies the distance between the two wheels. Since `turnRightNB()` is a non-blocking function, then `moveWait()` needs to be called on `groupB` and `groupC` to pause the program. Once both groups have finished their motions, the line

```
groupD.driveBackwardNB(360);
```

drives `robot1`, `robot2`, and `robot3` backward by 360 degrees at the same time. The following line

```
robot4.driveForwardNB(360);
```

drives `robot4` forward by 360 degrees at the same time the Linkbot-Is in `groupD` are moving forward. Note that the member function `driveForwardNB()` is being used on a single Linkbot-I instead of a group. The member functions `driveBackwardNB()`, `turnLeftNB()`, and `turnRightNB()` also have counterparts in the **CLinkbotI** class. Finally, the lines

```
groupD.moveWait();
robot4.moveWait();
```

pause the program until `groupD` and `robot4` finish their motions.

 Do Exercises 1 2 on page 217.

### 12.2.1 Summary

1. Call the non-blocking **CLinkbotI** member function

```
robot.driveForwardNB(angle);
```

to drive a single Linkbot-I forward by the specified angle relative to its current position. The next line of code begins execution before this motion has finished.

2. Call the non-blocking **CLinkbotIGroup** member function

```
group.driveForwardNB(angle);
```

to drive all Linkbot-Is in a group forward by the specified angle relative to its current position. The next line of code begins execution before this motion has finished.

3. Call the non-blocking **CLinkbotI** member function

```
robot.driveBackwardNB(angle);
```

to drive a single Linkbot-I backward by the specified angle relative to its current position. The next line of code begins execution before this motion has finished.

4. Call the non-blocking **CLinkbotIGroup** member function

```
group.driveBackwardNB(angle);
```

to drive all Linkbot-Is in a group backward by the specified angle relative to its current position. The next line of code begins execution before this motion has finished.

5. Call the non-blocking **CLinkbotI** member function

## 12.2. Control Multiple Groups of Linkbots

```
robot.turnLeftNB(angle, radius, trackwidth);
```

to turn a single Linkbot-I left by the specified angle. The next line of code begins execution before this motion has finished.

6. Call the non-blocking **CLinkbotIGroup** member function

```
group.turnLeftNB(angle, radius, trackwidth);
```

to turn all Linkbot-Is in a group left by the specified angle. The next line of code begins execution before this motion has finished.

7. Call the non-blocking **CLinkbotI** member function

```
robot.turnRightNB(angle, radius, trackwidth);
```

to turn a single Linkbot-I right by the specified angle. The next line of code begins execution before this motion has finished.

8. Call the non-blocking **CLinkbotIGroup** member function

```
group.turnRightNB(angle, radius, trackwidth);
```

to turn all Linkbot-Is in a group right by the specified angle. The next line of code begins execution before this motion has finished.

### 12.2.2 Terminology

**robot.driveForwardNB()**, **robot.driveBackwardNB()**, **robot.turnLeftNB()**, **robot.turnRightNB()**,  
**group.driveForwardNB()**, **group.driveBackwardNB()**, **group.turnLeftNB()**, **group.turnRightNB()**,  
multiple groups.

### 12.2.3 Exercises

1. Run the program `groups.ch` in Program 12.2 to control multiple Linkbot groups.
2. Based on the program `groups.ch` in Program 12.2, write a program `groups2.ch` to control four Linkbots. The program `groups2.ch` has four Linkbot groups of A, B, C, and D, similar to groups in Program 12.2. These groups will complete the following motions in order: First, Group A rolls forward for two full rotations of 720 degrees, then Group B turns left for 90 degrees, afterwards Group C turns right for 180 degrees, next Group D rolls forward for 360 degrees, and finally Linkbot 4 rolls backward for 360 degrees.

---

---

## CHAPTER 13

---

# Controlling Multiple Connected Linkbots

In Chapters 11 and 12, we learned how to control multiple individual Linkbots and multiple groups of Linkbots in synchronous motions, respectively. In this chapter, we will learn how to control connected Linkbots as well as groups of connected Linkbots in synchronous motions.

### 13.1 Control Multiple Connected Linkbots

In this section, we will learn how to write various programs for controlling multiple connected Linkbot-Is. Program 13.1 controls two Linkbot-Is connected in the four-wheel drive configuration shown in Figure 13.1. To assemble this configuration, connect two simple connectors to opposite sides of a cubic connector. Then attach joint 2, which is the non-moving joint, of the two Linkbot-Is to the simple connectors on the cubic connector. Be sure to attach wheels to joints 1 and 3 of both Linkbot-Is.

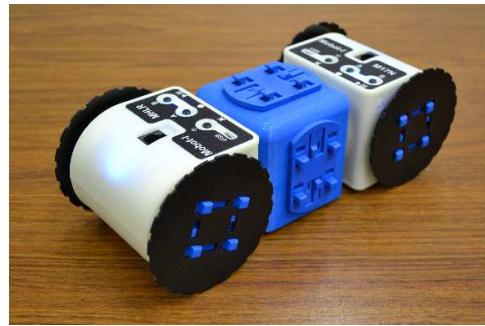


Figure 13.1: A four-wheel drive configured with two Linkbot-Is.

## 13.1. Control Multiple Connected Linkbots

```

/* File name: fourwheeldrive.ch
 * Four wheel drive configuration with two Linkbot-Is
 *      Top view
 *
 *      |----|
 *      |____| <- robot1
 *      |--|
 *      |__| <- cubic connector
 *      |----|
 *      |____| <- robot2
 *
 * Note: attach wheels for two Linkbot-I's */
#include <linkbot.h>

CLinkbotI robot1, robot2;

robot1.connect();
robot2.connect();

robot1.resetToZero();
robot2.resetToZero();

/* drive forward */
robot1.driveForwardNB(360);
robot2.driveBackwardNB(360);
robot1.moveWait();
robot2.moveWait();

/* drive backward */
robot1.driveBackwardNB(360);
robot2.driveForwardNB(360);
robot1.moveWait();
robot2.moveWait();

```

Program 13.1: Controlling two Linkbot-Is as a four-wheel drive vehicle.

Program 13.1 moves the four-wheel drive forward by 360 degrees, then backward by 360 degrees. The lines

```

robot1.driveForwardNB(360);
robot2.driveBackwardNB(360);

```

use non-blocking functions to drive `robot1` forward by 360 degrees and `robot2` backward by 360 degrees simultaneously. The simultaneous motions of `robot1` and `robot2` result in the four-wheel drive moving forward. The program pauses until both `robot1` and `robot2` have finished their motions. Then the lines

```

robot1.driveBackwardNB(360);
robot2.driveForwardNB(360);

```

use non-blocking functions to drive `robot1` backward by 360 degrees and `robot2` forward by 360 degrees simultaneously. The simultaneous motions of both Linkbot-Is result in the four-wheel drive moving backward.

 Do Exercise 1, on page 226.

Other considerations may arise when dealing with multiple-configuration designs. To accomplish certain motions, it may be necessary to perform motions in steps, with delays and pauses for motions to finish, before doing the next motion. The next program demonstrates how to address this consideration, controlling four Linkbot-Is in lifting and lowering motions as shown in Figure 13.2.

## 13.1. Control Multiple Connected Linkbots

To assemble the configuration in Figure 13.2, connect `robot1` and `robot2` with a bridge connector at joint 1 of both Linkbot-Is. Then connect `robot1` and `robot2` with another bridge connector at joint 3 of both Linkbot-Is. `robot3` and `robot4` will be connected in the same way as `robot1` and `robot2`. Then connect `robot2` and `robot3` with a simple connector at joint 2 of both Linkbot-Is.

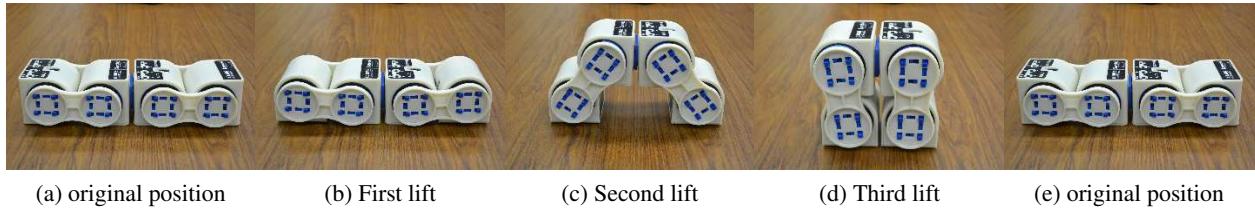


Figure 13.2: Lifting and unlifting motions with four connected modules.

## 13.1. Control Multiple Connected Linkbots

```

/* File: lift.ch
 * Lift four connected Linkbot-Is
 *          Top View
 *
 *      -----
 *      +---+ +---+ +---+ +---+
 *      | 1| | 2| | | 3| | 4|
 *      +---+ +---+ +---+ +---+
 *      -----
 *          ^      ^
 *          |      |
 *      Bridge |__ Simple
 *      Connector   Connector
 * The joint 1's of both robot 1 and robot 2 are connected with the bridge connector
 * The joint 3's of both robot 1 and robot 2 are connected with the bridge connector
 * The same configuration for connecting robot 3 and robot 4.
 * Also, robot 2 and robot 3 are connected by a simple connector at joint 2's
 * of both robots.
 */
#include <linkbot.h>
CLinkbotI robot1, robot2, robot3, robot4;

/* connect to the paired robot and set joints to zero */
robot1.connect();
robot2.connect();
robot3.connect();
robot4.connect();
robot1.resetToZeroNB();
robot2.resetToZeroNB();
robot3.resetToZeroNB();
robot4.resetToZero();

/* first lift */
robot1.moveToNB(90, NaN, -90);
robot4.moveTo(-90, NaN, 90);
robot1.delaySeconds(1);

/* second lift */
robot1.moveToNB(45, NaN, -45);
robot4.moveToNB(-45, NaN, 45);
robot2.moveToNB(-45, NaN, 45);
robot3.moveTo(45, NaN, -45);
robot1.delaySeconds(1);

/* third lift */
robot1.moveToNB(0, NaN, 0);
robot4.moveToNB(0, NaN, 0);
robot2.moveToNB(-90, NaN, 90);
robot3.moveTo(90, NaN, -90);
robot1.delaySeconds(1);

/* unlift */
robot2.moveToNB(0, NaN, 0);
robot3.moveTo(0, NaN, 0);

```

Program 13.2: Lifting for four connected Linkbot-Is.

Program 13.2 controls four connected Linkbot-Is in lifting and unlifting motions. The lines

### 13.1. Control Multiple Connected Linkbots

```
robot1.resetToZeroNB();
robot2.resetToZeroNB();
robot3.resetToZeroNB();
robot4.resetToZero();
```

resets joints 1 and 3 of all four Linkbot-Is simultaneously. Notice that the blocking version of the member function **resetToZero()** is used to reset `robot4`. This eliminates the need to call **moveWait()** on the four Linkbot-Is, since the next line of code will not begin executing until `robot4` has finished resetting to the zero position. Using a blocking version of a motion function for the last robot in a configuration can sometimes help reduce the size of the program. The next lines

```
robot1.moveToNB(90, NaN, -90);
robot4.moveTo(-90, NaN, 90);
```

perform the first stage of the lift. The feet of this configuration, `robot1` and `robot4`, rotate simultaneously to absolute joint angle positions of 90 degrees and  $-90$  degrees respectively. This puts the feet of the configuration in the correct position for the second stage of the lift. Since the blocking version of the member function **moveTo()** is used on `robot4`, there is no need to use **moveWait()** to pause the program. However, the next line

```
robot1.delaySeconds(1);
```

inserts a one-second pause after the first stage of the lift to help differentiate between the lift stages. Pausing between stages gives more stability to the motions of this particular configuration. The following lines

```
robot1.moveToNB(45, NaN, -45);
robot4.moveToNB(-45, NaN, 45);
robot2.moveToNB(-45, NaN, 45);
robot3.moveTo(45, NaN, -45);
robot1.delaySeconds(1);
```

perform the second stage of the lift. The feet of the configuration, `robot1` and `robot4`, rotate simultaneously to absolute joint angle positions of 45 degrees and  $-45$  degrees respectively. At the same time, `robot2` and `robot3` also rotate to absolute joint angle positions of  $-45$  degrees and 45 degrees respectively. The simultaneous motions of the four Linkbot-Is help lift `robot2` and `robot3` up off the ground. The program is then delayed for another second, to help stabilize the connected Linkbot-Is in this position. The next lines

```
robot1.moveToNB(0, NaN, 0);
robot4.moveToNB(0, NaN, 0);
robot2.moveToNB(-90, NaN, 90);
robot3.moveTo(90, NaN, -90);
robot1.delaySeconds(1);
```

perform the third stage of the lift. The feet of the configuration, `robot1` and `robot4`, rotate simultaneously to absolute joint angle positions of 0 degree. Meanwhile `robot2` and `robot3` also rotate to absolute joint angle positions of  $-90$  degrees and 90 degrees respectively. After the simultaneous motions of the four Linkbot-Is have completed, the configuration will be standing with its legs completely upright, feet touching each other. Another one second delay helps stabilize the configuration in this position. Then the final lines

```
robot2.moveToNB(0, NaN, 0);
robot3.moveTo(0, NaN, 0);
```

lower all four Linkbot-Is back down to their original positions. Since `robot1` and `robot4` already have their joints in the zero position after stage three of the lift, they do not need to be moved during the lowering stage. So only the joints of `robot2` and `robot3` need to be moved back to the zero position in order to lower the configuration back down to the floor.

 Do Exercise 2 on page 227.

### 13.1. Control Multiple Connected Linkbots

Program 13.3 moves five connected Linkbot-Is in a snake configuration. To assemble the snake configuration, attach joints 1 and 3 of `robot5` and `robot4` with bridge connectors. Be sure that joint 3 of both Linkbot-Is are connected with the same bridge connector. Connect `robot3` and `robot2` in the same way as `robot5` and `robot4`. Attach the upper part of the claw to joint 1 of `robot1` and the lower part to joint 3. This will be the head of the snake. Connect `robot3` and `robot4` with a simple connector at joint 2 of both Linkbot-Is to form the body of the snake. Make sure that all four Linkbot-Is in the body of the snake are connected so that joint 3 of each Linkbot is on the same side. Connect the head of the snake to the body with a simple connector at joint 2 of `robot1` and `robot2`. The head of the snake should have joint 3 on the same side as all the Linkbots in the body of the snake. Finally, connect a caster to joint 2 of `robot5` to give the snake a tail. Wrap rubber bands around the tail to give the snake the right amount of friction.

## 13.1. Control Multiple Connected Linkbots

The video for the snake motion can be viewed in a video file SnakeMotin.mp4 available at [c-stem.ucdavis.edu](http://c-stem.ucdavis.edu).

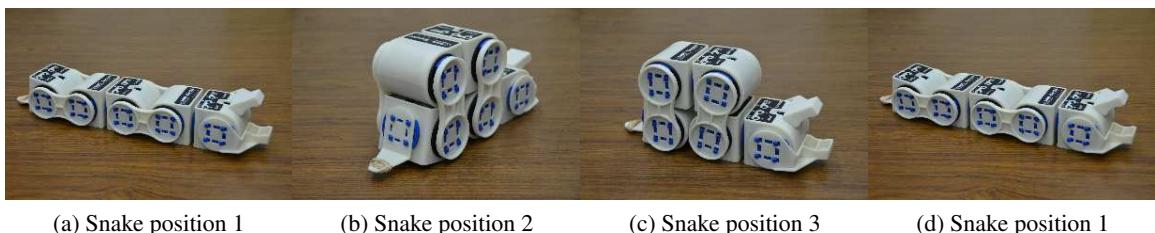


Figure 13.3: The snake motion with five Linkbot-Is.



Figure 13.4: The configuration for a snake with five Linkbot-Is. Joint 3 for all Linkbot-Is are on the same side.

```
/*
 * File: snake.ch
 * This program uses 5 Linkbot-Is for snake motion.
 * The linkbots are connected by bridges and simple connectors.
 * The robot1 has a claw attached as a mouth. The robot5 has a caster on
 * the back as a tail. The rubber-bands on the tail provide the needed friction.
 *
 * Initial configuration: Joint 3 for all Linkbot-Is are on the same side
 * as shown in snake.jpg.
 *
 *          Top View
 *
 *      -----
 *      +---+ +---+ +---+ +---+ +---+
 *      _| | 5| | 4| | 3| | 2| | 1| <- Claw
 *      +---+ +---+ +---+ +---+ +---+
 *      ^ ----- -----
 *      |     ^           ^
 * Caster   |           |
 *      Bridge       Simple
 *      Connector    Connector
 */
#include <clinkbot.h>
CLinkbotI robot1, robot2, robot3, robot4, robot5;

robot1.connect();
robot2.connect();
robot3.connect();
```

## 13.1. Control Multiple Connected Linkbots

```

robot4.connect();
robot5.connect();

robot1.resetToZeroNB();
robot2.resetToZeroNB();
robot3.resetToZeroNB();
robot4.resetToZeroNB();
robot5.resetToZeroNB();
robot1.moveWait();
robot2.moveWait();
robot3.moveWait();
robot4.moveWait();
robot5.moveWait();

/* Lift the tail up */
robot5.moveTo(-30, NaN, 30);

/* Move the body of the snake together */
robot1.moveToNB(-10, NaN, -30);
robot2.moveToNB(95, NaN, -95);
robot3.moveToNB(95, NaN, -95);
robot4.moveToNB(-95, NaN, 95);
robot5.moveToNB(-110, NaN, 110);
robot1.moveWait();
robot2.moveWait();
robot3.moveWait();
robot4.moveWait();
robot5.moveWait();

/* Set the tail down */
robot3.moveToNB(85, NaN, -85);
robot4.moveToNB(-100, NaN, 100);
robot5.moveToNB(-85, NaN, 85);
robot3.moveWait();
robot4.moveWait();
robot5.moveWait();

/* Set the body flat to moves it forward */
robot1.resetToZeroNB();
robot2.resetToZeroNB();
robot3.resetToZeroNB();
robot4.resetToZeroNB();
robot5.resetToZeroNB();
robot1.moveWait();
robot2.moveWait();
robot3.moveWait();
robot4.moveWait();
robot5.moveWait();

```

Program 13.3: The Snake motion with five connected Linkbot-Is.

Program 13.3 moves five connected Linkbot-Is in the motion of a snake. The line

```
robot5.moveTo(-30, NaN, 30);
```

lift up the tail of the snake by rotating `robot5` to an absolute joint angle position of 30 degrees. The next lines

```
/* Move the body of the snake together */
robot1.moveToNB(-10, NaN, -30);
```

### 13.1. Control Multiple Connected Linkbots

```
robot2.moveToNB(95, NaN, -95);
robot3.moveToNB(95, NaN, -95);
robot4.moveToNB(-95, NaN, 95);
robot5.moveToNB(-110, NaN, 110);
```

move all five Linkbot-Is synchronously to move the body to position 2 shown in Figure 13.4. The head opens its claw by rotating joints 1 and 3 of `robot1` by  $-10$  degrees and  $-30$  degrees respectively. The front half of the body moves by rotating `robot2` and `robot3` to an absolute joint angle position of  $95$  degrees. The back half of the body moves by rotating `robot4` and `robot5` to absolute joint angle positions of  $-95$  and  $-110$  respectively. Then `moveWait()` is called on all Linkbots to pause the program until all parts of the snake have finished their motions. The next lines

```
robot3.moveToNB(85, NaN, -85);
robot4.moveToNB(-100, NaN, 100);
robot5.moveToNB(-85, NaN, 85);
```

set the tail back down by synchronously rotating the joints of `robot3`, `robot4`, and `robot5` to absolute joint angle positions of  $85$  degrees,  $-100$  degrees, and  $-85$  degrees respectively. The snake is now in position 3, shown in Figure 13.4. The joint rotations are small, but they help position the snake for the final movement back to position 1. The function `moveWait()` is called on all Linkbots to pause the program until all parts of the snake have finished their motions for this position. Finally, all five Linkbots are reset to zero simultaneously. This results in the snake moving its body forward into a flat position. The function `moveWait()` is called on all Linkbot-Is one final time, to pause the program until the final motion is finished.

 Do Exercises 3 and 4 on page 227.

#### 13.1.1 Summary

1. Perform motions in steps, using either the member function `delaySeconds()` or the member function `moveWait()` to pause the program between each step.
2. Use the blocking version of a `CLinkbotI` member function for the last Linkbot-I in a configuration, for each step in a series of motions. This can reduce the program size when controlling multiple connected Linkbots.

#### 13.1.2 Terminology

connected Linkbots-Is, movement in steps, delay between steps.

#### 13.1.3 Exercises

1. Run the program `fourwheeldrive.ch` in Program 13.1 with two Linkbot-Is connected as shown in Figure 13.1. Modify the program `fourwheeldrive.ch` as the program `fourwheeldrive2.ch` by adding the following statements for turning Linkbots left and right.

```
/* turn left at the same time */
robot1.turnLeftNB(90, radius, trackwidth);
robot2.turnLeftNB(90, radius, trackwidth);
robot1.moveWait();
robot2.moveWait();
/* turn right for robot1, then robot2. */
robot1.turnRight(90, radius, trackwidth);
```

## 13.2. Program Linkbots with Pose Teaching

- ```
robot2.turnRight(90, radius, trackwidth);
```
2. Modify the program `lift.ch` in Program 13.2 as a program `lift2.ch` by changing 45 to 60 and -45 to -60. Run this new lifting program.
  3. Modify the program `snake.ch` in Program 13.3 as the program `snake2.ch` to move the snake forward continuously using a **while** loop.
  4. Write a program `snake3.ch` with five Linkbot-Is for the snake motion shown in Figure 13.3. The program shall begin with the following comments on how the snake robot is configured.

```
/* File: snake3.ch
 * This program uses 5 Linkbot-Is for snake motion.
 * The linkbots are connected by bridges and simple connectors.
 * The robot5 has a claw attached as a mouth. The robot1 has a caster on
 * the back as a tail. The rubber-bands on the tail provides the needed friction.
 *          Top View
 *
 *      -----
 *      +---+ +---+ +---+ +---+ +---+
 *      _| | 1| | 2| | | 3| | 4| | | 5|  <- Claw
 *      +---+ +---+ +---+ +---+ +---+
 *      ^   -----
 *      |       ^
 * Caster   |           |
 *      Bridge           Simple
 *      Connector        Connector
 */
```

## 13.2 Program Linkbots with Pose Teaching

Programming multiple Linkbots connected with different configurations may become quite complicated. This is especially true for a robot configured with many Linkbots. The programming with multiple Linkbots can be simplified with **PoseTeaching**, which is the process of training a robot to perform motions by physically moving the robot into desired positions. The motions can be repeated after the pose teaching. A Linkbot program can also be generated through the pose teaching so that the motions can be repeated by running the program later. The user may also modify the Linkbot program generated by the pose teaching for other applications.

To pose teach a robot or multiple robots, first connect all of the Linkbots that will be trained by pose teaching to a computer through the Connection Panel of the BaroboLink, as described in section 2.2. Then switch to the “Pose Teaching” tab to bring up the Pose Teaching Panel, as shown in Figure 13.5. When BaroboLink displays the Pose Teaching Panel, the function of the Linkbot’s on-board buttons will change to Pose Teaching mode. In Pose Teaching mode, the Linkbot buttons have the following functions:

- Button A: Record pose. This takes the position readings of all of the connected Linkbots and saves them as a single recorded pose.
- Button B: Play the current recorded motions in order, or stop if motions are currently being played.
- Buttons A and B together: Clear all of the recorded poses.

### 13.2. Program Linkbots with Pose Teaching

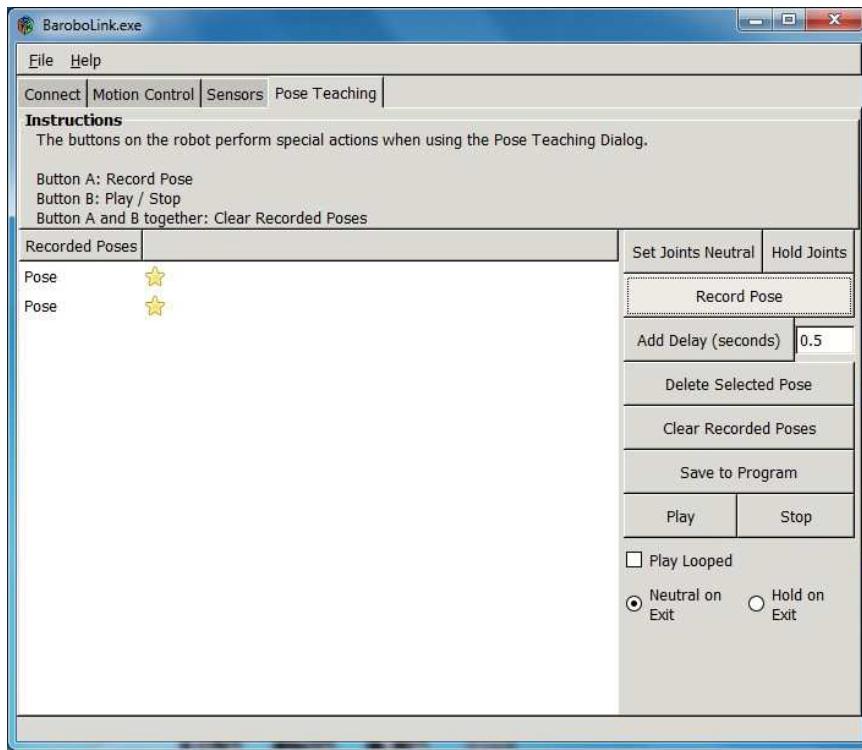


Figure 13.5: The Pose Teaching Panel.

Note that when the Linkbots are being used in this mode, all of the Linkbot buttons are connected together and do the same functions. In other words, if both Linkbot 1 and Linkbot 2 are connected to the computer, pressing the 'A' button on Linkbot 1 is identical to pressing the 'A' button on Linkbot 2; They will both result in a new recorded pose of both Linkbots being created in BaroboLink.

The joints of the Linkbots can be set to either "Neutral" mode or "Hold" mode by clicking on either the "Set Joints Neutral" button or the "Hold Joints" button, respectively. To pose teach the robot, click the "Set Joints Neutral" so that joints of Linkbots can be moved.

Each time a pose is recorded, an indicator for that pose will appear inside the Pose Teaching Panel under "Recorded Poses". As the poses are played, the pose icon changes for each pose to indicate the current pose being played. To delete a specific pose, select the indicator for that pose and then click the "Delete Selected Pose" button.

Delays may be added between poses by using the "Add Delay" button. The length of the delay (in seconds) should be entered in the text box next to the "Add Delay" button.

By default, when a program finishes its execution, all joints will be set to the state of neutral. This default behavior can be changed by clicking the "Hold" button in the entry for "Set Exit State" so that all Linkbots hold their final positions at the end of the program. This instructs the program to end with the following statement for each Linkbot.

```
robot.holdJointsAtExit();
```

The details about holding the joints at the exit have been described in section 8.4.

You can also save the recorded motions as a program by clicking on the "Save to Program" button. The generated program is a standard Linkbot program which can be executed in CHIDE.

As an example, you can connect to a Linkbot from BaroboLink. Then switch to the pose teaching mode in BaroboLink. Click the "Set Joints Neutral" button to start pose teaching. Next, pose teach the Linkbot by

### 13.2. Program Linkbots with Pose Teaching

moving the Linkbot joints and press the button 'A' for several different poses. Then, click the "Play" button to play back the recorded motions. Finally, click "Save to Program" and save the program as a new program `teachrobot.ch`. You can then open the program `teachrobot.ch` in ChIDE and run the program to repeat the motions again. The saved program can be modified for different applications. For example, you may modify the program to change the joint speed.

As another example, we wrote the program `lift.ch` in Program 13.2 to lift four connected Linkbot-Is as shown in Figure 13.2. We can pose teaching the robot as shown in Figure 13.2 to lift the Linkbot-Is in the sequence as presented in Program 13.2. Save the recorded motion as a program by clicking on the "Save to Program" button on the Pose Teaching Panel. A sample program is shown in Program 13.4. Compare Program 13.4 with Program 13.2. You may notice that the angles recorded in Program 13.4 may not be exactly as those in Program 13.2. However, the motion of these two programs will be very similar. The program generated with Pose Teaching uses the member function `moveWait()` to synchronize the motion of multiple modules.

## 13.2. Program Linkbots with Pose Teaching

```

/* Program generated by BaroboLink */
#include <linkbot.h>

CLinkbotI robot1;
CLinkbotI robot2;
CLinkbotI robot3;
CLinkbotI robot4;
robot1.connect();
robot2.connect();
robot3.connect();
robot4.connect();

/* Pose */
robot1.moveToNB(0.38, NaN, -2.28);
robot2.moveToNB(-4.93, NaN, 1.14);
robot3.moveToNB(1.52, NaN, -1.90);
robot4.moveToNB(-2.28, NaN, -0.76);
robot1.moveWait();
robot2.moveWait();
robot3.moveWait();
robot4.moveWait();

/* Pose */
robot1.moveToNB(-94.11, NaN, 86.27);
robot2.moveToNB(-4.93, NaN, -1.14);
robot3.moveToNB(-0.76, NaN, 0.76);
robot4.moveToNB(88.04, NaN, -85.76);
robot1.moveWait();
robot2.moveWait();
robot3.moveWait();
robot4.moveWait();

/* Pose */
robot1.moveToNB(-43.26, NaN, 38.46);
robot2.moveToNB(52.37, NaN, -54.64);
robot3.moveToNB(-45.92, NaN, 42.12);
robot4.moveToNB(39.84, NaN, -47.05);
robot1.moveWait();
robot2.moveWait();
robot3.moveWait();
robot4.moveWait();

/* Pose */
robot1.moveToNB(-3.79, NaN, -6.32);
robot2.moveToNB(92.59, NaN, -97.90);
robot3.moveToNB(-97.52, NaN, 98.66);
robot4.moveToNB(-7.59, NaN, 8.35);
robot1.moveWait();
robot2.moveWait();
robot3.moveWait();
robot4.moveWait();

```

Program 13.4: A program to lift four linked Linkbot-Is, generated by pose teaching.



Do Exercises 1, 2, and 3 on page 231.

## 13.2. Program Linkbots with Pose Teaching

**13.2.1 Summary**

1. Use Pose Teaching to make the programming of multiple Linkbots connected with different configurations easier.
2. To access the Pose Teaching Panel, click on the “Pose Teaching” tab of the Connection panel in BaroboLink.
3. Press button ‘A’ of a Linkbot to record the current poses of all Linkbots connected to BaroboLink.
4. Press button ‘B’ of a Linkbot to play all recorded motions in order, or to stop the motions if currently playing.
5. Press buttons ‘A’ and ‘B’ together to clear all recorded poses.
6. Click the “Set Joints Neutral” button on the Pose Teaching Panel to set the joints of all Linkbots to “Neutral” mode.
7. Click the “Hold Joints” button on the Pose Teaching Panel to set the joints of all Linkbots to “Hold” mode.
8. To delete a pose from the Pose Teaching Panel, select the indicator for that pose and then click the “Delete Selected Pose” button.
9. Click the “Add Delay” button on the Pose Teaching Panel to add delay between poses. Enter the length of the delay in seconds in the text box next to the “Add Delay” button before clicking it.
10. Select the “Hold on Exit” button on the Pose Teaching Panel to make all Linkbots hold their final positions.
11. Click the “Save to Program” button on the Pose Teaching Panel to save all recorded motions as a program.

**13.2.2 Terminology**

Pose Teaching, Pose Teaching Panel, Record Pose, Play button, Stop button, Clear Recorded Poses, “Set Joints Neutral” button, “Hold Joints” button, “Delete Selected Pose” button, “Add Delay” button, “Hold on Exit” button, “Save to Program” button, pose indicator.

**13.2.3 Exercises**

1. Pose teach a Linkbot to move two joints in multiple locations. Play the recorded motion. Save the motion in a program `teachpose.ch` and run the program in ChIDE.
2. Pose teach four linked Linkbot-Is as shown in Figure 13.2 on page 220 to lift itself up first, then flatten itself in its original position. Add a delay of 1.5 seconds between the first lift and second lift. Save the motion in a program `teachlift2.ch` and run the program in ChIDE.
3. Pose teach the snake motion shown in Figure 13.3 on page 224. Play the recorded motion. Save the motion in a program `teachsnake.ch` and run the program in ChIDE.

13.3.  Control Multiple Connected Linkbot-Ls

## 13.3 Control Multiple Connected Linkbot-Ls

In Section 13.1 we learned how to control multiple connected Linkbot-Is. In this section we will learn how to write programs to control multiple connected Linkbot-Ls. The following program demonstrates how to control two connected Linkbot-Ls to stand up and lay back down again. To assemble this configuration, attach a square faceplate with a SnapConnection to joint 2 of `robot1` and `robot2` or fasten a square faceplate using a Phillips-head screwdriver. When the connected Linkbot-Ls are eventually in the standing position, this faceplate will be the base on which they stand. Then connect joint 1 on each Linkbot-L using a bridge connector. Then place the connected Linkbot-Ls in position 1, shown in Figure 13.6.



(a) position 1                  (b) position 2                  (c) position 3                  (d) position 4                  (e) position 5

Figure 13.6: Standing and unstanding motions with two connected Linkbot-Ls and a faceplate.

13.3.  Control Multiple Connected Linkbot-Ls

```

/* File: stand.ch
Stand and unstand two linked Linkbot-Ls.
Joint 2 of robot1 is connected to a square faceplate, placed on the ground.
Joint 1 of two robots are connected by a bridge connector.

Top View in its initial configuration

robot1 robot2
|----| |----|
2|    | |    | 2
|----| |----|
           1-----1
           ^
           |
Bridge Connector

Front View in its standing position

      +---+
Joint1 ->|| |<- robot2
Bridge      |+++
connector ->|+++
           Joint1 ->|| |<- robot1
           +---+
           -----
           ^
           |
Joint 2 with
Square faceplate attached

*/
#include <linkbot.h>
CLinkbotL robot1, robot2;

/* connect to robots and move to the zero position at the same time. */
robot1.connect();
robot2.connect();
robot1.resetToZeroNB();
robot2.resetToZero();

/* stand */
robot1.moveTo(90, 0, NaN);
robot2.moveTo(-60, 0, NaN);
robot1.moveTo(90, 45, NaN);
robot1.moveTo(-5, 45, NaN);

/* rotate two face plates at the same time */
robot1.moveJointNB(JOINT2, 360);
robot2.moveJoint(JOINT2, -360);

/* unstand */
robot1.resetToZeroNB();
robot2.resetToZero();

robot1.moveTo(45, 0, NaN);
robot1.moveTo(0, 0, NaN);

```

Program 13.5: Controlling two Linkbot-Ls for standing and unstanding motions.

### 13.3. Control Multiple Connected Linkbot-Ls

Most of the **CLinkbotI** member functions are also available for the **CLinkbotL** class. The main difference is that the Linkbot-L uses joints 1 and 2 instead of joints 1 and 3. Recall, however, that only the Linkbot-I can be treated as a two-wheel vehicle. Therefore member functions such as **driveForward()**, **driveBackward()**, **turnLeft()**, **turnRight()**, as well as their non-blocking counterparts can only be used for the **CLinkbotI** class. In Program 13.5, the line

```
robot1.moveTo(90, 0, NaN);
```

moves joint 1 to the absolute joint angle position of 90 degrees using the **CLinkbotL** version of the member function **moveTo()**. Since we do not want joint 2 to move just yet, the second argument has a value of zero. Since joint 3 of a Linkbot-L does not move, the argument has the value **NaN**. At this point the Linkbot-Ls will be in position 2, as shown in Figure 13.6. The following line

```
robot2.moveTo(-60, 0, NaN);
```

moves joint 1 of **robot2** by  $-60$  degrees. We do not yet want to move joint 2 of **robot2** either, so the second argument is given a value of zero. The Linkbot-Ls will be in position 3, as shown in Figure 13.6. The next line

```
robot1.moveTo(90, 45, NaN);
```

will rotate the faceplate on joint 2 of **robot1** by 45 degrees while keeping joint 1 in its absolute joint angle position of 90 degrees. The connected Linkbot-Ls will now be in position 4, as shown in Figure 13.6. Then the line

```
robot1.moveTo(-5, 45, NaN);
```

keeps the faceplate on joint 2 of **robot1** in its absolute joint angle position of 45 degrees. At the same time joint 1 of **robot1** rotates to the absolute joint angle position of  $-5$  degrees. This will move **robot1** into a vertical position, holding **robot2** up in the air. The Linkbot-Ls are now in position 5, as shown in Figure 13.6. The next two lines

```
robot1.moveJointNB(JOINT2, 360);
robot2.moveJoint(JOINT2, -360);
```

rotates faceplates on joint 2 of both **robot1** and **robot2** simultaneously to the absolute joint angle positions of 360 degrees and  $-360$  degrees respectively. Since the **CLinkbotL** version of the member functions **moveJointNB()** and **moveJoint()** are used, the enumerated value **JOINT2** is the appropriate value for the first argument in each statement. To make the connected Linkbot-Ls lay back down, joints 1 and 2 of both Linkbots are reset to the zero position. The **CLinkbotL** member function **resetToZeroNB()** is used for **robot1** in this case to allow both Linkbot-Ls to reset simultaneously. Finally, the line

```
robot1.moveTo(45, 0, NaN);
```

will rotate joint 1 of **robot1** by 45 degrees, folding the connected Linkbot-Ls forward toward the ground. And the last line

```
robot1.moveTo(0, 0, NaN);
```

will lay the connected Linkbots back down into position 1.

 Do Exercises 1 and 2 on page 246.

Just as we can make two connected Linkbot-Ls stand up from a horizontal position, we can also make two connected Linkbot-Ls bow from a standing position. The configuration needed for Program 13.6 is the same one used for Program 13.5. Before running the program, however, the connected Linkbots should be placed in a standing position, with the square faceplate attached to joint 2 of **robot1** placed on the ground. The various positions for a bowing motion can be seen in Figure 13.7.

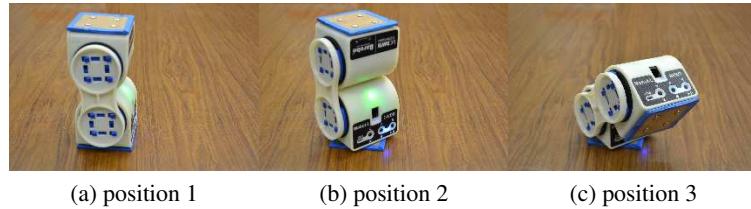
13.3.  Control Multiple Connected Linkbot-Ls

Figure 13.7: Bowing motion with two connected Linkbot-Ls and a faceplate.

```

/* File: bow.ch
Bow two linked Linkbot-Ls.
Joint 2 of robot1 is connected to a square faceplate, placed on the ground.
Joint 1 of two robots are connected by a bridge connector.

Top View in its initial configuration
    +--+
    Joint1 ->|| |<- robot2
    Bridge      |+++
connector ->|+++
    Joint1 ->|| |<- robot1
    +---+
    -----
    ^
    |
    Joint 2 with
    Square faceplate attached
*/
#include <linkbot.h>
CLinkbotL robot1, robot2;

/* connect to robots and move to the zero position at the same time. */
robot1.connect();
robot2.connect();
robot1.resetToZeroNB();
robot2.resetToZero();

/* bow */
robot1.moveTo(0, 45, NaN);
robot2.moveToNB(90, 0, NaN);
robot1.moveTo(-45, 45, NaN);

/* back to the original position */
robot1.resetToZeroNB();
robot2.resetToZero();

```

Program 13.6: Controlling two Linkbot-Ls for bowing motion.

The line

```
robot1.moveTo(0, 45, NaN);
```

will rotate the faceplate attached to joint 2 of `robot1` by 45 degrees. This will partially turn the standing Linkbots right, as shown in position 2 of Figure 13.7. The next line

```
robot2.moveToNB(90, 0, NaN);
```

### 13.3. Control Multiple Connected Linkbot-Ls

rotates joint 1 of `robot2` by 90 degrees. This will cause `robot2` to fold forward. Then the statement

```
robot1.moveTo(-45, 45, NaN);
```

holds the position of joint 2 of `robot1` in its absolute joint angle position of 45 degrees, while rotating joint 1 forward by 45 degrees. The connected Linkbot-Ls should now be in position 3 as shown in Figure 13.7. The final two lines of the program simultaneously reset joints 1 and 2 of both Linkbot-Ls to the zero positions. This will cause the bowing linkbots to turn and stand back up in the original position.

 Do Exercise 3 on page 246.

We can also make two connected Linkbot-Ls crawl like an inchworm. The configuration needed for Program 13.7 is the same as the one used for Program 13.6. Be sure, however, to lay the connected Linkbot-Ls flat as shown in Figure 13.8 before running Program 13.7.

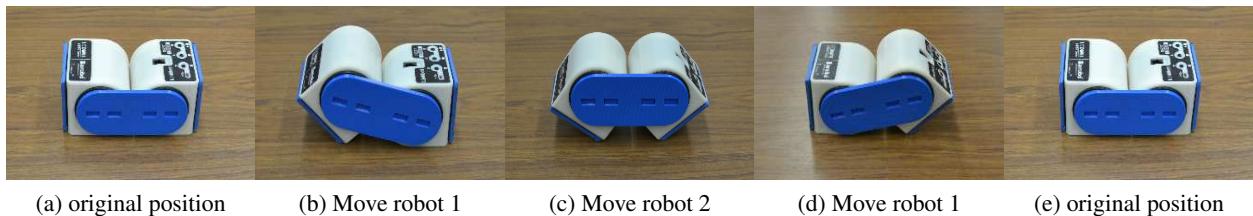


Figure 13.8: The positions for an inchworm moving left.

### 13.3. Control Multiple Connected Linkbot-Ls

```
/* File: inchworm.ch
 *
 *      Top View
 *
 *  robot1 robot2
 *  |---| |---|
 *  2|   | |   | 2
 *  |---| |---|
 *  1-----1
 *          ^
 *          |
 * Bridge Connector
 *
 * Joint 2 of each robot is connected with a square faceplate.
 * Joint 1 of two robots are connected by a bridge connector.
 */

#include <linkbot.h>

CLinkbotL robot1, robot2;

robot1.connect();
robot2.connect();
robot1.resetToZeroNB();
robot2.resetToZero();

/* inchworm left */
robot1.moveJointTo(JOINT1, -45);
robot2.moveJointTo(JOINT1, 45);
robot1.moveJointTo(JOINT1, 0);
robot2.moveJointTo(JOINT1, 0);

/* inchworm right */
robot2.moveJointTo(JOINT1, 45);
robot1.moveJointTo(JOINT1, -45);
robot2.moveJointTo(JOINT1, 0);
robot1.moveJointTo(JOINT1, 0);
```

Program 13.7: Controlling two connected Linkbot-Ls in an inchworm motion.

Program 13.7 first moves the inchworm left, as in Figure 13.8. Then it moves the inchworm right, in a manner similar to the movement left. The line

```
robot1.moveJointTo(JOINT1, -45);
```

rotates joint 1 of `robot1` by  $-45$  degrees. This begins the compression cycle of the worm movement. When this motion completes, the inchworm will be in the position shown in Figure 13.8 part (b). The next line

```
robot2.moveJointTo(JOINT1, 45);
```

moves joint 1 of `robot2` by  $45$  degrees. After this movement completes, the is now completely compressed as in Figure 13.8 part (c). The following lines

```
robot1.moveJointTo(JOINT1, 0);
robot2.moveJointTo(JOINT1, 0);
```

stretch the inchworm to the left back into a flat position. First, joint 1 of `robot1` will move back to the zero position. The inchworm is now in the position shown in Figure 13.8 part (d). Then joint 1 of `robot2`

### 13.3. Control Multiple Connected Linkbot-Ls

will move back to the zero position. The inchworm is now flat, as shown in Figure 13.8 part (e). Next, the inchworm will inch to the right. This movement will be a mirror image of movement left shown in Figure 13.8. The lines

```
robot2.moveJointTo(JOINT1, 45);
robot1.moveJointTo(JOINT1, -45);
```

compress the inchworm. This time joint 1 of `robot2` moves first, by 45 degrees, starting the compression cycle. Then `robot1` follows, moving its joint 1 by  $-45$  degrees to complete the compression. Finally, the lines

```
robot2.moveJointTo(JOINT1, 0);
robot1.moveJointTo(JOINT1, 0);
```

stretch the inchworm to the right into a flat position. First joint 1 of `robot2` moves back to the zero position, then joint 1 of `robot1` moves back into the zero position.

#### Do Exercise 4 on page 246.

Up until this point we have learned how to control multiple connected Linkbots of only one kind. But it is also possible to control configurations that include both Linkbot-Is and Linkbot-Ls. The following program, `explorer.ch`, controls a configuration consisting of four Linkbot-Is and one Linkbot-L. To assemble the explorer configuration, connect joints 1 and 3 of `robot3` and `robot4` with bridge connectors. This will be the arm of the explorer. Then connect joint 2 of `robot3` to the top of a cubic connector. The open end of the cubic connector should be on the bottom. Joint 1 of `robot1` should be connected to the left side of the cubic connector, and *a 4-inch diameter wheel* should be connected to joint 3 of this Linkbot-I. Connect joint 3 of `robot2` to the right side of the cubic connector, and attach *a 4-inch diameter wheel* to joint 1 of this Linkbot-I. `robot1` and `robot2` will be the wheels of the explorer. Then connect a claw to the Linkbot-L, with the top half of the claw attached to joint 1 and the bottom half attached to joint 3 (the non-moving joint). This will be the gripper of the explorer. Connect the gripper to the arm by connecting joint 2 of the gripper with joint 2 of `robot4` using a simple connector. Remember that joint 2 on the gripper is a moving joint, while joint 2 on `robot4` is a non-moving joint. Finally, place a caster on the front of the cubic connector in order to stabilize the explorer. Place a highlighter pen standing upright on the ground in front of the explorer. The explorer will pick up this pen when the program is run.

Before running Program 13.8, the explorer should be set in the initial position shown in Figure 13.9. In this starting position:

1. `robot3` has joint 1 positioned at  $-12$  degrees and joint 3 positioned at  $12$  degrees.
2. `robot4` has joint 1 positioned at  $-90$  degrees and joint 3 positioned at  $90$  degrees.
3. All other Linkbots have their joints initially set in the zero position.

Wheels with *4-inch diameter* are recommended to ensure that the explorer moves smoothly.

### 13.3. Control Multiple Connected Linkbot-Ls

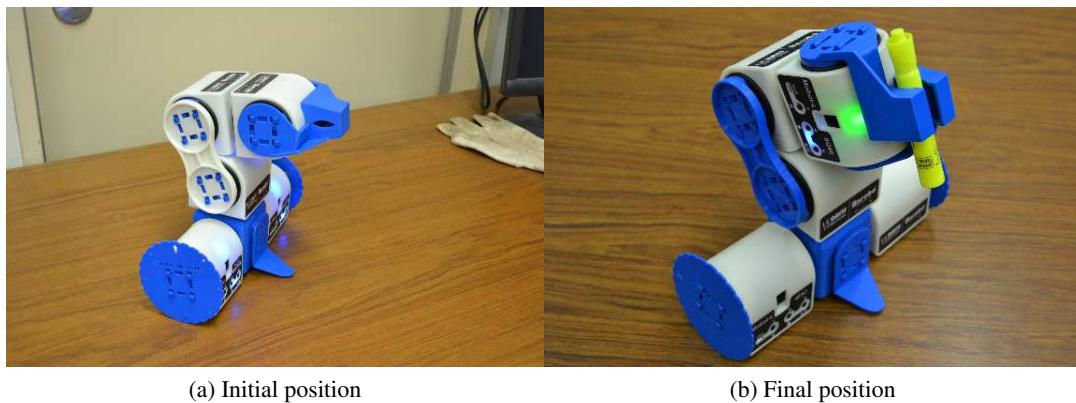


Figure 13.9: An explorer with four Linkbot-Is and one Linkbot-L picking up a highlighter pen.

```
/*
 * File: explorer.ch
 * An explorer using four Linkbot-Is and one Linkbot-L for a gripper to pick up
 * a highlighter pen.
 * 1) Diameters of two wheels are of 4" inches.
 * 2) Numbers 1, 2 and 3 indicate joints.
 * 3) 1 caster is attached at the front of the cubic connector.
 * 4) Before running the program explorer.ch, the explorer should be set
 *    in the initial position shown in explorer.jpg,
 *    In this starting position:
 *      a) robot3 has joint 1 positioned at -12 degrees and
 *         joint 3 positioned at 12 degrees.
 *      b) robot4 has joint 1 positioned at -90 degrees and joint 3 positioned
 *         at 90 degrees.
 *      c) All other robots have their joints initially set in the zero position.
 * 5) When mounting the gripper, make sure joint 1 is in zero position
 *    if the gripper is closed
 * 6) Front View in its initial configuration
 *          |--| gripper
 * gripper attached here -> |__|
 *          -- <- simple connector
 *          3|--|1 robot4
 *          ||__||
 * bridge connector -> |     | <- bridge connector
 *          ||--|||
 *          3|__|1 robot3
 *          1|--|----|--|3
 * robot2 -> |__|| |__| <- robot1
 *
 *          |
 *          cubic connector
 */
#include <linkbot.h>
CLinkbotI robot1, robot2, robot3, robot4;
CLinkbotL gripper;

robot1.connect();
robot2.connect();
robot3.connect();
robot4.connect();
```

### 13.3. Control Multiple Connected Linkbot-Ls

```

gripper.connect();

robot1.holdJoint(JOINT1);
robot2.holdJoint(JOINT3);

/* Initial position */
robot1.resetToZeroNB();
robot2.resetToZeroNB();
robot3.moveToNB(-12, NaN, 12);
robot4.moveToNB(-90, NaN, 90);
gripper.resetToZeroNB();
robot1.moveWait();
robot2.moveWait();
robot3.moveWait();
robot4.moveWait();
gripper.moveWait();

/* move forward */
robot1.moveNB(0, NaN, 360);
robot2.moveNB(-360, NaN, 0);
robot1.moveWait();
robot2.moveWait();

/* turn left */
robot1.moveNB(0, NaN, -235);
robot2.moveNB(-235, NaN, 0);
robot1.moveWait();
robot2.moveWait();

/* move forward */
robot1.moveNB(0, NaN, 360);
robot2.moveNB(-360, NaN, 0);
robot1.moveWait();
robot2.moveWait();

/* Open the gripper by 90 and joint2 to 90 */
gripper.openGripper(90);
gripper.moveJointTo(JOINT2, 90);

/* arm ready */
robot3.moveToNB(70, NaN, -70);
robot4.moveToNB(-10, NaN, 10);
robot3.moveWait();
robot4.moveWait();

/* Close the gripper to grab an object */
gripper.closeGripper();

/* lift the arm */
robot3.setJointSafetyAngle(50);
robot3.moveToNB(-12, NaN, 12);
robot4.moveToNB(-90, NaN, 90);
robot3.moveWait();
robot4.moveWait();

/* move backward */
robot1.moveNB(0, NaN, -360);
robot2.moveNB(360, NaN, 0);
robot1.moveWait();

```

### 13.3. Control Multiple Connected Linkbot-Ls

```

robot2.moveWait();

/* turn right */
robot1.moveNB(0, NaN, 235);
robot2.moveNB(235, NaN, 0);
robot1.moveWait();
robot2.moveWait();

/* move backward */
robot1.moveNB(0, NaN, -360);
robot2.moveNB(360, NaN, 0);
robot1.moveWait();
robot2.moveWait();

robot3.holdJointsAtExit(); // robot3 holds joints
gripper.holdJointsAtExit(); // gripper holds the object

```

Program 13.8: Controlling an explorer with four Linkbot-Is and one Linkbot-L.

You can hold a joint angle of a Linkbot by calling the function **holdJoint()**. The general syntax of this function is

```
robot.holdJoint(id);
```

The argument **id** specifies the joint that you wish to hold.

After all Linkbots have connected, the lines

```

robot1.holdJoint(JOINT1);
robot2.holdJoint(JOINT3);

```

hold the movement of joint 1 of **robot1** and joint 3 of **robot2**. These are the joints attaching the wheels to the cubic connector. Since we do not want these particular joints to move, they are held. Then the lines

```

robot1.resetToZeroNB();
robot2.resetToZeroNB();
robot3.moveToNB(-12, NaN, 12);
robot4.moveToNB(-90, NaN, 90);
gripper.resetToZeroNB();

```

make sure that all joints of all Linkbots are set in the desired positions for the initial configuration. **robot1**, **robot2**, and **gripper** are all reset to the zero position simultaneously. Since we want **robot3** and **robot4** to start in the initial position shown in Figure 13.9, the function **moveToNB()** is used instead of **resetToZeroNB()** for these two Linkbot-Is. The function **moveWait()** is called on all five Linkbots to pause the program until all joints are finished setting to the initial configuration. Then the lines

```

/* move forward */
robot1.moveNB(0, NaN, 360);
robot2.moveNB(-360, NaN, 0);
robot1.moveWait();
robot2.moveWait();

```

simultaneously move the wheels of the explorer forward by 360 degrees. Since the inner joints don't move, the arguments for these joints are assigned an angle value of zero. The function **moveWait()** is used on **robot1** and **robot2** to pause the program until the explorer has finished moving forward. Then the next statements

```

/* turn left */
robot1.moveNB(0, NaN, -235);
robot2.moveNB(-235, NaN, 0);
robot1.moveWait();
robot2.moveWait();

```

### 13.3. Control Multiple Connected Linkbot-Ls

cause the explorer to make a 90-degree left turn. Then, the explorer moves forward again.

The statements

```
/* Open the gripper by 90 and joint2 to 90 */
gripper.openGripper(90);
gripper.moveJointTo(JOINT2, 90);
```

open joint 1 mounted with a gripper by 90 degrees and joint 2 to 90 degrees. The syntax of the member function **openGripper()** is as follows.

```
robot.openGripper(angle);
```

The function opens joint 1 mounted with a gripper by an angle in degrees specified in its argument. When mounting the gripper using a Linkbot-L, make sure joint 1 is in zero position if the gripper is closed. When using a Linkbot-I as the gripper, joints 1 and 3 should be in zero positions if the gripper is closed.

The statements

```
/* arm ready */
robot3.moveToNB(70, NaN, -70);
robot4.moveToNB(-10, NaN, 10);
robot3.moveWait();
robot4.moveWait();
```

prepare the arm of the explorer to grab the highlighter pen. The joints of `robot4` rotate 10 degrees backward, while the joints of `robot3` rotate 70 degrees forward. The overall effect will be the arm bending forward toward the highlighter pen, while the gripper turns sideways and opens its claw around the pen. The member function **moveWait()** is called on `gripper`, `robot3`, and `robot4` to pause the program until all Linkbots have finished the current motion.

The statement

```
/* Close the gripper to grab an object */
gripper.closeGripper();
```

closes the claw of the gripper around the highlighter pen. The syntax of the member function **closeGripper()** is as follows.

```
robot.closeGripper();
```

The function closes the gripper.

The lines

```
/* lift the arm */
robot3.setJointSafetyAngle(50);
robot3.moveToNB(-12, NaN, 12);
robot4.moveToNB(-90, NaN, 90);
robot3.moveWait();
robot4.moveWait();
```

rotate joints 1 and 3 of `robot3` and `robot4` of the explorer arm back into the initial position. The program pauses until this motion completes.

The Linkbot is equipped with a safety feature to protect itself and its surrounding environment. When a motor deviates by a certain amount from its expected value, the Linkbot will shut off all power to the motor, in case it has hit an obstacle, or for any other reason. The amount of deviation required to trigger the safety protocol is the joint safety angle which can be set using the member function **setJointSafetyAngle()**. The general syntax of this function is

```
robot.setJointSafetyAngle(angle);
```

### 13.3. Control Multiple Connected Linkbot-Ls

The argument `angle` is the safety angle. The default safety angle is 10 degrees. Higher values indicate “less safe” behavior of the Linkbot because the Linkbot will not engage safety protocols until the joint has deviated by a greater amount. Since `robot3` will carry a heavy weight at this cantilever position, the safety angle is set to 50 degrees.

The lines

```
/* move backward */
robot1.moveNB(0, NaN, -360);
robot2.moveNB(360, NaN, 0);
robot1.moveWait();
robot2.moveWait();
```

move the wheels of the explorer backward by 360 degrees.

The lines

```
/* turn right */
robot1.moveNB(0, NaN, 235);
robot2.moveNB(235, NaN, 0);
robot1.moveWait();
robot2.moveWait();
```

turn the wheels of the explorer right by 90 degrees. The program pauses again until `robot1` and `robot2` complete this turn.

The explorer moves back again. The explorer should be in its original position, as in Figure 13.9, but now holding the highlighter pen in its claw. The program pauses one last time to allow this backward motion to finish.

Finally, the statements

```
robot3.holdJointsAtExit(); // robot3 holds joints
gripper.holdJointsAtExit(); // gripper holds the object
```

make sure the `robot3` holds all joints and the `gripper` holds the object even after the program finishes its execution.

Program 13.8 can also be executed in RoboSim as one of Preconfigured Linkbot Configurations in `explorer.ch`.

Do Exercises 5, 6, 7, 8, 9, and 10 on page 248.

Another way to control connected Linkbot-Ls is in the four-wheel omnidrive configuration. This configuration is shown in Figure 13.10. It uses four Linkbot-Ls, one for each wheel. To assemble this configuration, connect joint 2 of each Linkbot-L to the four corners of an H-connector. Then connect a wheel to joint 1 of each Linkbot-L. If you look at the omnidrive from the top, `robot4` will be on the back left corner, `robot2` will be on the back right corner, `robot3` will be on the front left corner, and `robot1` will be on the front right corner.

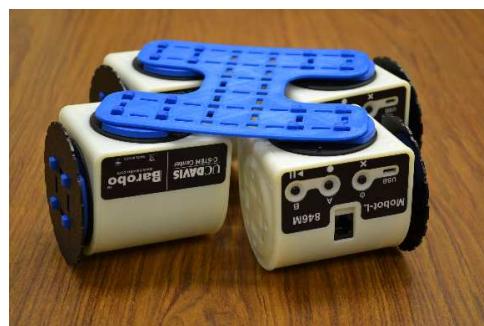


Figure 13.10: An omnidrive with four Linkbot-Ls.

### 13.3. Control Multiple Connected Linkbot-Ls

```
/* File: omnidrive.ch
 * This program uses 4 Linkbot-Ls to make a four-wheel omnidrive robot
 * where each wheel can turn.
 * H connector connects joint 2 of each Linkbot-L.
 * Wheels are attached to joint 1 of each Linkbot-L.
 *
 *      Top View
 *
 *      robot4      robot2
 *      |---|      |---|
 *      1| 2-----+--2 |1
 *      |---|      |---|
 *      |
 *      | <----- connector
 *      |---|      |---|
 *      1| 2-----+--2 |1
 *      |---|      |---|
 *      robot3      robot1
 *
 */
#include <linkbot.h>
CLinkbotL robot1, robot2, robot3, robot4;
double angle = 250;

robot1.connect();
robot2.connect();
robot3.connect();
robot4.connect();

robot1.resetToZeroNB();
robot2.resetToZeroNB();
robot3.resetToZeroNB();
robot4.resetToZero();

/* Move Forward */
robot1.moveNB(angle,0,NaN);
robot2.moveNB(angle,0,NaN);
robot3.moveNB(-angle,0,NaN);
robot4.move(-angle,0,NaN);

/* Move Backward */
robot1.moveNB(-angle,0,NaN);
robot2.moveNB(-angle,0,NaN);
robot3.moveNB(angle,0,NaN);
robot4.move(angle,0,NaN);

/* Sharp Turn 90 */
robot1.moveJointToNB(JOINT2, 90);
robot2.moveJointToNB(JOINT2, -90);
robot3.moveJointToNB(JOINT2, -90);
robot4.moveJointTo(JOINT2, 90);

/* Move Forward */
robot1.moveNB(angle,0,NaN);
robot2.moveNB(-angle,0,NaN);
robot3.moveNB(angle,0,NaN);
robot4.move(-angle,0,NaN);
```

Program 13.9: Controlling an omnidrive with four Linkbot-Ls.

### 13.3. Control Multiple Connected Linkbot-Ls

Running Program 13.9 will roll the four wheels simultaneously to move the omnidrive forward and backward. The line

```
double angle = 250;
```

declares a variable `angle` of **double** type and assigns it the value 250. This variable is used to control each of the four wheels in forward and backward motions of 250 degrees. Then all Linkbot-Ls connect and reset their joints to the zero position. Then the lines

```
robot1.moveNB(angle,0,NaN);
robot2.moveNB(angle,0,NaN);
robot3.moveNB(-angle,0,NaN);
robot4.move(-angle,0,NaN);
```

simultaneously rotate `robot1` and `robot2` by 250 degrees and rotate `robot3` and `robot4` by -250 degrees. Since joint 1 of both `robot1` and `robot2` are on the left side of the omnidrive, they rotate by a positive angle value according to the right-hand rule. Since joint 1 of `robot3` and `robot4` are on the right side of the omnidrive, they rotate by a negative angle value according to the right-hand rule. The combined motion of all four Linkbot-Ls moves the omnidrive forward by 250 degrees. A blocking motion function is used for `robot4` so that the program will wait until all four wheels have finished moving forward. The next statements

```
robot1.moveNB(-angle,0,NaN);
robot2.moveNB(-angle,0,NaN);
robot3.moveNB(angle,0,NaN);
robot4.move(angle,0,NaN);
```

simultaneously move all four wheels of the omnidrive backward by 250 degrees. This time the angle values for joint 1 of `robot1` and `robot2` are negative, and the angle values for joint 1 of `robot3` and `robot4` are positive. The next lines

```
robot1.moveJointToNB(JOINT2, 90);
robot2.moveJointToNB(JOINT2, -90);
robot3.moveJointToNB(JOINT2, -90);
robot4.moveJointTo(JOINT2, 90);
```

simultaneously move joint 2 of `robot1` and `robot4` to an absolute joint angle position of 90 degrees. At the same time, joint 2 of `robot2` and `robot3` move to an absolute joint angle position of -90 degrees. The cumulative effect of these motions is to turn all four wheels of the omnidrive in a sharp left turn. The last four lines of the program

```
robot1.moveNB(angle,0,NaN);
robot2.moveNB(-angle,0,NaN);
robot3.moveNB(angle,0,NaN);
robot4.move(-angle,0,NaN);
```

move the omnidrive forward by 250 degrees. Since joint 1 of `robot1` and `robot3` are now on the left side of the omnidrive, they rotate by a positive angle value in order to move forward. `robot2` and `robot4` are now on the right side of the omnidrive, so they need to rotate by a negative angle value in order to move the omnidrive forward.

 Do Exercise 11 on page 249.

#### 13.3.1 Summary

1. Call the **CLinkbotI** member function

```
robot.holdJoint(id);
```

### 13.3. L Control Multiple Connected Linkbot-Ls

to relax a joint of a Linkbot specified by its argument `i.d.`

2. Call the `CLinkbotI` member function

```
robot.setJointSafetyAngle(angle);
```

to set the joint safety angle.

3. Most of the blocking and non-blocking `CLinkbotI` member functions are also available for the `CLinkbotL` class.

#### 13.3.2 Terminology

connected Linkbots-Ls.

#### 13.3.3 L Exercises

1. Write a program `stand2.ch` to control two connected Linkbot-Ls with the standing motion. Joint 2 of the 1st robot is connected with a square faceplate. Joint 1 of two robots are connected by a bridge connector as shown in the figure. The program will move joints for two robots in the following sequences. Move joint 1 of robot1 to -90 degrees, joint 1 of robot2 to 90 degrees, joint 2 of robot1 to 45 degrees, then joint 1 of robot1 to 0 degree.



2. L Pose teach two linked Linkbot-Ls from the flat position to stand up as shown Figure 13.6 on page 232. Play the recorded motion. Save the motion in a program `teachstand.ch` and run the program in ChIDE.
3. L Pose teach two linked Linkbot-Ls to bow as shown in Figure 13.7 on page 235. Play the recorded motion. Save the motion in a program `teachbow.ch` and run the program in ChIDE. Compare the program `teachbow.ch` with the program `bow.ch` in Program 13.6.
4. L Write a program `inchworm2.ch` to control two Linkbot-Ls in an inchworm motion. Joint 2 of the two robots are connected with a square faceplate. Joint 1 of the two robots are connected by a bridge connector. The program will move joint 1 of each robot in the following sequences. To move the inchworm left move joint 1 of robot1 to -50 degrees, joint 1 of robot2 to 40 degrees, joint 1 of robot1 to 0 degrees, and joint 1 of robot2 to 0 degrees. To move the inchworm right move joint 1 of robot2 to 40 degrees, joint 1 of robot1 to -50 degrees, joint 1 of robot2 to 0 degrees, and joint 2 of robot1 to 0 degrees. Joint 2 of robot1 and robot2 will not move.

### 13.3. Control Multiple Connected Linkbot-Ls

5. Run the program `gripper.ch` using a Linkbot-L to pick up a highlighter pen and hackysack as shown in Figure 13.11. The gripper is opened by 90 degrees first, joint 2 rotates by 90 degrees, then close the gripper. Write a program `gripper2.ch` using a Linkbot-I to open the gripper by 90 degrees first, then close the gripper.

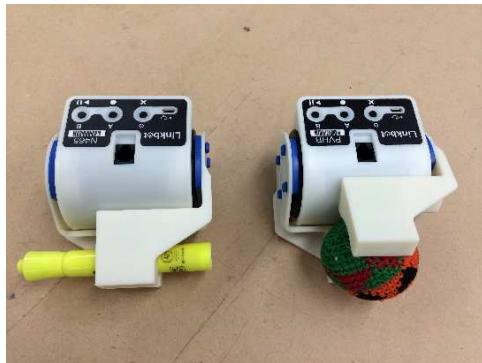


Figure 13.11: A Linkbot-I picks up a pen and hackysack.

6. The program `opengripper.ch` illustrates how the program `gripper.ch` in Exercise 6 can be implemented similarly without using the member functions `openGripper()` and `closeGripper()`.

```
/* File: opengripper.ch
   Grip an object using a Linkbot-L.
   When mounting the gripper, make sure joint 1 is in zero position
   if the gripper is closed */
#include <linkbot.h>
CLinkbotL gripper;
double gripperAngleNew, gripperAngleOld;

gripper.connect();
gripper.resetToZero();

/* Open the gripper by moving joint1 to -90 and joint2 to 90 */
gripperAngleOld = 0;           // initialize the variable
gripperAngleNew = -90;
gripper.moveTo(gripperAngleNew, 90, NaN);

/* Close the gripper to grab an object */
while(abs(gripperAngleNew - gripperAngleOld) > 0.1) {
    printf("gripperAngleNew = %lf\n", gripperAngleNew);
    gripperAngleOld = gripperAngleNew;      // update the old position
    gripper.moveJointNB(JOINT1, 8);        // move 8 degrees
    gripper.delaySeconds(1);               // closing for 1 second
    gripper.getJointAngle(JOINT1, gripperAngleNew); // get the new position
}
gripper.moveJointNB(JOINT1, 8); // try to move another 8 degrees
gripper.delaySeconds(1);      // closing for 1 second
gripper.holdJoint(JOINT1);    // hold the object
gripper.holdJointsAtExit();  // hold the object when the program ends
```

Program 13.10: Opening the gripper by 90 degrees, rotating joint 2 by 90 degrees, then closing the gripper using a Linkbot-L.

The statements

### 13.3. Control Multiple Connected Linkbot-Ls

```
gripperAngleOld = 0;           // initialize the variable
gripperAngleNew = -90;
```

initialize the variable `gripperAngleOld` with zero and `gripperAngleNew` with  $-90$ .

The statement

```
/* Open the gripper by moving joint1 to -90 and joint2 to 90 */
gripper.moveTo(gripperAngleNew, 90, NaN);
```

rotates the gripper sideways by  $90$  degrees, while the claw rotates open by  $-90$  degrees.

Then the next lines of the program

```
/* Close the gripper to grab an object */
while(abs(gripperAngleNew - gripperAngleOld) > 0.1) {
    gripperAngleOld = gripperAngleNew;      // update the old position
    gripper.moveJointNB(JOINT1, 8);        // move 8 degrees
    gripper.delaySeconds(1);               // closing for 1 second
    gripper.getJointAngle(JOINT1, gripperAngleNew); // get the new position
}
gripper.moveJointNB(JOINT1, 8); // try to move another 8 degrees
gripper.delaySeconds(1);       // closing for 1 second
gripper.holdJoint(JOINT1);     // hold the object
```

closes the claw of the gripper around the highlighter pen. The code uses a **while** loop to repeatedly move the joint 1 of the gripper by  $8$  degrees till the absolute value for the difference between the two subsequent readings is smaller than  $0.1$  degree. The function `abs()` obtains the absolute value of its argument. The motion for joint 1 is accomplished by the member function `moveJointNB()` for  $1$  second by the member function `delaySeconds()`. Then, the joint angle is obtained by the member function `getJointAngle()`. For a firm hold on the pen, after the **while** loop, joint 1 for the gripper is moved again for  $1$  second and set to the hold state by the member function `holdJoint()`.

- Run the program `opengripper.ch` to open and close a gripper as shown in Figure 13.11 to grab an object.
- Write a similar program `opengripper2.ch` using a Linkbot-I to grab an object. The program will open the gripper by  $90$  degrees using the following statements.

```
/* Open the gripper by moving joint1 to -45 and joint3 to -45 */
gripperAngleOld = 0;           // initialize the variable
gripperAngleNew = -45;
gripper.moveTo(gripperAngleNew, NaN, -45);
```

It then closes the gripper.

- Run the program `explorer.ch` in Program 13.8 in both hardware and RoboSim (in Preconfigured Linkbot Configurations in `explorer.ch`).
- Modify Program 13.8 as `explorer2.ch` to pick up a hackysack as shown in Figure 13.12. The code for getting the arm ready should be as follows.

```
/* arm ready */
robot3.moveToNB(50, NaN, -50);
robot4.moveToNB(-100, NaN, 100);
robot3.moveWait();
robot4.moveWait();
```

### 13.3. Control Multiple Connected Linkbot-Ls

Run the program `explorer2.ch` in both hardware and RoboSim (in Preconfigured Linkbot Configurations in `explorer.ch`).



Figure 13.12: An explorer picks up a hackysack.

9. An explorer with a four-wheel drive is shown in Figure 13.13. Write a program `fourwheelexplorer.ch`, similar to Program 13.8. The program shall be able to pick up a highlighter pen and hackysack using such a four-wheel drive explorer. Run the program in both hardware and RoboSim (in Preconfigured Linkbot Configurations in `fourwheelexplorer.ch`).

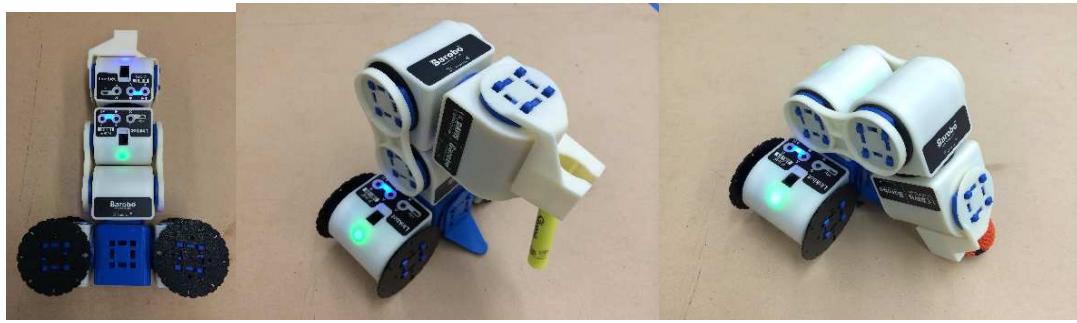
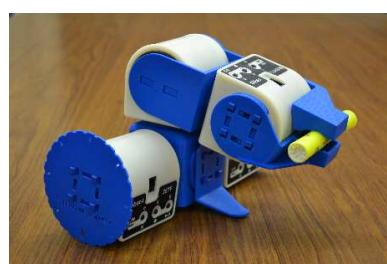


Figure 13.13: An explorer with four Linkbot-Is and one Linkbot-L using a four-wheel drive.

10.  Pose teach an explorer with four Linkbots as shown in the figure below to move towards an object and pick it up. Play the recorded motion. Save the motion in a program `teachexplorer.ch` and run the program in ChIDE.



### 13.4. Control a Group of Connected Linkbots with Identical Movements

11.  Write a program `omnidrive2.ch` by appending the following code to the program `omnidrive.ch` in Program 13.9 an omnidrive with four Linkbot-Ls shown in Figure 13.10. Run the program in ChIDE in debug mode.

```

/* Move Backward */
robot1.moveNB(-angle,0,NaN);
robot2.moveNB(angle,0,NaN);
robot3.moveNB(-angle,0,NaN);
robot4.move(angle,0,NaN);

/* Sharp Turn Back */
robot1.moveJointToNB(JOINT2, 0);
robot2.moveJointToNB(JOINT2, 0);
robot3.moveJointToNB(JOINT2, 0);
robot4.moveJointTo(JOINT2, 0);

/* Sharp Turn 45 */
robot1.moveJointToNB(JOINT2, 45);
robot2.moveJointToNB(JOINT2, 45);
robot3.moveJointToNB(JOINT2, 45);
robot4.moveJointTo(JOINT2, 45);

/* Move Forward */
robot1.moveNB(angle,0,NaN);
robot2.moveNB(angle,0,NaN);
robot3.moveNB(-angle,0,NaN);
robot4.move(-angle,0,NaN);

/* Sharp Turn -45 */
robot1.moveJointToNB(JOINT2, -45);
robot2.moveJointToNB(JOINT2, -45);
robot3.moveJointToNB(JOINT2, -45);
robot4.moveJointTo(JOINT2, -45);

/* Move Forward */
robot1.moveNB(angle,0,NaN);
robot2.moveNB(angle,0,NaN);
robot3.moveNB(-angle,0,NaN);
robot4.move(-angle,0,NaN);

/* Sharp Turn Back */
robot1.moveJointToNB(JOINT2, 0);
robot2.moveJointToNB(JOINT2, 0);
robot3.moveJointToNB(JOINT2, 0);
robot4.moveJointTo(JOINT2, 0);

```

## 13.4 Control a Group of Connected Linkbots with Identical Movements

In Section 13.1 and Section 13.3, we learned how to control multiple connected Linkbots. In this section we will learn how to control a group of connected Linkbots in identical movements. Four Linkbot-Is can be connected in a four-bot drive configuration, which is similar to the omnidrive configuration from Program 13.9. Groups can be used to control the left and right wheels of the four-bot drive. Figure 13.14 shows

### 13.4. Control a Group of Connected Linkbots with Identical Movements

the four-bot drive configuration. To assemble this configuration, connect joint 2 of each Linkbot-I to each corner of an H-connector. Attach wheels to joint 1 of each Linkbot-I on the left hand side, and attach wheels to joint 3 of each Linkbot-I on the right hand side.



Figure 13.14: A four-bot drive with four Linkbot-Is.

### 13.4. Control a Group of Connected Linkbots with Identical Movements

```
/* File: fourbotdrive.ch
*
*      Top View
*
*      |++| ++|
*      |++| ++|
*
*      |++| ++|
*      |++| ++|
*
*/
#include <linkbot.h>

CLinkbotI robotLeftFront, robotLeftRear,
CLinkbotI robotRightFront, robotRightRear;
CLinkbotIGroup robotLeft, robotRight;

robotLeft.addRobot(robotLeftFront);
robotLeft.addRobot(robotLeftRear);
robotRight.addRobot(robotRightFront);
robotRight.addRobot(robotRightRear);

robotLeft.connect();
robotRight.connect();

robotLeft.resetToZeroNB();
robotRight.resetToZeroNB();
robotLeft.moveWait();
robotRight.moveWait();

/* move forward */
robotLeft.moveNB(360, NaN, 0);
robotRight.moveNB(0, NaN, -360);
robotLeft.moveWait();
robotRight.moveWait();

/* move backward */
robotLeft.moveNB(-360, NaN, 0);
robotRight.moveNB(0, NaN, 360);
robotLeft.moveWait();
robotRight.moveWait();

/* turn right */
robotLeft.moveNB(360, NaN, 0);
robotRight.moveNB(0, NaN, 360);
robotLeft.moveWait();
robotRight.moveWait();

/* turn left */
robotLeft.moveNB(-360, NaN, 0);
robotRight.moveNB(0, NaN, -360);
robotLeft.moveWait();
robotRight.moveWait();
```

Program 13.11: Controlling four Linkbot-Is as a four-bot drive vehicle.

Program 13.11 controls the wheels on the left side of the four-bot drive using one group and the wheels

### 13.4. Control a Group of Connected Linkbots with Identical Movements

on the right side using another group. The lines

```
CLinkbotI robotLeftFront, robotLeftRear;
CLinkbotI robotRightFront, robotRightRear;
```

declares variables to control each Linkbot-I. The variables `robotLeftFront`, `robotLeftRear`, `robotRightFront`, and `robotRightRear` control the Linkbot-Is in the corresponding positions of the four-bot configuration. The next line

```
CLinkbotIGroup robotLeft, robotRight;
```

declares two variables, `robotLeft` and `robotRight`, to control the motions of Linkbot-Is on the left and right sides of the four-bot drive, respectively. The following lines

```
robotLeft.addRobot(robotLeftFront);
robotLeft.addRobot(robotLeftRear);
```

add the Linkbot-Is on the left side of the four-bot drive to the `robotLeft` group, one at a time. Then the lines

```
robotRight.addRobot(robotRightFront);
robotRight.addRobot(robotRightRear);
```

add the Linkbot-Is on the right side of the four-bot drive to the `robotRight` group. The member function `connect()` is called on both groups in order to connect all four variables to Linkbot-Is through Barobolink. Then the non-blocking member function `resetToZeroNB()` is used to reset the joints of all Linkbot-Is to the zero position simultaneously. The next lines

```
robotLeft.moveNB(360, NaN, 0);
robotRight.moveNB(0, NaN, -360);
```

move the four-bot drive forward by 360 degrees. Joint 1 of each Linkbot-I in the `robotLeft` group is rotated by 360 degrees, and joint 3 of each Linkbot-I in the `robotRight` group is rotated by  $-360$  degrees. Since the non-blocking `moveNB()` function is used for both groups, all four Linkbot-Is move simultaneously. Because no wheel is attached to joint 3 of each Linkbot-I in the `robotLeft` group, this joint is rotated by 0 degree. Similarly, because no wheel is attached to joint 1 of each Linkbot-I in the `robotRight` group, this joint is also rotated by 0 degree. The resulting forward movement of the four-bot drive is equivalent to the movement of one Linkbot-I using the following function call

```
robot.move(360, NaN, -360);
```

The function `moveWait()` is called on each group to pause the program until the forward movement is finished. Then the lines

```
robotLeft.moveNB(-360, NaN, 0);
robotRight.moveNB(0, NaN, 360);
```

move the `robotLeft` and `robotRight` groups simultaneously, with the result that the four-bot drive backward by 360 degrees. The movement of the four-bot drive in this case is equivalent to the movement of one Linkbot-I using the function call

```
robot.move(-360, NaN, 360);
```

Then the function `moveWait()` is called on each group to pause the program until the backward movement is finished. The following lines

```
robotLeft.moveNB(360, NaN, 0);
robotRight.moveNB(0, NaN, 360);
```

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cause joint 1 of each Linkbot-I in the `robotLeft` group to rotate 360 degrees. This happens at the same time that joint 3 of each Linkbot-I in the `robotRight` group rotates 360 degrees. The resulting movements of the groups `robotLeft` and `robotRight` cause the four-bot drive to make a full right turn. The motion of the four-bot drive in this case is equivalent to the movement of one Linkbot-I using the function call

```
robot.turnRight(360, radius, trackwidth);
```

where `radius` is the length of the wheel radius and `trackwidth` is the distance between the two wheels. The function `moveWait()` is again called on both groups to pause the program until the right turn is finished. Then the next statements

```
robotLeft.moveNB(-360, NaN, 0);
robotRight.moveNB(0, NaN, -360);
```

cause joint 1 of each Linkbot-I in the `robotLeft` group to rotate -360 degrees. At the same time, joint 3 of each Linkbot-I in the `robotRight` group also rotates -360 degrees. The resulting simultaneous movements of both groups cause the four-bot drive to make a full left turn. The motion of the four-bot drive is equivalent to the movement of one Linkbot-I using the function call

```
robot.turnLeft(360, radius, trackwidth);
```

where `radius` is the length of the wheel radius and `trackwidth` is the distance between the two wheels. Finally, the function `moveWait()` is called on both groups to allow the left turn to complete before the program finishes execution.

 Do Exercise 1 on page 257.

We can also make a group of connected Linkbot-Ls perform identical bowing motions. Figure 13.15 shows a group of connected Linkbot-Ls, assembled as described in Section 13.3. Be sure that `robot3` and `robot4` are assembled in the same manner as `robot1` and `robot2`. Also be sure to place the faceplates of `robot1` and `robot3` on the ground before running Program 13.12.



Figure 13.15:  Two Linkbot-Ls bow at the same time.

13.4.  Control a Group of Connected Linkbots with Identical Movements

```

/* File: groupbow.ch
Bow a group of two, each with two linked Linkbot-Ls.
Joint 2 of robot1 is connected to a square faceplate, placed on the ground.
Joint 1 of robot1 and robot2 are connected by a bridge connector.
robot3 and robot4 are connected in the same manner as robot1 and robot2 */
#include <linkbot.h>
CLinkbotL robot1, robot2, robot3, robot4;
CLinkbotLGroup group1, group2;

/* add robot1 and robot3 to the group1
   add robot2 and robot4 to the group2 */
group1.addRobot(robot1);
group1.addRobot(robot3);
group2.addRobot(robot2);
group2.addRobot(robot4);

/* connect to robots and move to the zero position at the same time. */
group1.connect();
group2.connect();
group1.resetToZeroNB();
group2.resetToZero();

/* set speed ratio to 0.25 for slow motion */
group1.setJointSpeedRatios(0.25, 0.25, NaN);
group2.setJointSpeedRatios(0.25, 0.25, NaN);

/* bow */
group1.moveTo(0, 45, NaN);
group2.moveToNB(90, 0, NaN);
group1.moveTo(-45, 45, NaN);

/* back to the original position */
group1.resetToZeroNB();
group2.resetToZero();

```

Program 13.12:  Bowing a group of Linkbot-Ls for robot dance.

Program 13.12 controls groups of connected modules in bowing motions. A **connected module** refers to a single Linkbot that occupies a specific position in a configuration, such as the gripper of the explorer from Program 13.8. A **group of connected modules** refers to multiple corresponding Linkbots that occupy a specific position in multiple identical configurations. An example would be a group of grippers from multiple explorers. A group of connected modules can be controlled using member functions of either the **CLinkbotIGroup** or **CLinkbotLGroup** classes. Like the **CLinkbotIGroup** class, the **CLinkbotLGroup** class is defined in the **linkbot.h** header file. The line

```
CLinkbotLGroup group1, group2;
```

declares two variables, **group1** and **group2**, of class **CLinkbotLGroup**. These will be used to control the groups of connected modules. Then the lines

```
group1.addRobot(robot1);
group1.addRobot(robot3);
```

add **robot1** and **robot3** to **group1** using the **CLinkbotLGroup** version of the member function **addRobot()**. The syntax is the same as the syntax for the **CLinkbotIGroup** version, which is listed in Section 6.1. Since **robot1** and **robot3** are the feet in each of the identical configurations, they will be controlled by the same group. The next lines

### 13.4. L Control a Group of Connected Linkbots with Identical Movements

```
group2.addRobot(robot2);
group2.addRobot(robot4);
```

add `robot2` and `robot4` to `group2`. Since `robot2` and `robot4` are the heads in each of the identical configurations, they will be controlled by a different group than `robot1` and `robot3`. The next lines

```
group1.connect();
group2.connect();
group1.resetToZeroNB();
group2.resetToZero();
```

connect the variables in each group to Linkbot-Ls at the same time, and then reset all joints of all Linkbot-Ls to the zero position. The **CLinkbotLGroup** versions of the member functions **connect()**, **resetToZero()**, and **resetToZeroNB()** are used in this case, with syntax similar to that listed in Section 6.1. The next lines

```
group1.setJointSpeedRatios(0.25, 0.25, NaN);
group2.setJointSpeedRatios(0.25, 0.25, NaN);
```

sets the speed ratios for all joints of all Linkbot-Ls in `group1` and `group2` to the value 0.25, for slow motion. The general syntax for the **CLinkbotLGroup** version of the member function **setJointSpeedRatios()** is similar to that listed in Section 7.5.4, with two differences. The first difference is that, because **setJointSpeedRatios()** is being used for Linkbot-Ls, the arguments will be slightly different. The first and second arguments will be joint speed ratio values, and the third argument will be `Nan` since joint 3 does not move. The second difference is that, because **setJointSpeedRatios()** is being used for groups, the joint speed ratios of multiple Linkbot-Ls will be set using a single function call. The next line

```
group1.moveTo(0, 45, NaN);
```

rotates the faceplates attached to joint 2 of the Linkbot-Ls in `group1` by 45 degrees. This partially turns the two standing configurations so that they are facing left. Since the **CLinkbotLGroup** version of **moveTo()** is used, multiple Linkbot-Ls are turned at the same time. Then the line

```
group2.moveToNB(90, 0, NaN);
```

rotates joint 1 of the Linkbot-Ls in `group2` by 90 degrees. This will cause `robot2` and `robot4`, the heads of the bowing configurations, to fold forward. Since the statement uses a non-blocking function, then the next line will execute simultaneously with it. This synchronous statement

```
group1.moveTo(-45, 45, NaN);
```

holds the position of joint 2 of the Linkbot-Ls in `group1` at the absolute joint angle position of 45 degrees, while rotating joint 1 of both `robot1` and `robot3` forward by 45 degrees. These motions of `group1` will be performed at the same time as the motions from the previous statement. After this line executes, then both configurations in the group will be bowing at the same time, as shown in Figure 13.15. Finally, the lines

```
group1.resetToZeroNB();
group2.resetToZero();
```

resets joints 1 and 2 of all Linkbot-Ls in both groups simultaneously to the zero position. Both of the identical configurations will now be standing up straight and facing forward as the program finishes execution.

 Do Exercises 2 and 3 on page 257.

#### 13.4.1 Summary

1. Include the header file `linkbot.h` and use the class **CLinkbotIGroup** to declare a variable `group` by the following two statements

### 13.4. Control a Group of Connected Linkbots with Identical Movements

```
#include <linkbot.h>
CLinkbotIGroup group;
```

for controlling a group of Linkbot-Is.

2. Include the header file **linkbot.h** and use the class **CLinkbotLGroup** to declare a variable **group** by the following two statements

```
#include <linkbot.h>
CLinkbotLGroup group;
```

for controlling a group of Linkbot-Ls.

3. Call the **CLinkbotIGroup** member function

```
group.addRobot(name);
```

to add a single Linkbot-I to a group.

4. Call the **CLinkbotLGroup** member function

```
group.addRobot(name);
```

to add a single Linkbot-L to a group.

5. Use a group of connected modules to control multiple connected modules in identical motions.
6. Most of the blocking and non-blocking **CLinkbotIGroup** member functions are also available for the **CLinkbotLGroup** class.

#### 13.4.2 Terminology

**CLinkbotIGroup**, **CLinkbotLGroup**, connected modules, group of connected modules.

#### 13.4.3 Exercises

1. Write a program **fourbotdrive2.ch** to control groups of Linkbot-Is in a four-bot drive configuration. The program will move the four-bot drive in the following sequence. Move backward 360 degrees, turn left 720 degrees, move forward 360 degrees, and finally turn right 720 degrees.
2.  Write a program **groupbow2.ch** for four Linkbots to bow simultaneously.

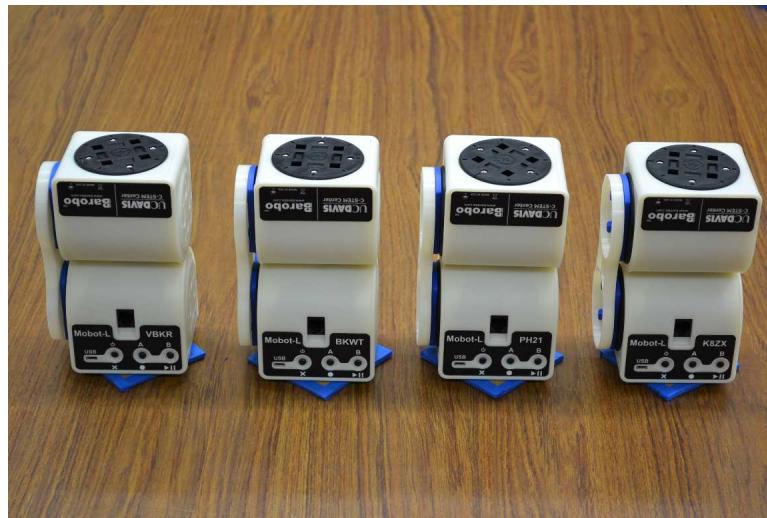
13.4.  Control a Group of Connected Linkbots with Identical Movements

Figure 13.16: A group of Linkbots bow simultaneously.

3.  Write a program `groupbow3.ch` for three Linkbots to bow in the following manner. The middle Linkbot bows first, delay for 0.5 second, then two other Linkbots bow at the same time. Treat the two other Linkbots as a group.

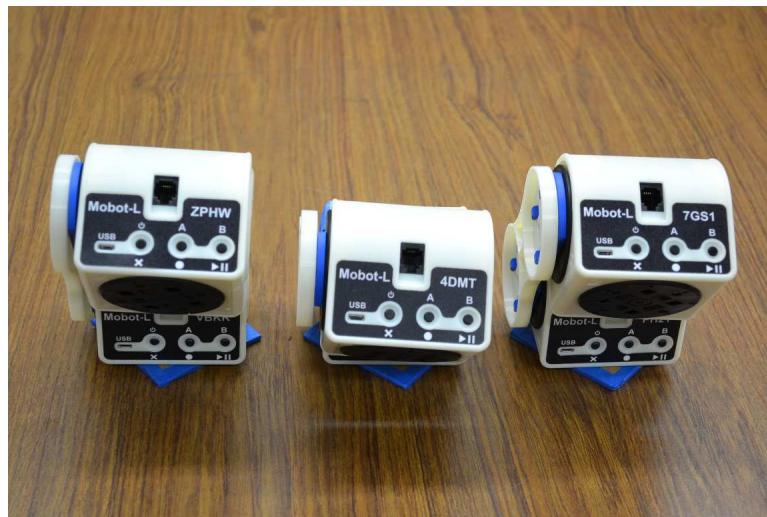


Figure 13.17: Three Linkbots bow together, with the middle one bowing first, followed by other two Linkbots.

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## APPENDIX A

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# Using Advanced Programming Features

This appendix lists a few sample programs using advanced programming features not covered in this book. You may learn more about these advanced features in the book *Learning Computer Programming in Ch for the Absolute Beginner*.

## A.1 Make a Decision Using an **if** and **else if** Statements

The general syntax of an **if**, **else if**, and **else** statement is as follows:

```
if(expression1) {  
    /* statements1; */  
}  
else if(expression2) {  
    /* statements2; */  
}  
else {  
    /* statements3; */  
}
```

The **if-else** statement is a common way to make decisions in a program. The expressions in parentheses, `expression1` and `expression2` are called the **controlling expressions** because they control which part of the **if-else** statement is used. If the controlling expression `expression1` is true, then the `statements1` following the **if** statement are executed and the statements following the **else if** and **else** statements get skipped. If the controlling expression `expression1` is false, then the `statements1` following the **if**

## A.1. Make a Decision Using an **if** and **else if** Statements

statement are skipped and the next controlling expression, `expression2` is evaluated. If `expression2` is true, then the `statements2` following the **else if** statement are executed and the `statements3` following the **else** statement get skipped. If `expression2` is false, however, then the `statements2` following the **else if** statement get skipped and the `statements3` following the **else** statement are executed. An **if-else** statement always has an **if** statement. The **else if** and **else** statements are optional.

Program 11.16 copies the position of the one Linkbot to the other Linkbot. Program A.1 controls the joint speed for a Linkbot by the corresponding joint angle of a controlled Linkbot. In Program A.1, the statement

```
robot1.relaxJoints();
```

relaxes joints 1 and 3 of `robot1`. This allows the user to turn each joint freely. The statement

```
robot2.driveForeverNB();
```

drives joints 1 and 3 of `robot1` forever.

A **while** loop is used to control the speed of joints 1 and 3 for `robot2` based on the joint angles of joints 1 and 3 of `robot1`. Inside the **while** loop, first the statement

```
speed1 = angle1;
```

obtains the joint angles for joints 1 and 3. The statement

```
speed1 = angle1;
```

then assigns the value of the angular position for joint 1 as the value of the speed for joint 1. The statements

```
if(speed1 > 240) {
    speed1 = 240;
}
else if(speed1 < -240)
    speed1 = -240;
}
```

compare the value of `speed1` with the maximum positive and negative speeds that a Linkbot joint can move. If the first controlling expression `speed1 > 240` is true, then the variable `speed1` is changed to the maximum speed of 240 degrees per second. If `speed1 > 240` is false, however, then the program skips to the **else if** statement and evaluates the second controlling expression `speed1 < -240`. If this expression is true, then `speed1` is changed to the value  $-240$  degrees per second. If both controlling statements prove to be false, then `speed1` is unchanged. The **if** statement and **if else** statements that check the value of `speed1` are used as boundary checks. This helps ensure that the speed of joint 1 is not set higher than the maximum speed of 240 degrees per second or lower than the speed of  $-240$  degrees per second. A similar speed boundary check is performed for joint 3 in the program.

A.1. Make a Decision Using an **if** and **else if** Statements

```

/* Filename: speedcontrol.ch
The joint angles for robot1 in green color will determine
the speed of joints for robot2 in red color. */
#include <linkbot.h>
CLinkbotI robot1, robot2;
double angle1, angle3;
double speed1, speed3;

/* Connect to robots */
robot1.connect();
robot2.connect();

/* Set colors for robots. Use the green robot to control the red one */
robot1.setLEDColor("green");
robot2.setLEDColor("red");

robot1.resetToZeroNB();
robot2.resetToZeroNB();
robot1.moveWait();
robot2.moveWait();

/* relax all joints of robot1 */
robot1.relaxJoints();

/* set joints of robot2 to move forward */
robot2.driveForeverNB();

while(1) {
    robot1.getJointAngles(angle1, NaN, angle3);

    speed1 = angle1;
    if(speed1 > 240) {
        speed1 = 240;
    }
    else if(speed1 < -240) {
        speed1 = -240;
    }

    speed3 = angle3;
    if(speed3 > 240) {
        speed3 = 240;
    }
    else if(speed3 < -240) {
        speed3 = -240;
    }

    robot2.setJointSpeeds(speed1, NaN, -speed3);
}

```

Program A.1: Controlling the joint speed for a Linkbot by the corresponding joint angle of a controlled Linkbot.

 Do Exercise 1, on page 265.

A.2. Use a **while**-Loop for Repeating Motions

```
/* File: whileloop.ch
   repeat motions using a while-loop */
#include <linkbot.h>
CLinkbotI robot;
int i, num;

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* repeat rolling forward and backward 3 times */
num = 3;
i=0;
while(i<num) {
    robot.driveForward(360); // drive forward 360 degrees
    robot.driveBackward(360); // drive backward 360 degrees
    i++; // increment i
}
```

Program A.2: Rolling a Linkbot-I forward and backward three times using a **while** loop.

A **while** loop in Ch can be used to repeat actions. Program A.2 uses a **while** loop to repeat the motion of rolling forward 360 degrees and rolling backward 360 degrees. The **while** loop consists of the code fragment below.

```
/* repeat rolling whileward and backward 3 times */
num = 3;
i=0;
while(i<num) {
    robot.driveForward(360); // drive forward 360 degrees
    robot.driveBackward(360); // drive backward 360 degrees
    i++;
```



The variable `num` with the value of 3 is the number of the repetitions. The variable `i` is the loop control variable. It is initialized to zero. The loop control expression `i < num` is the loop continuation condition. If the control variable `i` is less than `num`, the statements below in the loop body is executed.

```
robot.driveForward(360); // drive forward 360 degrees
robot.driveBackward(360); // drive backward 360 degrees
i++; // increment i;
```

At the end of the loop body, the variable `i` is incremented by 1. While the value of `i` is less than the value of `num`, the loop iterates. Because `num` is 3, the motion of rolling forward 360 degrees and rolling backward 360 degrees will be repeated three times.

 Do Exercise 2, on page 265.

A.3. Use a **for**-Loop for Repeating Motions

```
/* File: forloop.ch
   repeat motions using a for-loop */
#include <linkbot.h>
CLinkbotI robot;
int i, num;

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* repeat rolling forward and backward 3 times */
num = 3;
for (i=0; i<num; i++) {
    robot.driveForward(360);    // roll forward 360 degrees
    robot.driveBackward(360);   // roll backward 360 degrees
}
```

Program A.3: Rolling a Linkbot-I forward and backward three times using a **for** loop.

A **for** loop in Ch can also be used to repeat actions. Similar to Program A.2, Program A.3 uses a **for** loop to repeat the motion of rolling forward 360 degrees and rolling backward 360 degrees three times. The **for** loop consists of the code fragment below.

```
/* repeat rolling forward and backward 3 times */
num = 3;
for (i=0; i<num; i++) {
    robot.driveForward(360);    // drive forward 360 degrees
    robot.driveBackward(360);   // drive backward 360 degrees
}
```

The variable `num` with the value of 3 is the number of the repetitions. There are three expressions in the **for** loop control structure

```
for (i=0; i<num; i++)
```

The first expression `i=0` initializes the loop control variable `i` with 0. The second expression `i<num` is the loop continuation condition. The loop iterates when the control variable `i` is less than `num`. The third expression `i++` increments the control variable after the loop body

```
robot.driveForward(360);    // drive forward 360 degrees
robot.driveBackward(360);   // drive backward 360 degrees
```

is executed.

The above **for** loop is the same as the following **while** loop presented in section A.2.

```
/* repeat rolling forward and backward 3 times */
num = 3;
i=0;
while(i<num)  {
    robot.driveForward(360);    // drive forward 360 degrees
    robot.driveBackward(360);   // drive backward 360 degrees
    i++;
}
```

 Do Exercise 3, on page 265.

## A.4 Use a Function with an Argument of the **CLinkbotI** Class

```
/* File: function.ch
   repeat motions using the functions roll() */
#include <linkbot.h>
CLinkbotI robot;

/* the function prototype for roll() */
void roll(CLinkbotI &robot);

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* call the function roll() three times
   to repeat the motions defined in the function three times */
roll(robot);
roll(robot);
roll(robot);

/* define the function roll() */
void roll(CLinkbotI &robot) {
    robot.driveForward(360); // drive forward 360 degrees
    robot.driveBackward(360); // drive backward 360 degrees
}
```

Program A.4: Rolling a Linkbot-I forward and backward using the function `roll()`.

A function can be written in Ch to also repeat actions. Program A.4 uses a function `roll()` for the motion of rolling forward 360 degrees and rolling backward 360 degrees. The function prototype for the function `roll()` is as follows.

```
/* the function prototype for roll() */
void roll(CLinkbotI &robot);
```

Since the data type **void** is the return type for the function `roll()`, the function does not return a value. The function uses an argument of reference type of **CLinkbotI**. Therefore, the variable name `robot` can be used inside the function to access the member functions of **CLinkbotI**. The function `roll()` is defined as

```
/* define the function roll() */
void roll(CLinkbotI &robot) {
    robot.driveForward(360); // drive forward 360 degrees
    robot.driveBackward(360); // drive backward 360 degrees
}
```

When the function `roll()` is called, it will roll forward 360 degrees and roll backward 360 degrees. The program calls this function three times by the following statements.

```
roll(robot);
roll(robot);
roll(robot);
```

Therefore, the motion of rolling forward 360 degrees and rolling backward 360 degrees will be repeated three times.

 Do Exercises 4 and 5 on page 265.

### A.4.1 Exercises

1. Write a program `speedcontrol2.ch`, based on the program `speedcontrol.ch` in Program A.1, to control joint speeds of the controller Linkbot-I by the joint angles of the controlled Linkbot-I by changing the statements

```
speed1 = angle1;
speed3 = angle3;
```

to

```
speed1 = 2*angle1;
speed3 = 2*angle3;
```

The controlled robot will move faster by the same joint angle of the controlling robot. Test the program by changing the statements to

```
speed1 = angle1/2;
speed3 = angle3/2;
```

2. Write a program `whileloop2.ch` using a **while** loop to repeat the motion of rotating joint 1 by 360 degrees and then by  $-360$  degrees for five times. Use the member function **robot.moveJoint()**.
3. Write a program `forloop2.ch` using a **for** loop to repeat the motion of rotating joint 1 by 360 degrees and then by  $-360$  degrees for five times.
4. Write a program `function2.ch` using a function `rotateJoint1()` for the motion of rotating joint 1 by 360 degrees and then by  $-360$  degrees. Call the function `rotateJoint1()` five times to repeat the motion defined in the function.
5. The function `wait5robots()` is defined as follows:

```
void wait5robots(CLinkbotI &robot1, CLinkbotI &robot2, CLinkbot &robot3,
                 CLinkbotI &robot4, CLinkbotI &robot5) {
    robot1.moveWait();
    robot2.moveWait();
    robot3.moveWait();
    robot4.moveWait();
    robot5.moveWait();
}
```

Modify the program `snake.ch` in Program 13.3 to call the function `wait5robots()` once using

```
wait5robots(robot1, robot2, robot3, robot4, robot5);
```

instead of calling the member function **moveWait()** five times.

---

---

## APPENDIX B

---

# Moving Robots in a Coordinate System in RoboSim

Ch programs can control robots in RoboSim with an x and y coordinate system as described in Chapter 4. Because of the convenience for defining the motion of robots in a coordinate system, member functions **drivexyTo()**, **getxy()**, **drivexyToFunc()**, **drivexyToExpr()**, **drivexyToNB()**, **drivexyWait()**, **drivexy()**, **drivexyNB()**, **traceOn()**, **traceOff()**, **recordxyBegin()**, and **recordxyEnd()**, are implemented to control robots in RoboSim. In addition, member functions **point()**, **line()**, and **text()** are implemented to draw points, lines, and text on the RoboSim scene. These member functions are especially useful for learning mathematics concepts with RoboSim. They are available for controlling Linkbots in RoboSim only, but not available for use with the Linkbot Hardware. In this appendix, these member functions and their applications are described.

### B.1 Move a Linkbot-I in a Coordinate System

The member function **drivexyTo()** drives the Linkbot-I to the location (x, y) in the x and y coordinate system. The syntax of the member function **drivexyTo()** is as follows.

```
robot.drivexyTo(x, y, radius, trackwidth);
```

The first two arguments specify the location (x, y) to which the robot will drive. The third argument is the radius of the two wheels. The fourth argument is the track width as shown in Figure 5.3 on page 73. Like the arguments for the member functions **turnLeft()** and **turnRight()**, the units for both radius and track width must be the same. They can be inches, feet, centimeters, meters, etc.

The member function **getxy()** can be used to obtain the position of a robot in the x and y coordinate system. The syntax of the member function **getxy()** is as follows.

```
robot.getxy(x, y);
```

## B.1. Move a Linkbot-I in a Coordinate System

The position (x, y) of the robot specified in the x and y coordinate system is passed through its two arguments x and y. The information obtained by this function is the same as the position information obtained by clicking on a Linkbot in a RoboSim scene. But when **getxy()** is called this information is stored internally, and can be used or analyzed later in the program.

Program B.1 demonstrates how to use **drivexyTo()** to draw a graph of a straight line in RoboSim, and how to use **getxy()** to get the position of the Linkbot-I after this line is drawn. Before running program B.1 configure the RoboSim GUI as is shown in Figure 4.1 from Section 4.1, so that the starting position of the Linkbot-I is (0, 0).

```
/* File: drivexyto.ch
Note: This program uses drivexyTo() available in RoboSim only
      to move a Linkbot-I from (0, 0) to (3, 4).
      Use getxy() to get the x and y coordinates of the robot.
      Set the initial position (x, y) in RoboSim GUI to (0, 0) for robot. */
#include <linkbot.h> /* for CLinkbotI */

CLinkbotI robot;
double radius = 1.75;           // radius of 1.75 inches
double trackwidth = 3.69;       // the track width, the distance between two wheels
double x, y;                  // x and y coordinates

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* move the robot to the position (3, 4) */
robot.drivexyTo(3, 4, radius, trackwidth);

/* get the position of the robot */
robot.getxy(x, y);
printf("getxy(x, y) = (%lf, %lf)\n", x, y);
```

Program B.1: Moving a Linkbot-I to a specified location (x, y) using **drivexyTo()**.

## B.1. Move a Linkbot-I in a Coordinate System

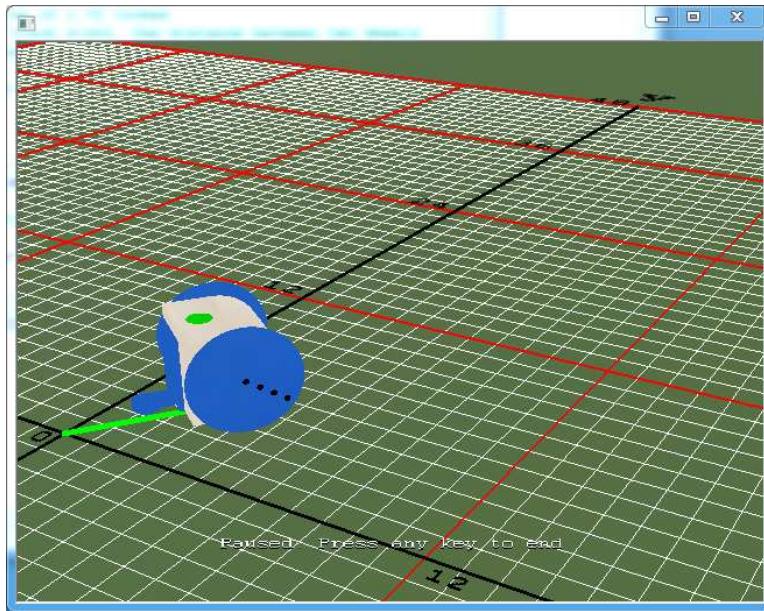


Figure B.1: The RoboSim scene with the robot trajectory from Program B.1.

Program B.1 uses the **CLinkbotI** class member function **drivexyTo()** to drive a Linkbot-I in a straight line from (0, 0) to (3, 4) in RoboSim. The lines

```
double radius = 1.75; // radius of 1.75 inches
double trackwidth = 3.69; // the track width, the distance between two wheels
double x, y; // x and y coordinates
```

declare and initialize the variables that are needed in order to use **drivexyTo()** and **getxy()**. A variable **radius** of **double** type is declared and assigned a value of 1.75, which is desired wheel radius. Another variable **trackwidth**, also of **double** type, is declared and assigned a value of 3.69, which is the distance between the two wheels of the Linkbot-I. The variables **x** and **y** of **double** type will be used to store the **x** and **y** coordinate values that are passed from the arguments of the member function **getxy()**. After the Linkbot-I is connected and set to the zero position, the line

```
robot.drivexyTo(3, 4, radius, trackwidth);
```

uses the **CLinkbotI** member function **drivexyTo()** to drive the virtual Linkbot-I from point (0, 0) to point (3, 4). Pressing the 't' key shows a straight green line between these two points, which looks the same as in Figure B.1. The final two program statements

```
robot.getxy(x, y);
printf("getxy(x, y) = (%lf, %lf)\n", x, y);
```

uses the **CLinkbotI** member function **getxy()** to retrieve the final **x** and **y** coordinates of the Linkbot-I and then prints these coordinates to the ChIDE console using **printf()**. The input/output pane will display the following line

```
getxy(x, y) = (2.993417, 3.997225)
```

Program B.1 demonstrates the efficiency of the member function **drivexyTo()**. In this case, the function call

```
robot.drivexyTo(x, y, radius, trackwidth);
```

is somehow equivalent to the two statements

## B.1. Move a Linkbot-I in a Coordinate System

```
robot.turnRight(angle, radius, trackwidth);
robot.driveDistance(distance, radius);
```

Using **drivexyTo()** in this case eliminates the need to calculate the angle to turn and the distance to drive. Instead, these are calculated internally by the function **drivexyTo()**.

You can also use **getxy()** to obtain the position of a robot after it is driven by **driveForward()**.

 Do Exercises 1, 2, and 3 on 276.

The member function **drivexyTo()** can be used multiple times in a program to drive a virtual Linkbot-I to different points in a coordinate system, drawing a graph along the way. Program B.2 demonstrates this use of **drivexyTo()**, and also uses **CPlot** member functions to plot the specified points in a separate window. Member functions **mathCoord()**, **title()**, and **label()** of the **CPlot** class are introduced in section 8.1 in Chapter 8. Comparing a plot, generated using the **CPlot** member functions, to the trajectory of a virtual Linkbot shows the accuracy of the RoboSim GUI's graphing capabilities. Set the initial position of the Linkbot-I in RoboSim GUI to (0, 0) before running Program B.2. To see the full trajectory of the Linkbot's motion in the RoboSim GUI, hold the right mouse button and drag to zoom out and then hold both mouse buttons and drag to pull the Linkbot-I to the left side of the RoboSim GUI window.

```
/* File: points.ch
Note: This program uses drivexyTo() available in RoboSim only
      to move one Linkbot-I to multiple points.
Set the initial position (x, y) in RoboSim GUI to (0, 0) for the robot.
A robot moves to specified points */
#include <chplot.h> /* for CPlot */
#include <linkbot.h> /* for CLinkbotI */

CPlot plot;
CLinkbotI robot;
double radius = 1.75; // radius of 1.75 inches
double trackwidth = 3.69; // the track width, the distance between two wheels
double x, y; // x and y coordinates

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* move the robot to specified points */
robot.drivexyTo(12, 5.5, radius, trackwidth);
robot.drivexyTo(24, 30, radius, trackwidth);
robot.drivexyTo(36, 10, radius, trackwidth);
robot.drivexyTo(48, 5, radius, trackwidth);

/* plot the points */
plot.mathCoord();
plot.title("");
plot.label(PLOT_AXIS_X, "x (in)");
plot.label(PLOT_AXIS_Y, "y (in)");
plot.point(0, 0);
plot.point(12, 5.5);
plot.point(24, 30);
plot.point(36, 10);
plot.point(48, 5);
plot.plotting();
```

Program B.2: Moving a Linkbot-I to multiple specified locations using **drivexyTo()**.

## B.1. Move a Linkbot-I in a Coordinate System

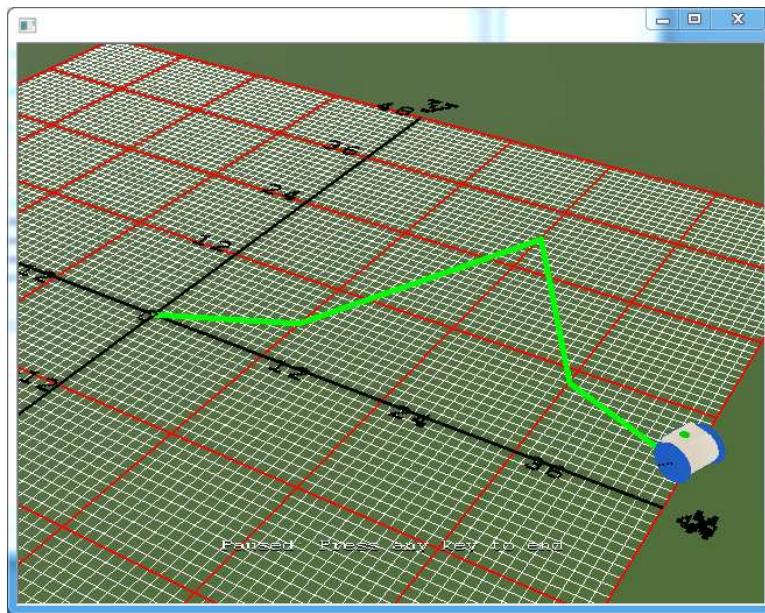


Figure B.2: The RoboSim scene with the robot trajectory from Program B.2.

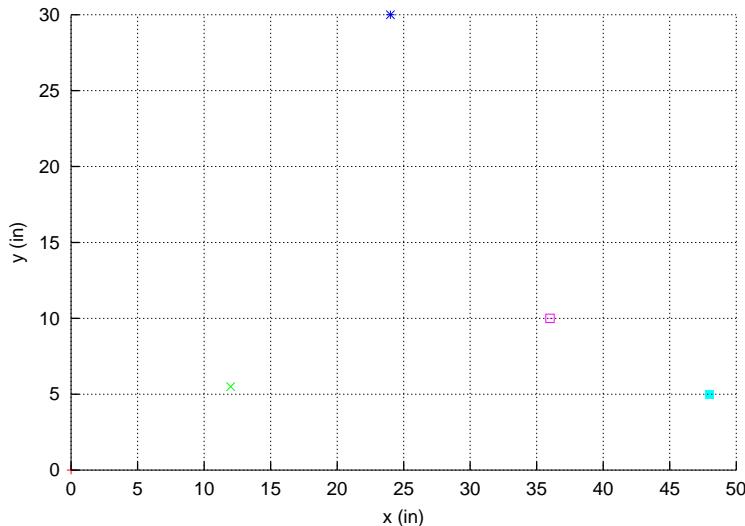


Figure B.3: The plot for the locations traveled by the robot from Program B.2.

Program B.2 drives a virtual Linkbot-I to four different points in a coordinate system. The line

```
robot.drivexyTo(12, 5.5, radius, trackwidth);
```

drives the virtual Linkbot-I from (0, 0) to (12, 5.5) in the coordinate system. The next line

```
robot.drivexyTo(24, 30, radius, trackwidth);
```

drives the virtual Linkbot-I from (12, 5.5) to (24, 30). Notice that the member function **drivexyTo()** drives a virtual Linkbot to an absolute position in an x and y coordinate system. That is, the Linkbot does not need to start at (0, 0) in order to get to the point (24, 30) specified in the second **drivexyTo()** function call. Instead, the program internally calculates how to drive in a straight line from the virtual Linkbot's current location to the absolute location specified by the arguments x and y passed to **drivexyTo()**. Similarly, the lines

## B.1. Move a Linkbot-I in a Coordinate System

```
robot.drivexyTo(36, 10, radius, trackwidth);
robot.drivexyTo(48, 5, radius, trackwidth);
```

drive the virtual Linkbot-I from (24, 30) to (36, 10) and then from (36, 10) to (48, 5) in the coordinate system. The final trajectory of the Linkbot-I is shown in Figure B.2. To plot the individual start and end points along the Linkbot-I's trajectory, the **CPlot** member function **point()** is used. The general syntax of this function is

```
plot.point(x, y);
```

where **x** and **y** are the coordinates of the point to be plotted. The lines

```
plot.point(0, 0);
plot.point(12, 5.5);
plot.point(24, 30);
plot.point(36, 10);
plot.point(48, 5);
```

plot each of the individual points along the Linkbot-I's trajectory. The resulting graph is shown in Figure B.3.

 Do Exercises 4 and 6(a) on page 277.

A virtual Linkbot-I can also be used to draw geometric shapes. Program B.3 drives a Linkbot-I along a trajectory that forms a right triangle using the member function **drivexyTo()**. A plot of the Linkbot's triangular trajectory is also generated using **CPlot** member functions. Before running Program B.3, set the initial position of the Linkbot-I in the RoboSim GUI to (0, 0).

## Appendix B. Moving Robots in a Coordinate System in RoboSim

### B.1. Move a Linkbot-I in a Coordinate System

```

/* File: righttriangle.ch
Note: This program uses drivexyTo() available in RoboSim only
      to move one Linkbot-I from (0, 0) to (3, 0), (3, 4), then to (0, 0).
      Set the initial position (x, y) in RoboSim to (0, 0) for the robot. */
#include <chplot.h>    /* for CPlot */
#include <clinkbot.h>   /* for CLinkbotI */

CPlot plot;
CLinkbotI robot;
double radius = 1.75;      // radius of 1.75 inches
double trackwidth = 3.69;  // the track width, the distance between two wheels
double x, y;              // x and y coordinates

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* move the robot to specified points */
robot.drivexyTo(3, 0, radius, trackwidth);
robot.getxy(x, y);
printf("getxy(x, y) = (%lf, %lf)\n", x, y);

robot.drivexyTo(3, 4, radius, trackwidth);
robot.getxy(x, y);
printf("getxy(x, y) = (%lf, %lf)\n", x, y);

robot.drivexyTo(0, 0, radius, trackwidth);
robot.getxy(x, y);
printf("getxy(x, y) = (%lf, %lf)\n", x, y);

/* the distance between points (0, 0) and (3, 4) */
printf("distance = %lf\n", sqrt(3*3 + 4*4));

/* plot the points */
plot.mathCoord();
plot.title("");
plot.label(PLOT_AXIS_X, "x (in)");
plot.label(PLOT_AXIS_Y, "y (in)");
plot.line(0, 0, 3, 0);
plot.line(3, 0, 3, 4);
plot.line(3, 4, 0, 0);
plot.axisRange(PLOT_AXIS_X, 0, 5); // set the x-axis range
plot.axisRange(PLOT_AXIS_Y, 0, 5); // set the y-axis range
plot.sizeRatio(1);
plot.plotting();

```

Program B.3: Moving a Linkbot-I to follow a right triangle using **drivexyTo()**.

Program B.3 drives a virtual Linkbot-I along the trajectory of a right triangle, prints each of the triangle's three points, calculates the length of the hypotenuse, and then plots the Linkbot's triangular trajectory. The lines

```

robot.drivexyTo(3, 0, radius, trackwidth);
robot.getxy(x, y);
printf("getxy(x, y) = (%lf, %lf)\n", x, y);

```

## B.1. Move a Linkbot-I in a Coordinate System

drives the virtual Linkbot-I from (0, 0) to (3, 0), obtains the x and y coordinates of the virtual Linkbot after the movement, and prints these coordinates to the input/output pane. This printed point represents the first of the right triangle's three points. These actions are repeated by the program to drive the virtual Linkbot-I from (3, 0) to (3, 4), and then from (3, 4) to (0, 0), printing the coordinates of the right triangle's second and third points along the way.

In Program B.3, the Pythagorean Theorem is used to calculate the hypotenuse of the right triangle. For the right triangle shown in Figure B.4,  $c$  is the length of the hypotenuse.  $a$  and  $b$  are the lengths of the two legs. Based on the Pythagorean theorem, they are related by the formula

$$c^2 = a^2 + b^2$$

Given the lengths of the two legs, the length of the hypotenuse for a right triangle can be calculated by the formula

$$c = \sqrt{a^2 + b^2}$$

In Ch, the function `sqrt()` is used to calculate square roots. The general syntax of the `sqrt()` function is

```
sqrt(x);
```

where  $x$  is a number or expression that evaluates as a **double** data type. In Program B.3, the length of the hypotenuse is represented by the distance between points (0, 0) and (3, 4). Given that the length of leg  $a$  is represented by the distance between (0, 0) and (3, 0), which is 3, and the length of leg  $b$  is represented by the distance between (0, 0) and (0, 4), which is 4, the line

```
printf("distance = %lf\n", sqrt(3*3 + 4*4));
```

calculates the hypotenuse of the triangle drawn by the virtual Linkbot-I and then prints it to the input/output pane. After this statement, the input/output pane will display the following lines

```
getxy(x, y) = (3.000506, -0.004528)
getxy(x, y) = (3.004118, 3.994140)
getxy(x, y) = (-0.001259, 0.004295)
distance = 5.000000
```

The **CPlot** member functions `line()` and `sizeRatio()` are used to generate the plot of the virtual Linkbot-I's trajectory. The syntax of the member function `line()` is

```
plot.line(x1, y1, x2, y2);
```

This function draws a straight line between the two points  $(x_1, y_1)$  and  $(x_2, y_2)$ . The lines

```
plot.line(0, 0, 3, 0);
plot.line(3, 0, 3, 4);
plot.line(3, 4, 0, 0);
```

plot the three sides of the right triangle, from point (0, 0), to point (3, 0), back to point (3, 4).

A plot is typically displayed in a rectangular area with the proper scale. The **aspect ratio** of a plot is the ratio of the length of the y-axis to the length of the x-axis. It can be set by the **CPlot** member function `sizeRatio()`, which has the following general syntax

```
plot.sizeRatio(ratio);
```

where the argument `ratio` specifies the aspect ratio. The line

```
plot.sizeRatio(1);
```

## B.1. Move a Linkbot-I in a Coordinate System

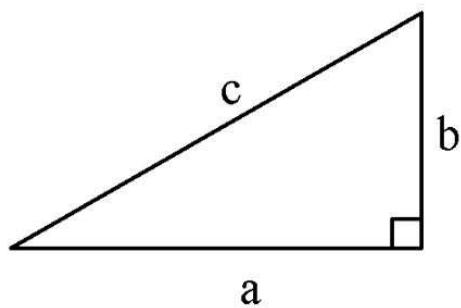


Figure B.4: A right triangle with length  $c$  for the hypotenuse, and lengths  $a$  and  $b$  for the other two legs.

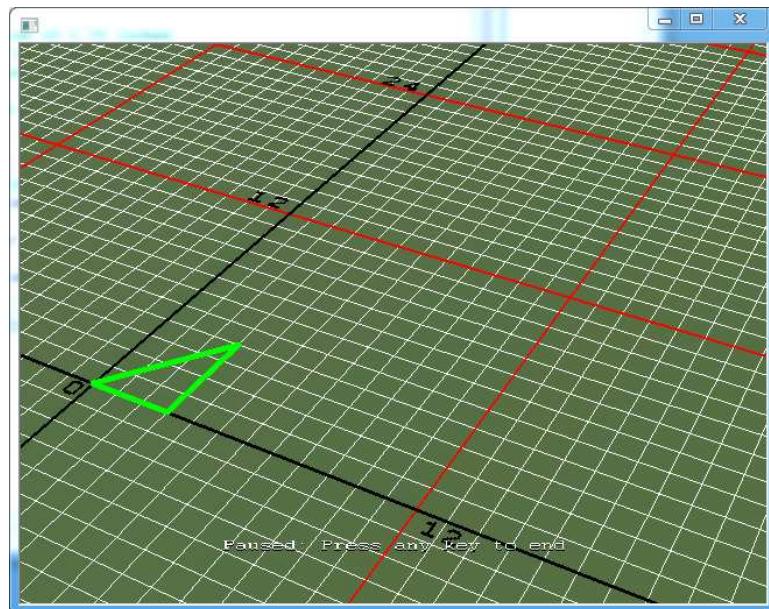


Figure B.5: The RoboSim scene with the robot trajectory of a right triangle from Program B.3.

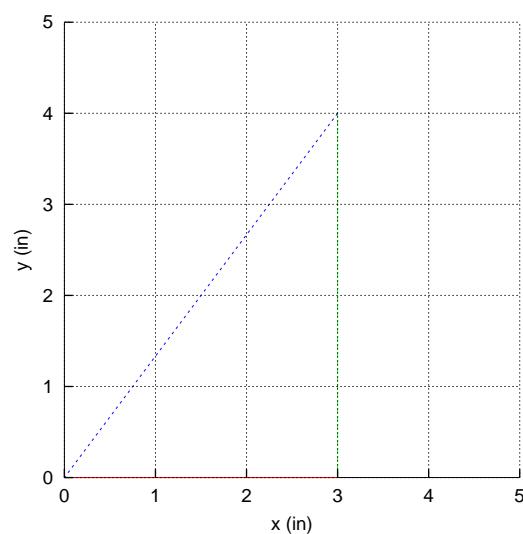


Figure B.6: The plot for the right triangle traveled by the robot from Program B.3.

## B.1. Move a Linkbot-I in a Coordinate System

displays a plot in a square box where the ranges for x and y are the same. The plot generated by Program B.3 is shown in Figure B.6. Toggle the 'r' key in the RoboSim GUI to get a clear view of the right triangle traced by the movement of the virtual Linkbot-I, as Figure B.5 shows.

 Do Exercise 5 on page 278.

Unlike the member function **drivexyTo()** moving to the absolute location (x, y) in the x and y coordinate system, the member function **drivexy()** drive the Linkbot-I by x and y relative to its current position in the x and y coordinate system. The syntax of the member function **drivexy()** is as follows.

```
robot.drivexy(x, y, radius, trackwidth);
```

Programs **drivexyto2.ch** and **drivexy2.ch**, distributed along with other sample programs, demonstrate the differences between the member functions **drivexyTo()** and **drivexy()**.

 Do Exercise 6(b) on page 278.

### B.1.1 Summary

1. Call the **CLinkbotI** member function

```
robot.drivexyTo(x, y, radius, trackwidth);
```

to drive a Linkbot-I from one point to another in an x and y coordinate system. This function works in RoboSim only.

2. Call the **CLinkbotI** member function

```
robot.drivexy(x, y, radius, trackwidth);
```

to drive a Linkbot-I by x and y relative to its current position in the x and y coordinate system.

3. Call the **CLinkbotI** member function

```
robot.getxy(x, y);
```

to obtain the position of a Linkbot-I in an x and y coordinate system. This function works in RoboSim only.

4. Call the **CPlot** member function

```
plot.point(x, y);
```

to plot a point.

5. Call the **CPlot** member function

```
plot.line(x1, y1, x2, y2);
```

to plot a straight line between  $(x_1, y_1)$  and  $(x_2, y_2)$ .

6. Call the **CPlot** member function

```
plot.sizeRatio(ratio);
```

to set the aspect ratio of a plot.

7. Call the function

```
sqrt(x);
```

to find the square root of a number.

## B.1. Move a Linkbot-I in a Coordinate System

### B.1.2 Terminology

**robot.drivexyTo()**, **robot.drivexy()**, **robot.getxy()**, **plot.point()**, **plot.line()**, **plot.sizeRatio()**, aspect ratio, **sqr()**.

### B.1.3 Exercises

1. Write a program `drivexyto3.ch`, similar to Program B.1, to drive a Linkbot-I from (0, 0) to (0, 8). Run this program to simulate the motion of the robot in RoboSim.

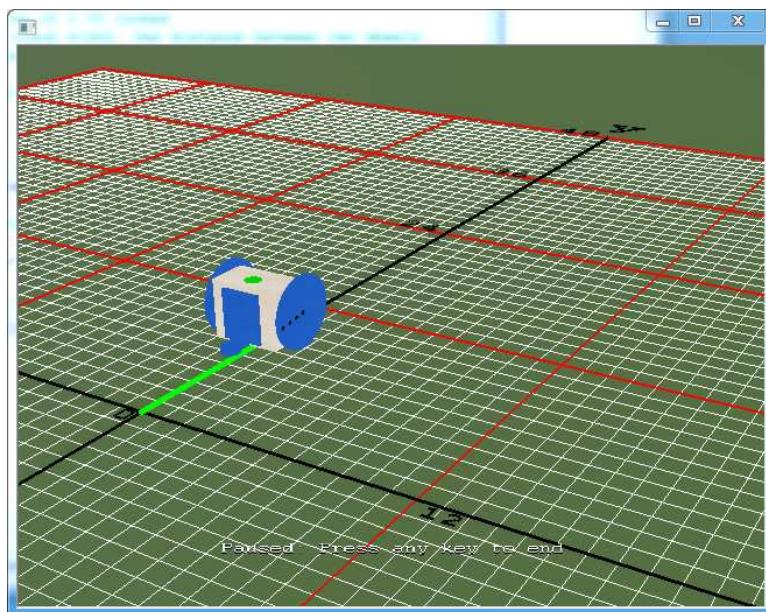


Figure B.7: Moving a virtual Linkbot-I along the y-axis from (0, 0) to (0, 8).

2. Write a program `drivexyto4.ch` to drive a Linkbot-I from (0, 0) to (6, 0). Run this program to simulate the motion of the robot in RoboSim.

## Appendix B. Moving Robots in a Coordinate System in RoboSim

### B.1. Move a Linkbot-I in a Coordinate System

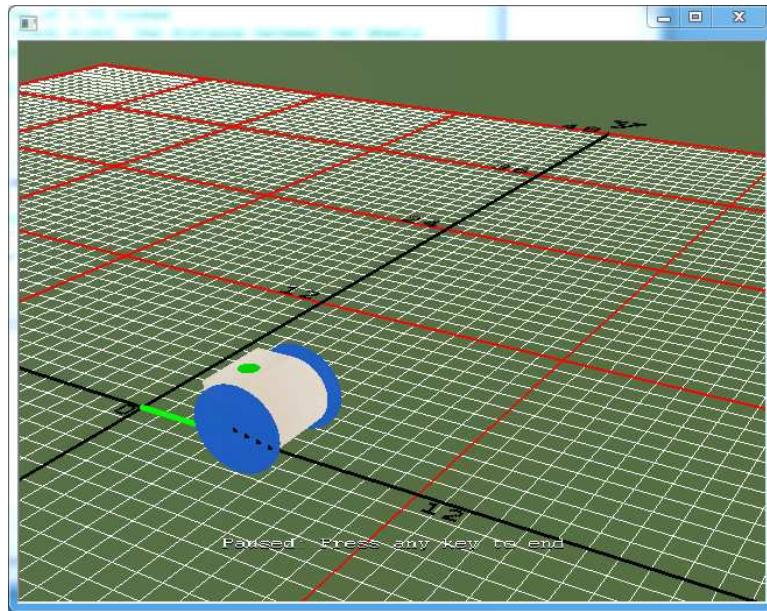


Figure B.8: Moving a virtual Linkbot-I along the x-axis from (0, 0) to (6, 0).

3. Write a program `drivexyto5.ch` to drive a virtual Linkbot-I in RoboSim from (0, 0) to (6, 8).

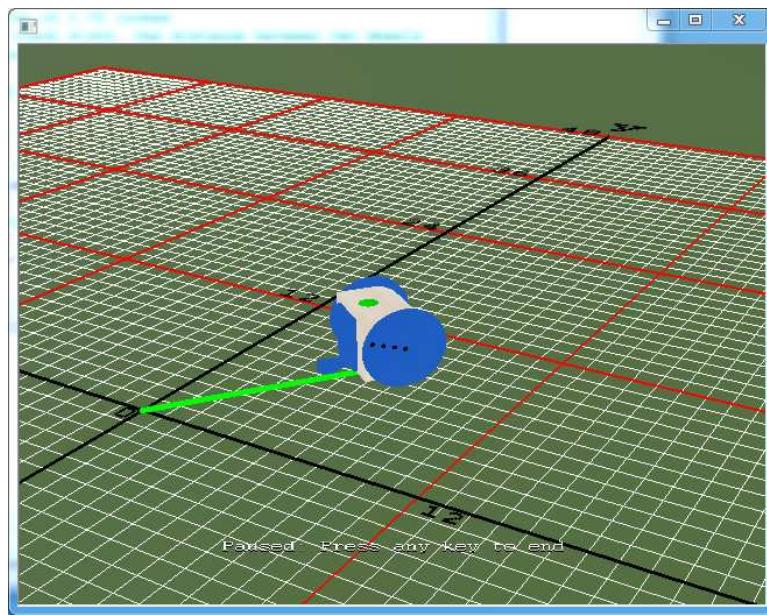


Figure B.9: Moving a virtual Linkbot-I from (0, 0) to (6, 8).

4. Write a program `points2.ch`, based on Program B.2, to drive a virtual Linkbot-I in RoboSim from (0, 0) to the following multiple points (-12, -5.5), (-24, -30), (-36, -10), and (-48, -5). Use `plot.point()` to plot the individual points. How does this graph relate to the graph generated by Program B.2?

## B.1. Move a Linkbot-I in a Coordinate System

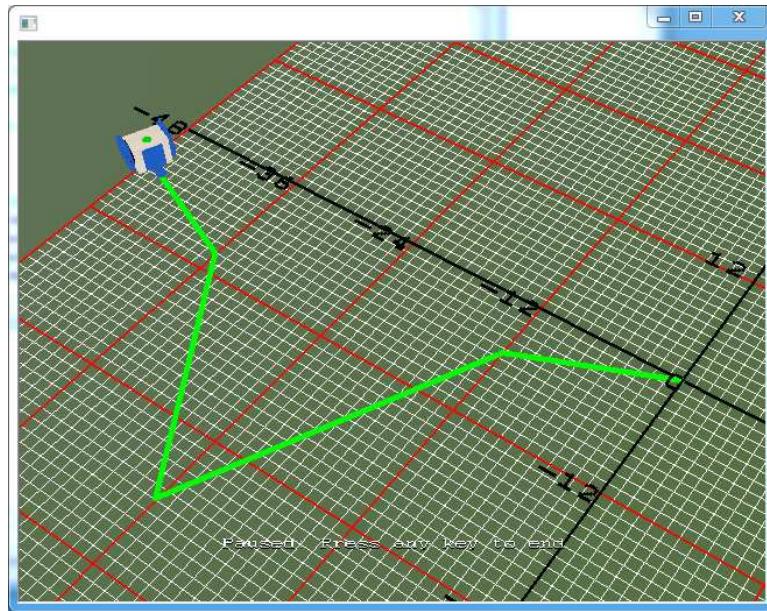


Figure B.10: The RoboSim scene with the robot trajectory for program `points2.ch`

5. Write a program `righttriangle2.ch`, based on Program B.3, to drive a virtual Linkbot-I in RoboSim from  $(0, 0)$ , to  $(-6, 0)$ , then to  $(-6, 8)$ , and back to  $(0, 0)$ . Calculate the length of the hypotenuse for this triangle, and use `plot.line()` and `plot.sizeRatio()` to plot the right triangle. How does this graph relate to the graph generated by Program B.3?

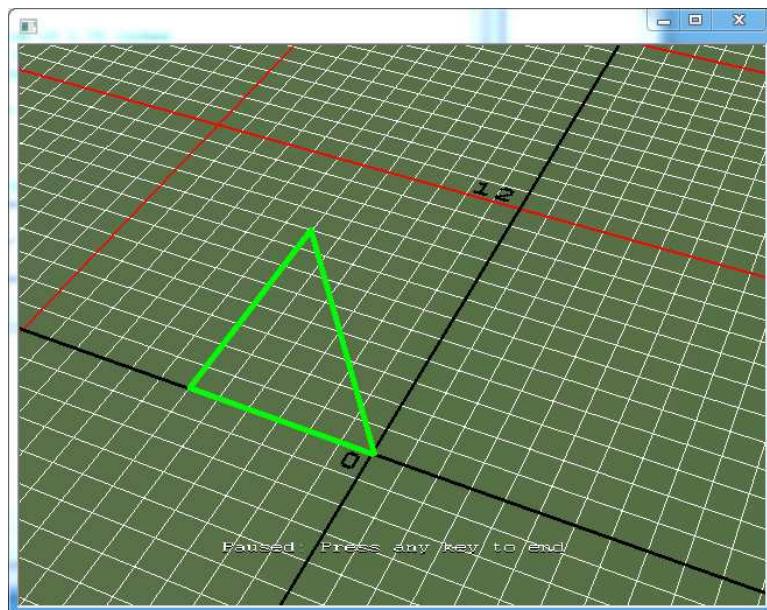


Figure B.11: The RoboSim scene with the robot trajectory for program `righttriangle2.ch`

6. Move a Linkbot-I from I from  $(0, 0)$  to  $(12, 10)$ , then to  $(7, 24)$ . Use `getxy()` to get the x and y coordinates of the robot when the robot is driven from one position to the other.

## B.2. Move a Linkbot-I Along a Trajectory

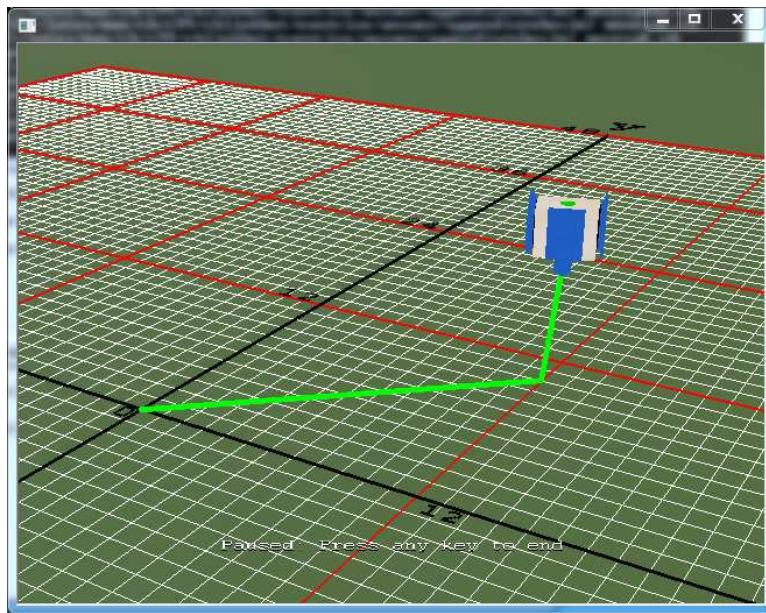


Figure B.12: The RoboSim scene with the robot trajectories for programs `drivexyto6.ch` and `drivexy6ch`

- (a) Write a program `drivexyto6.ch` using the member function `drivexyTo()`.
- (b) Write a program `drivexy6.ch` using the member function `drivexy()`.

## B.2 Move a Linkbot-I Along a Trajectory

A virtual Linkbot-I can also be programmed to drive along the trajectory based on a function or expression, such as a polynomial curve. In order to achieve this effect, the Linkbot must travel to many more points, with shorter distances between these points. Moving a Linkbot along a trajectory specified by a function can be accomplished by the member function `drivexyToFunc()`. The syntax of the member function `drivexyToFunc()` is as follows.

```
robot.drivexyToFunc(x0, xf, num, func, radius, trackwidth);
```

This member function drives a Linkbot-I following the trajectory specified by the function defined as `func()` in the range  $[x_0, xf]$  using `num` points. The last two arguments specify the radius of the two wheels and the track width of the robot.

Program B.4 drives a virtual Linkbot-I along the trajectory of a parabola in a coordinate system. Before running Program B.4, set the initial position of the Linkbot-I in the RoboSim GUI to  $(-6, 5.5)$ .

## B.2. Move a Linkbot-I Along a Trajectory

```

/* File: drivexytoFunc.ch
Note: This program uses drivexyToFunc() available in RoboSim only.
Set the initial position (x, y) in RoboSim GUI to (-6, 5.5) for the robot.

A robot moves along a polynomial curve y = 0.5(x+5)(x-5) for x from -6 to 6.
Plot the polynomial y for x from -6 to 6 with 500 points.
The range of x-axis is from -12 to 12.
The range of y-axis is from -15 to 12.
The tics range for x and y axes is 1. */
#include <chplot.h> /* for CPlot */
#include <clinkbot.h> /* for CLinkbotI */

double func(double x) {
    return 0.5*(x+5)*(x-5);
}

CPlot plot;
CLinkbotI robot;
double radius = 1.75;      // radius of 1.75 inches
double trackwidth = 3.69;  // the track width, the distance between two wheels
double x, y;              // x and y coordinates

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* move the robot along the polynomial curve */
robot.drivexyToFunc(-6, 6, 60, func, radius, trackwidth);

/* plot the polynomial curve */
plot.mathCoord();
plot.title("y = 0.5(x+5)(x-5)");
plot.label(PLOT_AXIS_X, "x");
plot.label(PLOT_AXIS_Y, "y");
plot.axisRange(PLOT_AXIS_X, -12, 12);
plot.axisRange(PLOT_AXIS_Y, -15, 12);
plot.ticsRange(PLOT_AXIS_X, 1);
plot.ticsRange(PLOT_AXIS_Y, 1);
plot.func2D(-6, 6, 500, func);
plot.plotting();

```

Program B.4: Moving a Linkbot-I to follow a polynomial curve using **drivexyToFunc()**.

Recall that a parabola is a graph of a quadratic equation. A quadratic equation is a second-degree polynomial equation of the form

$$y = ax^2 + bx + c$$

where  $a \neq 0$ . Graphs of parabolas are smooth, cup-shaped symmetric curves with a top or bottom point where the curve changes direction, called a vertex. If  $a > 0$ , the curve opens up and the  $y$ -coordinate of the vertex is the minimum value of  $y$ . If  $a < 0$ , it opens down and the  $y$ -coordinate is the maximum value of  $y$ . The quadratic equation in Program B.4 is

$$y = 0.5(x + 5)(x - 5) = 0.5x^2 - 25$$

Since  $a > 0$  in this case, the curve opens up.

## B.2. Move a Linkbot-I Along a Trajectory

In Program B.4 a function `func()` is used to define this quadratic equation, which calculates the  $y$ -coordinate for each point the virtual Linkbot-I travels to on the parabola. The function `func()` is defined as

```
/* define the function func() */
double func(double x) {
    return 0.5*(x+5)*(x-5);
}
```

This function takes in an argument of type **double**, which is the  $x$ -coordinate of a point. The function returns a value of type **double**, which is the corresponding  $y$ -coordinate. Since `func()` is defined before it is used in Program B.4, a function prototype is not needed.

After the virtual Linkbot-I is connected and reset to the zero position, the line

```
robot.drivexyToFunc(-6, 6, 60, func, radius, trackwidth);
```

drives the robot for  $x$  from  $-6$  to  $6$  along the parabola with 60 points. When  $x$  is  $-6$  or  $6$ ,  $y$  is  $5.5$ . Therefore, the robot drives from the coordinate  $(-6, 5.5)$  to  $(6, 5.5)$ . Figure B.13 shows the resulting smooth parabolic trajectory.

To plot the parabolic trajectory, the **CPlot** member functions **axisRange()**, **ticsRange()**, and **func2D()** are used. An **axis range** describes the beginning and ending numbers shown on each axis. The axis range can be set by the member function **axisRange()**, which has the general syntax

```
plot.axisRange(axis, minimum, maximum);
```

The argument `axis` specifies either the  $x$  or  $y$  axis of the plot. The arguments `minimum` and `maximum` specify the start and end points of the range.

A **tick mark** is the interval between units on each axis. This interval can be set by the member function **ticsRange()**, which has the general syntax

```
plot.ticsRange(axis, incr);
```

Like the member function **axisRange()**, the first argument `axis` specifies either the  $x$  or  $y$  axis. The second argument `incr` gives the increment between tick marks.

The relation represented in a function can be plotted by using the **CPlot** member function **func2D()**. The syntax of this function is

```
plot.func2D(x0, xf, num, func);
```

This member function will plot a function defined as `func()` in the range  $[x0, xf]$  using `num` points.

In Program B.4, the following lines

```
plot.axisRange(PLOT_AXIS_X, -12, 12);
plot.axisRange(PLOT_AXIS_Y, -15, 12);
plot.ticsRange(PLOT_AXIS_X, 1);
plot.ticsRange(PLOT_AXIS_Y, 1);
plot.func2D(-6, 6, 500, func);
```

plots the trajectory of the virtual Linkbot-I for the ranges  $[-12, 12]$  and  $[-15, 12]$  on the  $x$  and  $y$  axes, with an increment of 1 between tick marks. 500 points are used to plot the curve, since plotting with **CPlot** member functions requires more accuracy. Figure B.14 shows the generated graph.

 Do Exercise 1 on page 284.

Moving a Linkbot along a trajectory specified by an expression in terms of a variable can also be accomplished by the member function **drivexyToExpr()**. The syntax of the member function **drivexyToExpr()** is as follows.

## Appendix B. Moving Robots in a Coordinate System in RoboSim

### B.2. Move a Linkbot-I Along a Trajectory

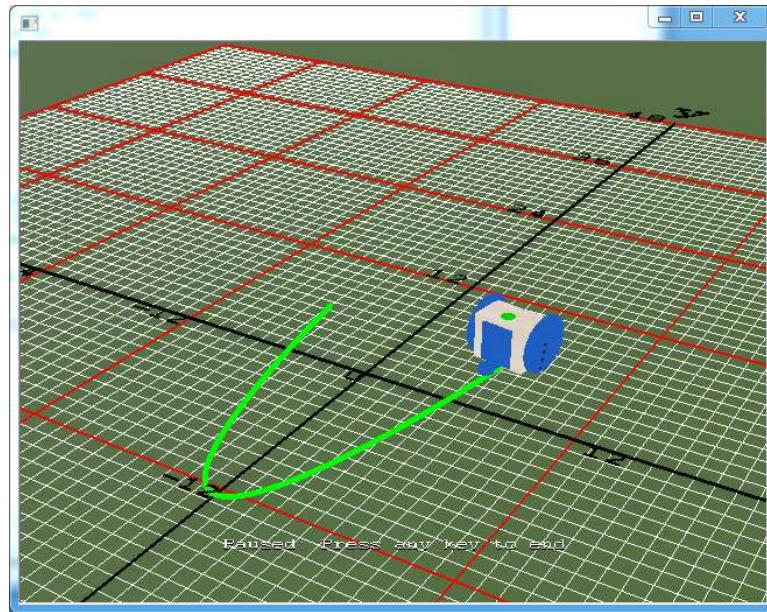


Figure B.13: The RoboSim scene with the robot trajectory of a polynomial from Programs B.4, B.5, and B.13.

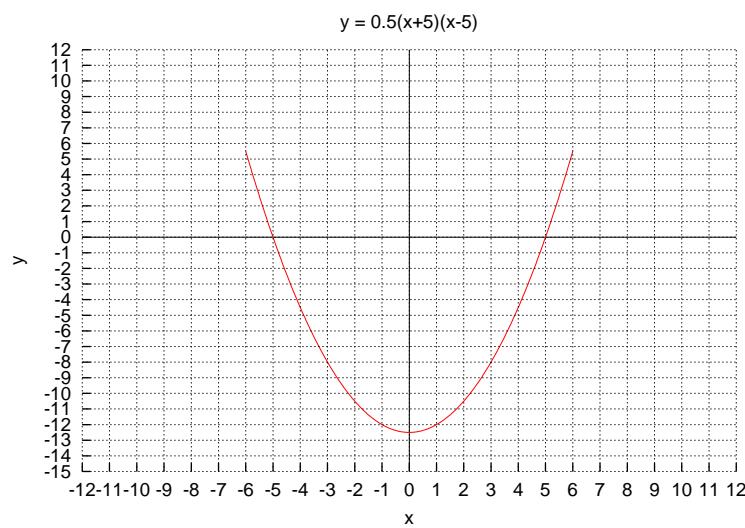


Figure B.14: The plot for the polynomial traveled by the robot from Programs B.4, B.5, and B.13.

## B.2. Move a Linkbot-I Along a Trajectory

```
robot.drivexyToExpr(x0, xf, num, expr, radius, trackwidth);
```

This member function drives a Linkbot-I based on an expression with the variable x, for x from x0 to xf with num number of points. The expression t expr should be a valid Ch expression in terms of the variable x. The last two arguments specify the radius of the two wheels and track width of the robot.

Program B.5 is the same as Program B.4, except that it uses the statement

```
robot.drivexyToExpr(-6, 6, 60, "0.5*(x+5)*(x-5)", radius, trackwidth);
```

to drive the robot for x from -6 to 6 along the parabola with 60 points using the expression "0.5\*(x+5)\*(x-5)", instead of using the member function **drivexyToFunc()**. The output from Program B.5 is the same as that from Program B.4, as shown in Figures B.13 and B.14.

```
/* File: drivexytoexpr.ch
Note: This program uses drivexyToExpr() available in RoboSim only.
Set the initial position (x, y) in RoboSim GUI to (-6, 5.5) for the robot.

A robot moves along a polynomial curve y = 0.5(x+5)(x-5) for x from -6 to 6.
Plot the polynomial y for x from -6 to 6 with 500 points.
The range of x-axis is from -12 to 12.
The range of y-axis is from -15 to 12.
The tics range for x and y axes is 1. */
#include <chplot.h> /* for CPlot */
#include <linkbot.h> /* for CLinkbotI */

CPlot plot;
CLinkbotI robot;
double radius = 1.75; // radius of 1.75 inches
double trackwidth = 3.69; // the track width, the distance between two wheels
double x, y; // x and y coordinates

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* move the robot along the polynomial curve */
robot.drivexyToExpr(-6, 6, 60, "0.5*(x+5)*(x-5)", radius, trackwidth);

/* plot the polynomial curve */
plot.mathCoord();
plot.title("y = 0.5(x+5)(x-5)");
plot.label(PLOT_AXIS_X, "x");
plot.label(PLOT_AXIS_Y, "y");
plot.axisRange(PLOT_AXIS_X, -12, 12);
plot.axisRange(PLOT_AXIS_Y, -15, 12);
plot.ticsRange(PLOT_AXIS_X, 1);
plot.ticsRange(PLOT_AXIS_Y, 1);
plot.expr(-6, 6, 500, "0.5*(x+5)*(x-5)");
plot.plotting();
```

Program B.5: Moving a Linkbot-I to follow a polynomial curve using **drivexyToExpr()**.

 Do Exercise 2 on page 285.

## B.2. Move a Linkbot-I Along a Trajectory

**B.2.1 Summary**

1. Call the **CLinkbotI** member function

```
robot.drivexyToFunc(x0, xf, num, func, radius, trackwidth);
```

drives a Linkbot-I based on a function `func()`, for x from `x0` to `xf` with `num` number of points.

2. Call the **CLinkbotI** member function

```
robot.drivexyToExpr(x0, xf, num, expr, radius, trackwidth);
```

drives a Linkbot-I based on an expression `expr` in terms of the variable `x`, for x from `x0` to `xf` with `num` number of points.

3. Call the **CPlot** member function

```
plot.axisRange(axis, minimum, maximum);
```

to set the range of an axis in a plot.

4. Call the **CPlot** member function

```
plot.ticsRange(axis, incr);
```

to set the increment between tick marks for a plot.

5. Call the **CPlot** member function

```
plot.func2D(x0, xf, num, func);
```

to plot the function `func()` for x in the range `[x0, xf]` using `num` points.

**B.2.2 Terminology**

`robot.drivexyToFunc()`, `robot.drivexyToExpr()`, `plot.axisRange()`, `plot.ticsRange()`, `plot.func2D()`, axis range, tick mark.

**B.2.3 Exercises**

1. Write a program `drivexytofunc2.ch` using the member function `drivexyToFunc()`, based on Program B.4, that drives a virtual Linkbot-I along the trajectory of a parabola from (-6, -5.5) to (6, -5.5). This parabola will open downward, with vertex at (0, 12.5). Use the **CPlot** member functions `axisRange()`, `ticsRange()`, and `func2D()` to generate a plot of the virtual Linkbot-I's trajectory.

## B.3. Trace the Positions of a Linkbot-I

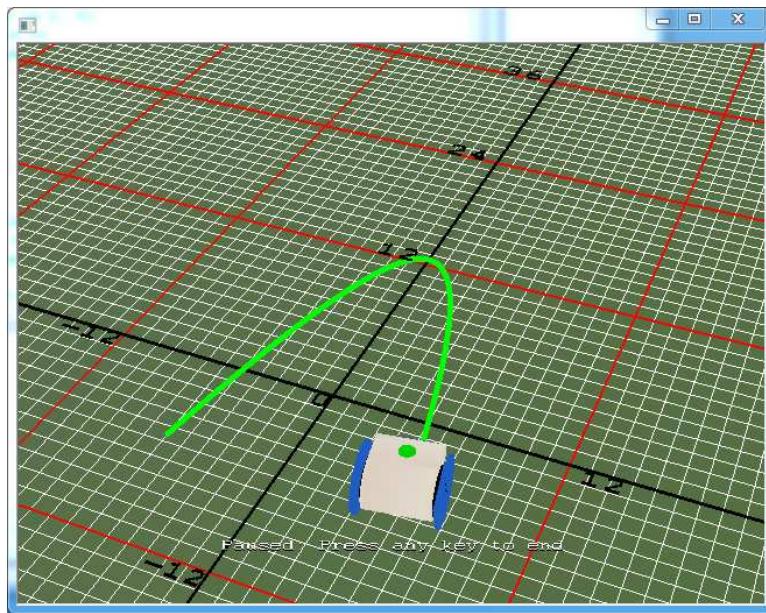


Figure B.15: The RoboSim scene with the robot trajectory for program `drivexytofunc2.ch`

2. Write a program `drivexytoexpr2.ch`, using the member function **`drivexyToExpr()`**, based on Program B.5, that drives a virtual Linkbot-I along the trajectory of a parabola from (-6, -5.5) to (6, -5.5), as shown in Figure B.15.

### B.3 Trace the Positions of a Linkbot-I

When the check box “Enable Robot Position Tracing”, as shown in Figure 4.1 on page 48, is selected on the RoboSim GUI, the trajectory for each Linkbot will be traced and displayed on the RoboSim scene. In some applications, it will be desirable to only trace certain parts of a trajectory. This can be accomplished by the member functions **`traceOn()`** and **`traceOff()`**. The member function **`traceOn()`** turns on tracing for a robot whereas **`traceOff()`** turns off tracing. The syntaxes of the member functions **`traceOn()`** and **`traceOff()`** are as follows.

```
robot.traceOn();
robot.traceOff();
```

These two member functions inside a program will overwrite the setting for the tracing selected on the RoboSim GUI.

Program B.6 demonstrates how to draw two parallel lines using a Linkbot-I as shown in Figure B.16. The motion and tracing of lines are handled by the following code segment in Program B.6.

```
robot.traceOn();
robot.drivexyTo(6, 5, radius, trackwidth); // line from (0, 0) to (6, 5)

robot.traceOff();
robot.drivexyTo(0, 10, radius, trackwidth); // line from (6, 5) to (0, 10)

robot.traceOn();
robot.drivexyTo(6, 15, radius, trackwidth); // line from (0, 10) to (6, 15)
```

## B.3. Trace the Positions of a Linkbot-I

Before the robot is driven from (0, 0) to (6, 5), the tracing is turned on to draw the first line. For the movement from (6, 5) to (0, 10), the tracing is turned off. Before the robot is driven from (0, 10) to (6, 15), the tracing is turned on again to draw the second line, which is parallel to the first line.

```
/* File: traceon.ch
   Turn trace on and off with two Linkbot-Is
   Set the initial position (x, y) in RoboSim GUI to (0, 0) for robot. */
#include <linkbot.h>
CLinkbotI robot;
double radius = 1.75;           // radius of 1.75 inches
double trackwidth = 3.69;        // the track width, the distance between two wheels

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZeroNB();

robot.traceOn();
robot.drivexyTo(6, 5, radius, trackwidth); // line from (0, 0) to (6, 5)

robot.traceOff();
robot.drivexyTo(0, 10, radius, trackwidth); // line from (6, 5) to (0, 10)

robot.traceOn();
robot.drivexyTo(6, 15, radius, trackwidth); // line from (0, 10) to (6, 15)
```

Program B.6: Drawing two parallel lines from (0, 0) to (6, 5) and from (0, 10) to (6, 15).

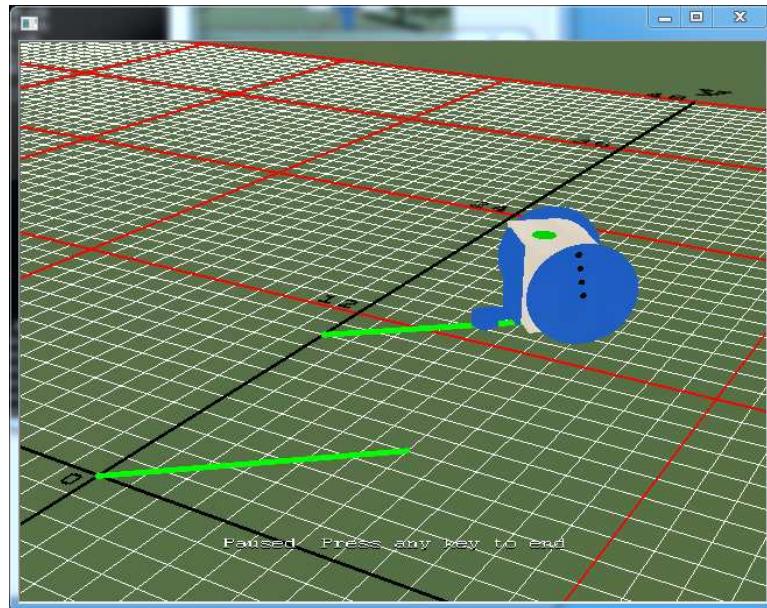


Figure B.16: The RoboSim scene with the robot trajectory from Programs B.6 and B.7.

Do Exercise 1, on 287.

## B.4. Record the Positions of a Linkbot-I

**B.3.1 Summary**

1. Call the **CLinkbotI** member function

```
robot.traceOn();
```

to turn on tracing of positions for a Linkbot-I.

2. Call the **CLinkbotI** member function

```
robot.traceOff();
```

to turn off tracing of positions for a Linkbot-I.

**B.3.2 Terminology**

**robot.traceOn()**, **robot.traceOff()**, and trace the trajectory of a robot.

**B.3.3 Exercises**

1. Write a program `traceon3.ch` to trace the letter 'A' in RoboSim as shown in Figure B.17. The horizontal line for the letter 'A' can be drawn from the point  $(-2.5, 5)$  to the point  $(2.5, 5)$ .

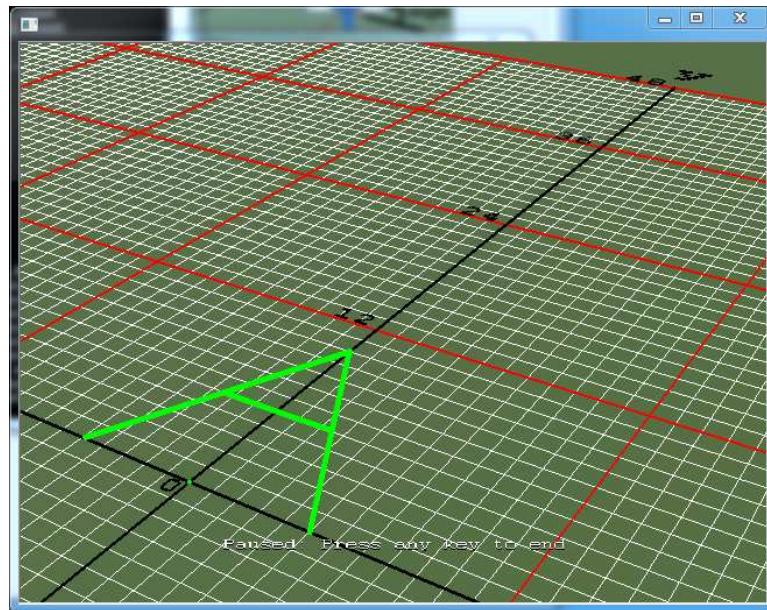


Figure B.17: Moving a virtual Linkbot-I to trace a letter 'A'.

## B.4 Record the Positions of a Linkbot-I

We learned in Section 9.1.6 on how to record and plot the distances versus time for a Linkbot. It is also possible to record and plot the positions  $(x, y)$  in a coordinate system for a Linkbot-I in RoboSim. To

## B.4. Record the Positions of a Linkbot-I

record the position data in RoboSim, we use the two **CLinkbotI** member functions **recordxyBegin()** and **recordxyEnd()**.

The general syntax for the function **recordxyBegin()** is

```
robot.recordxyBegin(xdata, ydata, timeInterval);
```

The first and second arguments **xdata** and **ydata** contain the data points for positions (x, y) of the Linkbot-I. They are variables of type **robotRecordData.t**. The reason for this is the same as why the **timedata** and **distances** arguments are of type **robotRecordData.t** in Program B.7. The third argument **timeInterval** is the time interval between position readings. The minimum possible value for **timeInterval** is 0.05 seconds.

The general syntax for the function **recordxyEnd()** is

```
robot.recordxyEnd(numDataPoints);
```

The argument **numDataPoints** is the total number of data points that were recorded while the Linkbot-I was moving.

Program B.6 draws two parallel lines as shown in Figure B.16. Based on Program B.6, Program B.7 records the positions (x, y) for the Linkbot-I and plots the acquired data using the Ch plotting member functions with the output shown in Figure B.18.

## B.4. Record the Positions of a Linkbot-I

```

/* File: recordxy.ch
   Trace and record the x and y positions, plot the acquired data
   Set the initial position (x, y) in RoboSim GUI to (0, 0) for robot. */
#include <linkbot.h>
#include <chplot.h>
CLinkbotI robot;
double radius = 1.75;           // radius of 1.75 inches
double trackwidth = 3.69;        // the track width, the distance between two wheels
double timeInterval = 0.1;       // time interval in 0.1 second
int numDataPoints;              // number of data points recorded
robotRecordData_t xdata, ydata; // recorded x and y positions
CPlot plot;                     // plotting class

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();

/* begin recording x and y positions */
robot.recordxyBegin(xdata, ydata, timeInterval);

robot.traceOn();
robot.drivexyTo(6, 5, radius, trackwidth); // line from (0, 0) to (6, 5)

robot.traceOff();
robot.drivexyTo(0, 10, radius, trackwidth); // line from (6, 5) to (0, 10)

robot.traceOn();
robot.drivexyTo(6, 15, radius, trackwidth); // line from (0, 10) to (6, 15)

/* end recording x and y positions */
robot.recordxyEnd(numDataPoints);

/* plot the data */
plot.mathCoord();
plot.title("Position");
plot.label(PLOT_AXIS_X, "X (inches)");
plot.label(PLOT_AXIS_Y, "Y (inches)");
plot.axisRange(PLOT_AXIS_X, -5, 15);
plot.axisRange(PLOT_AXIS_Y, 0, 20);
plot.data2DCurve(xdata, ydata, numDataPoints);
int datanum = 0, pointType = 7, pointSize = 1;
plot.plotType(PLOT_PLOTTYPE_POINTS, datanum);
plot.pointType(datanum, pointType, pointSize, "green");
plot.sizeRatio(1);
plot.plotting();

```

Program B.7: Plotting the positions of a Linkbot-I.

Similar to Program 9.6, we begin the recording of positions when the tracing of the trajectory is turned on. The statement

```
robot.recordxyBegin(xdata, ydata, timeInterval);
```

starts recording the positions of the Linkbot-I every 0.1 second. Only the positions displayed on the traced trajectory will be recorded. After the Linkbot stops moving, the statement

```
robot.recordxyEnd(JOINT1, numDataPoints);
```

stops recording the positions for the traced trajectory.

## B.4. Record the Positions of a Linkbot-I

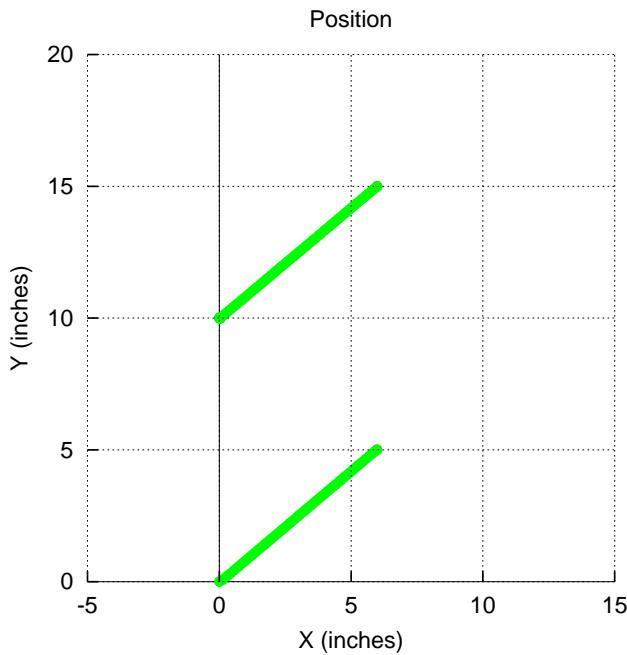


Figure B.18: The plot for the positions Program B.7.

By default, adjacent data points in a plot are connected each other to form a line. To plot the positions of the traced trajectory, we need to plot the position data using the point type for the plot. This is accomplished by the code fragment below.

```
int datanum = 0, pointType = 7, pointSize = 1;
plot.plotType(PLOT_PLOTTYPE_POINTS, datanum);
plot.pointType(datanum, pointType, pointSize, "green");
```

The member function **plotType()** uses the macro **PLOT\_PLOTTYPE\_POINTS** to set the plot type to the point type. The member function **pointType()** sets the type, size, and color for points.

Do Exercise 1 on page 291.

#### B.4.1 Summary

1. Call the **CLinkbotI** member function

```
robot.recordxyBegin(xdata, ydata, timeInterval);
```

to start recording positions (x, y) of the traced trajectory for a Linkbot-I in a specified interval between position readings.

2. Call the **CLinkbotI** member function

```
robot.recordxyEnd(id, num);
```

to stop recording positions of the traced trajectory for a Linkbot-I.

3. Call the plotting member function

## B.5. Create an Obstacle Course with Points, Lines, and Text on a RoboSim Scene

```
plot.plotType(PLOT_PLOTTYPE_POINTS, datanum);
```

to plot points for the data set `datanum`.

4. Call the plotting member function

```
plot.pointType(datanum, pointType, pointSize, "green");
```

to change the type, size, and color of the points created by the data set `datanum`.

### B.4.2 Terminology

`robot.recordxyBegin()`, `robot.recordxyEnd()`, `plot.plotType()`, `plot.pointType()`, and record positions.

### B.4.3 Exercises

1. Based on the program `traceon3.ch` developed in Exercise 1 on page 291, write a program `recordxy3.ch` to record and plot the traced trajectory with the letter 'A' as shown in Figure B.19.

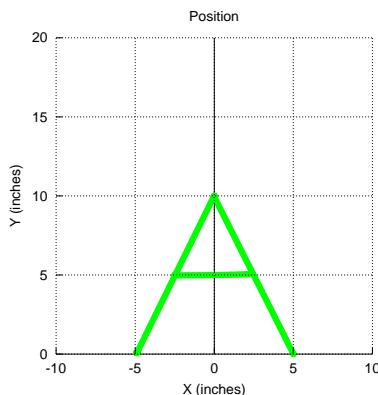


Figure B.19: A plot generated by the program `recordxy3.ch`.

## B.5 Create an Obstacle Course with Points, Lines, and Text on a RoboSim Scene

Points, lines, and text can be drawn on the RoboSim scene to create an obstacle course. The member function `point()` of the **CLinkbotI** class can draw a point on the RoboSim scene. The syntax of the member function `point()` is as follows.

```
robot.point(x, y, z, pointsize, "red");
```

The first three arguments specify the location  $(x, y, z)$  at which a point will be drawn. The fourth argument specifies the size of the point in an integer starting from 1. The last argument specifies the color of the point using a color name in a string, such as "`red`" for red.

The member function `line()` can draw a straight line between the two points  $(x_1, y_1, z_1)$  and  $(x_2, y_2, z_2)$  on the RoboSim scene. The syntax of the member function `line()` is as follows.

## B.5. Create an Obstacle Course with Points, Lines, and Text on a RoboSim Scene

```
robot.line(x1, y1, z1, x2, y2, z2, linewidth, "red");
```

The first six arguments specify the two points  $(x_1, y_1, z_1)$  and  $(x_2, y_2, z_2)$ . The seventh argument specifies the width of the point in an integer starting from 1. The last argument specifies the color of the line using a color name in a string, such as "red" for red.

The member function **text()** draws a text on the RoboSim scene. The syntax of the member function **line()** is as follows.

```
robot.text(x, y, z, "text");
```

The first three arguments specify the location  $(x, y, z)$  at which the text will be drawn and centered. The last argument specifies the text in a string.

Program B.8 demonstrates how to use the member functions **point()**, **line()**, and **text()**. The program uses the member function **point()** to draw five points at  $(-9, 9, 0)$ ,  $(-3, 9, 0)$ ,  $(3, 9, 0)$ ,  $(9, 9, 0)$ , and  $(15, 9, 0)$  with the point size of 1, 2, 3, 4, 5 in the red, green, blue, purple, and aqua colors, respectively, as shown in Figure B.20. For example, the function call

```
robot.point(-9, 9, 0, 1, "red");
```

draws a point at  $(-9, 9, 0)$  with the point size 1 in the red color. These points are labeled by the member function **text()**. For example, the function call

```
robot.text(-9, 9, 2.5, "(-9, 9)");
```

draws the text  $(-9, 9)$  at the point  $(-9, 9, 2.5)$ . The program also draws four lines of different widths and colors. For example, the function call

```
robot.line(-9, 18, 0, -3, 18, 0, 1, "red");
```

draws a straight line between the two points  $(-9, 18, 0)$  and  $(-3, 18, 0)$  with the line width of 1 in the red color. The RoboSim scene in Figure B.20 without a robot is accomplished by pressing the 'r' key.

## B.5. Create an Obstacle Course with Points, Lines, and Text on a RoboSim Scene

```

/* File: pointlinetext.ch
Note: This program marks points by point() and text(),
      lines by line() available only in RoboSim. */
#include <clinkbot.h> /* for CLinkbotI */
CLinkbotI robot;

/* connect to the paired robot */
robot.connect();

/* mark points on the floor */
robot.point(-9, 9, 0, 1, "red");
robot.point(-3, 9, 0, 2, "green");
robot.point( 3, 9, 0, 3, "blue");
robot.point( 9, 9, 0, 4, "purple");
robot.point(15, 9, 0, 5, "aqua");

/* label the points */
robot.text(-9, 9, 2.5, "(-9,9)");
robot.text(-3, 9, 2.5, "(-3,9)");
robot.text( 3, 9, 2.5, "(3,9)");
robot.text( 9, 9, 2.5, "(9,9)");
robot.text(15, 9, 2.5, "(15,9)");

/* connect the points by lines of different widths and colors */
robot.line(-9, 18, 0, -3, 18, 0, 1, "red");
robot.line(-3, 18, 0, 3, 18, 0, 2, "green");
robot.line( 3, 18, 0, 9, 18, 0, 3, "blue");
robot.line( 9, 18, 0, 15, 18, 0, 4, "purple");

```

Program B.8: Drawing points, lines, and text on the RoboSim scene.

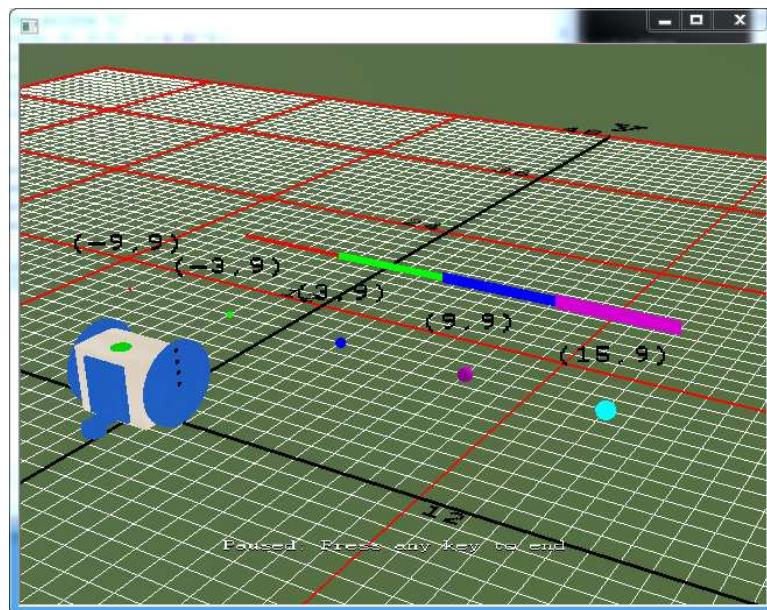


Figure B.20: The RoboSim scene with points, lines, and text, created by Program B.8.

Do Exercises 1 and 2 on 297.

## B.5. Create an Obstacle Course with Points, Lines, and Text on a RoboSim Scene

Program B.9 uses the member functions **point()**, **line()**, and **text()** to create an obstacle course in the RoboSim scene first. It then drives a robot through the specified points along the obstacle course. Finally, it displays the obstacle course in a separate plot. The robot placed at the origin (0, 0) will travel through these points (12, 5.5), (24, 30), (36, 10), and (48, 5), specified by the member function **point()** with the point size of 2 and in different colors . These points are labeled by the member function **text()**. The obstacle course in the blue color is created by the member function **line()**. The lines

```
/* drive the robot to specified points */
robot.drivexyTo(12, 5.5, radius, trackwidth);
robot.drivexyTo(24, 30, radius, trackwidth);
robot.drivexyTo(36, 10, radius, trackwidth);
robot.drivexyTo(48, 5, radius, trackwidth);
```

drive the robot through the specified points. The same points and lines are drawn in a Ch plot.

```
/* File: obstaclecourse.ch
Note: This program uses drivexyTo() to move a Linkbot-I to
multiple points in an obstacle course marked by point(), text(), and line().
Set the initial position (x, y) in RoboSim GUI to (0, 0) for the robot. */
#include <chplot.h> /* for CPlot */
#include <linkbot.h> /* for CLinkbotI */

CPlot plot;
CLinkbotI robot;
double radius = 1.75; // radius of 1.75 inches
double trackwidth = 3.69; // the track width, the distance between two wheels
double speed = 7; // the speed of the robot in inches per second

/* connect to the paired robot and move to the zero position */
robot.connect();

/* mark points on the floor */
robot.point(0, 0, 0, 5, "red");
robot.point(12, 5.5, 0, 5, "green");
robot.point(24, 30, 0, 5, "blue");
robot.point(36, 10, 0, 5, "purple");
robot.point(48, 5, 0, 5, "aqua");

/* label the points */
robot.text(12, 5.5, 0.5, "(12,5.5)");
robot.text(24, 30, 0.5, "(24,30)");
robot.text(36, 10, 0.5, "(36,10)");
robot.text(48, 5, 0.5, "(48,5)");

/* make obstacle course */
robot.line(-7.2, 0, 0, 9.777, 7.781, 0, 2, "blue");
robot.line(9.777, 7.781, 0, 23.733, 36.275, 0, 2, "blue");
robot.line(23.733, 36.275, 0, 37.75, 12.9, 0, 2, "blue");
robot.line(37.75, 12.9, 0, 48, 8.63, 0, 2, "blue");
robot.line(7.2, 0, 0, 14.223, 3.219, 0, 2, "blue");
robot.line(14.223, 3.219, 0, 24.267, 23.728, 0, 2, "blue");
robot.line(24.267, 23.728, 0, 34.25, 7.10, 0, 2, "blue");
robot.line(34.25, 7.10, 0, 48, 1.37, 0, 2, "blue");

/* move to the zero position */
robot.resetToZero();

/* set the speed for a two-wheel robot */
robot.setSpeed(speed, radius);
```

## B.5. Create an Obstacle Course with Points, Lines, and Text on a RoboSim Scene

```

/* move the robot to specified points */
robot.drivexyTo(12, 5.5, radius, trackwidth);
robot.drivexyTo(24, 30, radius, trackwidth);
robot.drivexyTo(36, 10, radius, trackwidth);
robot.drivexyTo(48, 5, radius, trackwidth);

/* plot the points and obstacle course */
plot.mathCoord();
plot.title("");
plot.label(PLOT_AXIS_X, "x (in)");
plot.label(PLOT_AXIS_Y, "y (in)");
/* mark poitns */
plot.point(0, 0);
plot.point(12, 5.5);
plot.point(24, 30);
plot.point(36, 10);
plot.point(48, 5);

/* make obstacle course */
plot.line(-7.2, 0, 9.77, 7.78);
plot.line(9.77, 7.78, 23.73, 36.28);
plot.line(23.73, 36.28, 36+1.75, 12.9);
plot.line(37.75, 12.9, 48, 8.63);
plot.line(7.2, 0, 14.22, 3.22);
plot.line(14.22, 3.22, 24.27, 23.73);
plot.line(24.27, 23.73, 36-1.75, 7.1);
plot.line(36-1.75, 7.1, 48, 1.37);
plot.axisRange(PLOT_AXIS_X, -10, 50); // set the x-axis range
plot.axisRange(PLOT_AXIS_Y, 0, 60); // set the y-axis range
plot.sizeRatio(1);
plot.plotting();

```

Program B.9: Moving a Linkbot-I through an obstacle course using **drivexyTo()**.

## B.5. Create an Obstacle Course with Points, Lines, and Text on a RoboSim Scene

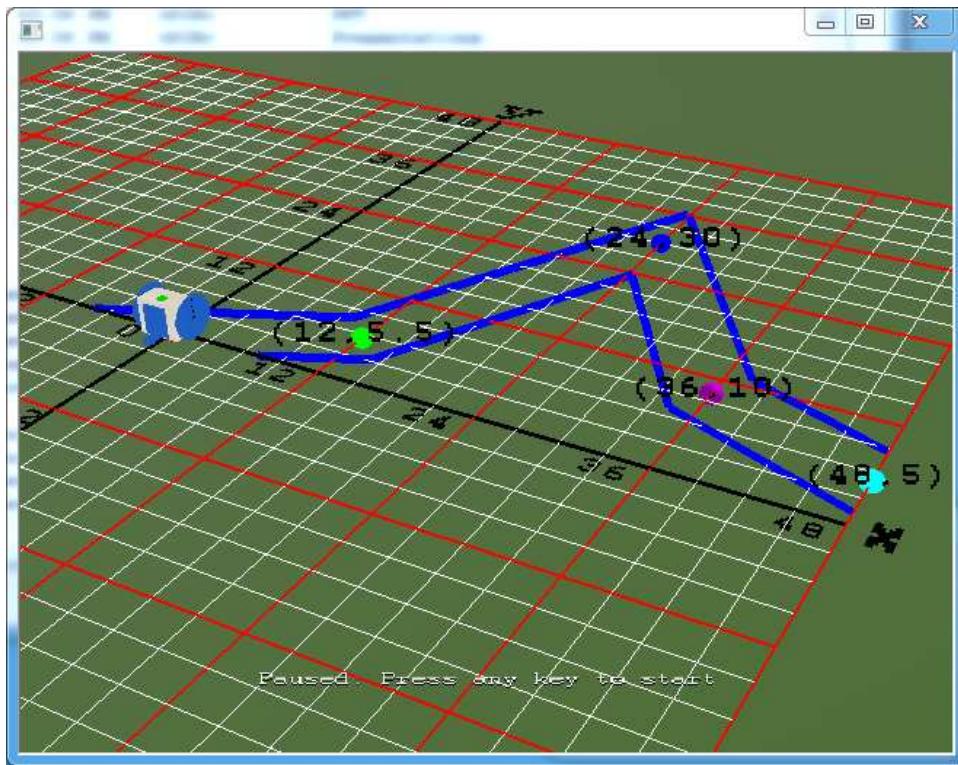


Figure B.21: The RoboSim scene with the obstacle course from Program B.9.

Do Exercises 3 and 4 on 297.

### B.5.1 Summary

1. Call the **CLinkbotI** member function

```
robot.point(x, y, z, pointsize, "red");
```

to plot a point on the RoboSim scene.

2. Call the **CLinkbotI** member function

```
plot.line(x1, y1, z1, x2, y2, z2, linewidth, "red");
```

to plot a straight line between the two points  $(x_1, y_1, z_1)$  and  $(x_2, y_2, z_2)$  on the RoboSim scene.

3. Call the **CLinkbotI** member function

```
plot.text(x, y, z, "text");
```

to plot a text centered at  $(x, y, z)$  on the RoboSim scene.

### B.5.2 Terminology

**robot.point()**, **robot.line()**, **robot.text()**.

## B.5. Create an Obstacle Course with Points, Lines, and Text on a RoboSim Scene

**B.5.3 Exercises**

1. Write a program `pointlinetext2.ch`, based on Program B.8, draw an obstacle course as shown in Figure B.22. The size for points in the obstacle course is 2. The line widths for the red, green, blue, and purple color are 1, 2, 3, and 4, respectively.

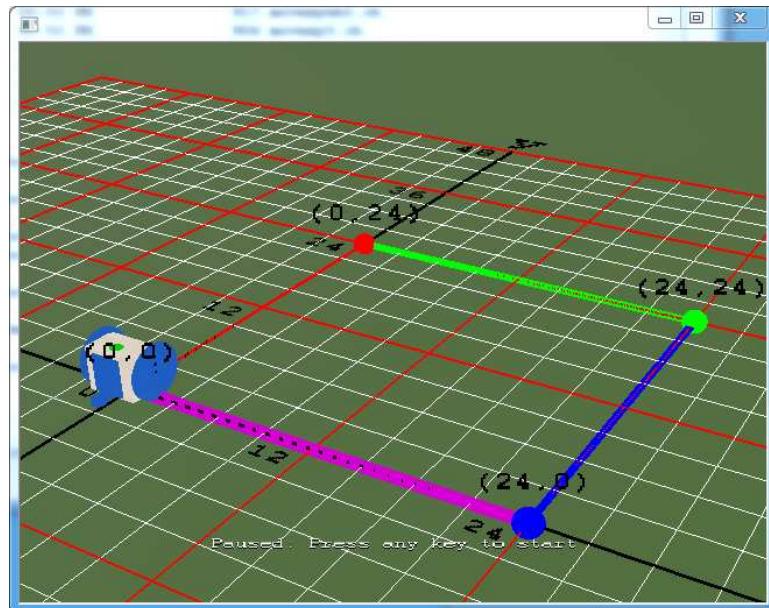


Figure B.22: The RoboSim scene with an obstacle course by the program `pointlinetext2.ch`

2. Write a program `pointlinetext3.ch` draw an obstacle course as shown in Figure B.23. The size for points in the obstacle course is 2. The line width for all lines is 2.

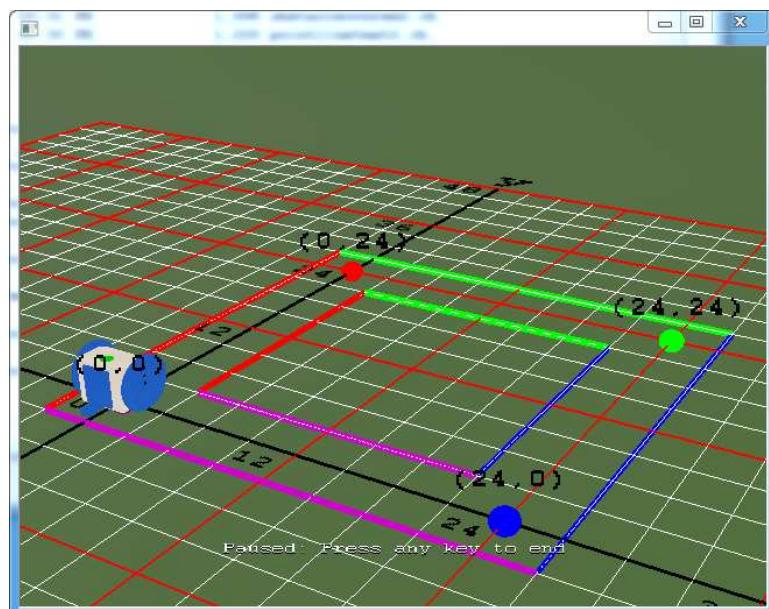


Figure B.23: The RoboSim scene with an obstacle course by the program `pointlinetext3.ch`

## B.6. Move Multiple Linkbot-Is in a Coordinate System

3. Write a program `obstaclecourse2.ch` to drive a robot following the obstacle course as shown in Figure B.22.
4. Write a program `obstaclecourse3.ch` to drive a robot following the obstacle course as shown in Figure B.23.

## B.6 Move Multiple Linkbot-Is in a Coordinate System

In Section B.1, we learned how to drive a single virtual Linkbot-I in an x and y coordinate system. In this section, we will learn how to drive multiple virtual Linkbot-Is in an x and y coordinate system. To do this, the **CLinkbotI** member function **drivexyToNB()** will be used. The general syntax of **drivexyToNB()** is

```
robot.drivexyToNB(x, y, radius, trackwidth);
```

Like the member function **drivexyTo()**, the arguments `x` and `y` specify the coordinates to drive the Linkbot-I to. The arguments `radius` and `trackwidth` specify the radius of and distance between the Linkbot-I's wheels, respectively. The member function **drivexyToNB()** is the non-blocking version of the member function **drivexyTo()**. It can be used to drive multiple Linkbot-Is to different locations at the same time. This is demonstrated in Program B.10. Before running Program B.10, set the initial position of robot 1 to  $(-6, 0)$  and the initial position of robot 2 to  $(6, 0)$  in the RoboSim GUI.

```
/* File: drivexytonb.ch
Note: This program uses drivexyToNB() available in RoboSim only
      to move one Linkbot-I from (-6, 0) to (-10, 5)
      and another Linkbot-I from (6, 0) to (10, 5) simultaneously.
      Then, to (-12, 10) and (12, 10) at the same time.
      Set the initial position (x, y) in RoboSim GUI to (-6, 0) for robot1.
      Set the initial position (x, y) in RoboSim GUI to (6, 0) for robot2. */
#include <clinkbot.h> /* for CLinkbotI */

CLinkbotI robot1, robot2;
double radius = 1.75; // radius of 1.75 inches
double trackwidth = 3.69; // the track width, the distance between two wheels

/* connect to the paired robot and move to the zero position */
robot1.connect();
robot2.connect();
robot1.resetToZeroNB();
robot2.resetToZero();

robot1.drivexyToNB(-10, 5, radius, trackwidth);
robot2.drivexyTo(10, 5, radius, trackwidth);
robot1.drivexyWait();

robot1.drivexyToNB(-12, 10, radius, trackwidth);
robot2.drivexyTo(12, 10, radius, trackwidth);
robot1.drivexyWait();
```

Program B.10: Moving two Linkbot-Is at the same time using **drivexyTo()** and **drivexyToNB()**.

## B.6. Move Multiple Linkbot-Is in a Coordinate System

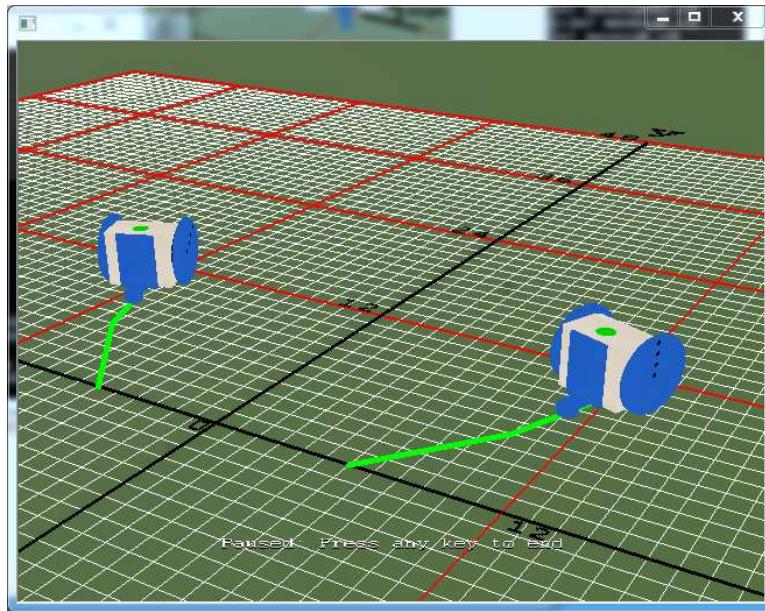


Figure B.24: The RoboSim scene with two robot trajectories from Program B.10.

Program B.10 is similar to Program B.1 from Section B.1. The difference is that in Program B.10, two Linkbot-Is are driven along two different straight lines. The statement

```
robot1.drivexyToNB(-10, 5, radius, trackwidth);
```

drives `robot1` from  $(-6, 0)$  to  $(-10, 5)$ . Before this statement finishes execution, the next statement

```
robot2.drivexyTo(10, 5, radius, trackwidth);
```

drives `robot2` from  $(6, 0)$  to  $(10, 5)$ . Since a non-blocking function is used to drive `robot1`, both Linkbots execute their motions simultaneously. The final statement

```
robot1.drivexyWait();
```

ensures that `robot1` will reach  $(-10, 5)$  before the program finishes executing. The syntax of this function is

```
robot.drivexyWait();
```

The function **drivexyWait()** has no argument. It pauses the program until the motion by the member function **drivexyToNB()** is completed. Since the motion for **drivexyToNB()** involves both moving distance and turning, the member function **drivexyWait()**, instead of **moveWait()**, is used for synchronization.

Similarly, the statements below

```
robot1.drivexyToNB(-12, 10, radius, trackwidth);
robot2.drivexyTo(12, 10, radius, trackwidth);
robot1.drivexyWait();
```

drive `robot1` from  $(-10, 5)$  to  $(-12, 10)$  and `robot2` from  $(10, 5)$  to  $(12, 10)$ .

Figure B.24 shows the trajectories and positions of two virtual Linkbot-Is when these two robots finish the above motions.

Do Exercises 1 and 2(a) on page 300.

The member function **drivexyNB()** is the non-blocking version of the member function **drivexy()** to drive a robot relative its current position. The general syntax of **drivexyNB()** is

## B.6. Move Multiple Linkbot-Is in a Coordinate System

```
robot.drivexyNB(x, y, radius, trackwidth);
```

The program `drivexynb.ch`, distributed along with other sample programs, uses the member function `drivexyNB()` to drive two robots in the same manner as they are controlled by Program B.10 using the member function `drivexyToNB()`.

 Do Exercise 2(b) on page 301.

### B.6.1 Summary

1. Call the non-blocking `CLinkbotI` member function

```
robot.drivexyToNB(x, y, radius, trackwidth);
```

on multiple Linkbot-Is to drive them simultaneously from one point to another in an x and y coordinate system. This function works in RoboSim only.

2. Call the non-blocking `CLinkbotI` member function

```
robot.drivexyNB(x, y, radius, trackwidth);
```

on multiple Linkbot-Is to drive them simultaneously from one point to another relative to its current position in an x and y coordinate system. This function works in RoboSim only.

3. Call the `CLinkbotI` member function

```
robot.drivexyWait();
```

to pause the program till the motion by a previous member function `robot.drivexyToNB()` or `robot.drivexyNB()` is completed. This function works in RoboSim only.

### B.6.2 Terminology

`robot.drivexyToNB()`, `robot.drivexyNB()`, `robot.drivexyWait()`.

### B.6.3 Exercises

1. Write a program `drivexytonb2.ch`, based on Program B.10, to drive two virtual Linkbot-Is. Move the first Linkbot-I from (0, -6) to (5, -10) and the second Linkbot-I from (0, 6) to (5, 10).

## B.6. Move Multiple Linkbot-Is in a Coordinate System

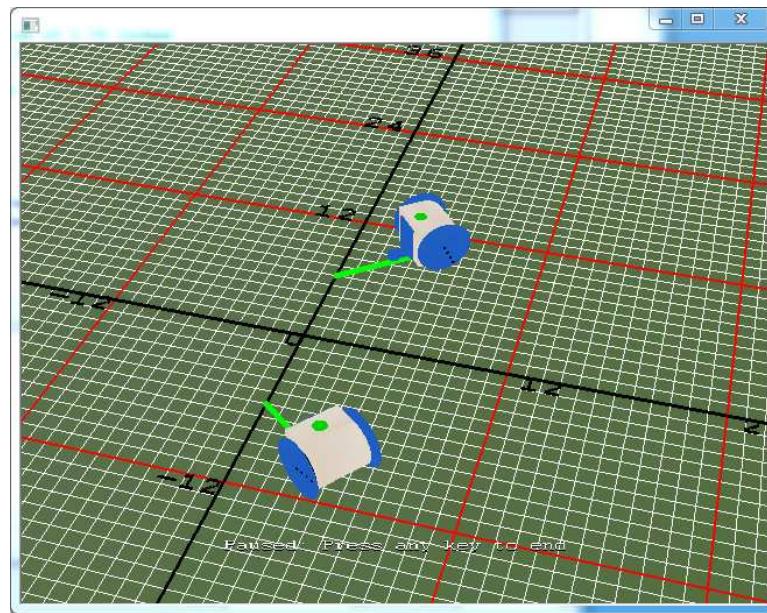


Figure B.25: The RoboSim scene with the robot trajectories for program `drivexytonb2.ch`

2. Write a program `drivexytonb3.ch`, based on Program B.10, to Move two virtual Linkbot-Is. Move the first Linkbot-I from  $(0, -6)$  to  $(10, -12)$  and the second Linkbot-I from  $(0, 6)$  to  $(10, 12)$  simultaneously. Then drive the first robot to  $(24, -5)$  and the second one to  $(24, 5)$  at the same time.

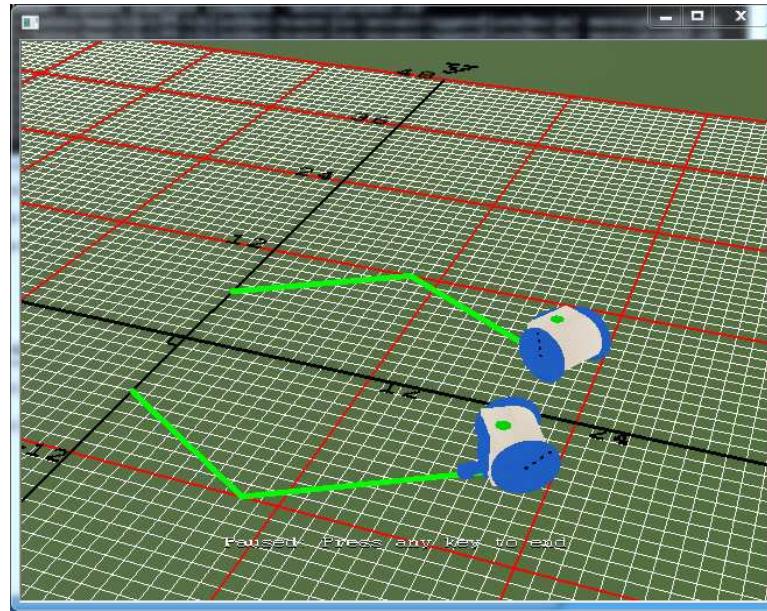


Figure B.26: The RoboSim scene with the robot trajectories for programs `drivexytonb3.ch` and `drivexynb3.ch`

- (a) Write a program `drivexytonb3.ch` using the member functions `drivexyTo()` and `drivexyToNB()`.
- (b) Write a program `drivexynb3.ch` using the member functions `drivexy()` and `drivexyNB()`.

## B.7 Trace and Record the Positions of Multiple Linkbot-Is

The trajectories for multiple robots can be traced simultaneously. Program B.11 demonstrates how to trace multiple trajectories for two Linkbot-Is, as shown in Figure B.27. Assume the `robot1` is initially placed at  $(0, 0)$  and `robot2` is at  $(6, 0)$  set in a RoboSim GUI. The following code segment in Program B.11.

```
robot1.traceOn();
robot2.traceOn();
robot1.drivexyToNB(6, 5, radius, trackwidth); // line from (0, 0) to (6, 5)
robot2.drivexyTo(12, 5, radius, trackwidth); // line from (6, 0) to (12, 5)
robot1.drivexyWait();
```

traces the line from  $(0, 0)$  to  $(6, 5)$  for `robot1` and the line from  $(6, 0)$  to  $(12, 5)$  for `robot2` simultaneously. For the next segment of the code,

```
robot1.traceOff();
robot2.traceOff();
robot1.drivexyToNB(0, 10, radius, trackwidth); // line from (6, 5) to (0, 10)
robot2.drivexyTo(6, 10, radius, trackwidth); // line from (12, 5) to (6, 10)
robot1.drivexyWait();
```

before `robot1` drives from  $(6, 5)$  to  $(0, 10)$  and `robot2` drives from  $(12, 5)$  to  $(6, 10)$ , the trace is turned off for both robots. Finally, the segment of the code,

```
robot1.traceOn();
robot2.traceOn();
robot1.drivexyToNB(6, 15, radius, trackwidth); // line from (0, 10) to (6, 15)
robot2.drivexyTo(12, 15, radius, trackwidth); // line from (6, 10) to (12, 15)
robot1.drivexyWait();
```

traces the lines from  $(0, 10)$  to  $(6, 15)$  and from  $(6, 10)$  to  $(12, 15)$ .

## B.7. Trace and Record the Positions of Multiple Linkbot-Is

```

/* File: traceon2.ch
   Turn trakce on and off with two Linkbot-Is
   Set the initial position (x, y) in RoboSim GUI to (0, 0) for robot1.
   Set the initial position (x, y) in RoboSim GUI to (6, 0) for robot2. */
#include <linkbot.h>
CLinkbotI robot1, robot2;
double radius = 1.75;           // radius of 1.75 inches
double trackwidth = 3.69;       // the track width, the distance between two wheels

/* connect to the paired robot and move to the zero position */
robot1.connect();
robot2.connect();
robot1.resetToZeroNB();
robot2.resetToZero();

robot2.setLEDColor("red"); // set the robot2 LED color to red

robot1.traceOn();
robot2.traceOn();
robot1.drivexyToNB(6, 5, radius, trackwidth); // line from (0, 0) to (6, 5)
robot2.drivexyTo(12, 5, radius, trackwidth); // line from (6, 0) to (12, 5)
robot1.drivexyWait();

robot1.traceOff();
robot2.traceOff();
robot1.drivexyToNB(0, 10, radius, trackwidth); // line from (6, 5) to (0, 10)
robot2.drivexyTo(6, 10, radius, trackwidth); // line from (12, 5) to (6, 10)
robot1.drivexyWait();

robot1.traceOn();
robot2.traceOn();
robot1.drivexyToNB(6, 15, radius, trackwidth); // line from (0, 10) to (6, 15)
robot2.drivexyTo(12, 15, radius, trackwidth); // line from (6, 10) to (12, 15)
robot1.drivexyWait();

```

Program B.11: Tracing trajectories for two Linkbot-Is.

## B.7. Trace and Record the Positions of Multiple Linkbot-Is

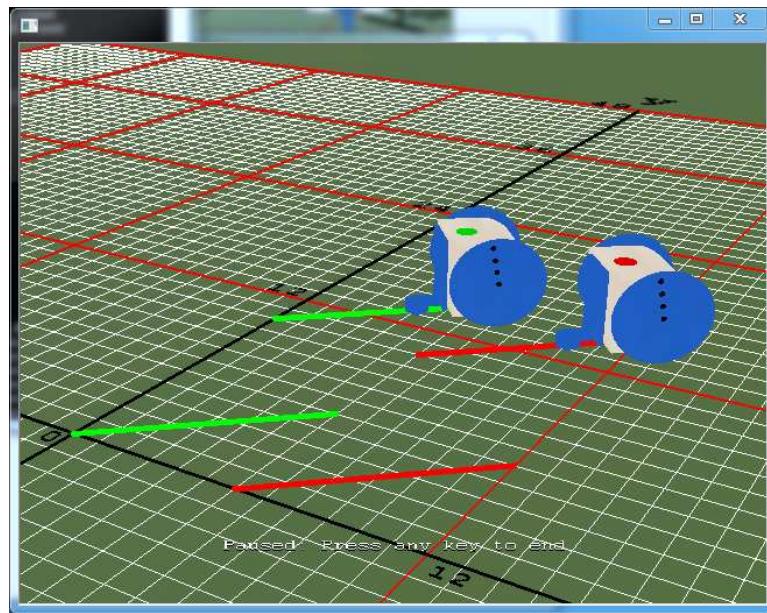


Figure B.27: The RoboSim scene with the robot trajectories from Programs B.11 and B.12.

**E** Do Exercise 1, on 306.

The positions for the traced trajectories for multiple Linkbot-Is can be recorded simultaneously and then plotted. Program B.12 demonstrates how to record and plot positions of the traced trajectories for two Linkbot-Is. Program B.12 will trace the trajectories shown in Figure B.27 and plot the acquired positions for the traced trajectories shown in Figure B.28. The tracing and motion statements for two Linkbots-Is in Program B.12 are the same as those in Program B.11.

The statements

```
/* begin recording x and y positions */
robot1.recordxyBegin(xdata1, ydata1, timeInterval);
robot2.recordxyBegin(xdata2, ydata2, timeInterval);
```

start recording the positions of traced trajectories for two Linkbot-Is.

After two Linkbot-Is stop moving, the statements

```
/* end recording x and y positions */
robot1.recordxyEnd(numDataPoints1);
robot2.recordxyEnd(numDataPoints2);
```

stop recording the positions for the traced trajectories.

The statements below

```
plot.data2DCurve(xdata1, ydata1, numDataPoints1);
int datanum = 0, pointType = 7, pointSize = 1;
plot.plotType(PLOT_PLOTTYPE_POINTS, datanum);
plot.pointType(datanum, pointType, pointSize, "green");
plot.data2DCurve(xdata2, ydata2, numDataPoints2);
datanum = datanum + 1;
plot.plotType(PLOT_PLOTTYPE_POINTS, datanum);
plot.pointType(datanum, pointType, pointSize, "red");
```

plot two sets of the data points. The first data set is plotted in the green color. and the second set in the red color.

```
/* File: recordxy2.ch
```

## B.7. Trace and Record the Positions of Multiple Linkbot-Is

```

Trace and record the x and y positions for two Linkbot-Is,
plot the acquired data.
Set the initial position (x, y) in RoboSim GUI to (0, 0) for robot1.
Set the initial position (x, y) in RoboSim GUI to (6, 0) for robot2. */
#include <linkbot.h>
#include <chplot.h>
CLinkbotI robot1, robot2;
double radius = 1.75;           // radius of 1.75 inches
double trackwidth = 3.69;        // the track width, the distance between two wheels
double timeInterval = 0.1;       // time interval in 0.1 second
int numDataPoints1;             // number of data points recorded for robot1
int numDataPoints2;             // number of data points recorded for robot2
robotRecordData_t xdata1, ydata1; // recorded x and y positions for robot1
robotRecordData_t xdata2, ydata2; // recorded x and y positions for robot2
CPlot plot;                     // plotting class

/* connect to the paired robot and move to the zero position */
robot1.connect();
robot2.connect();
robot1.resetToZeroNB();
robot2.resetToZero();

robot2.setLEDColor("red"); // set the robot2 LED color to red

/* begin recording x and y positions */
robot1.recordxyBegin(xdata1, ydata1, timeInterval);
robot2.recordxyBegin(xdata2, ydata2, timeInterval);

robot1.traceOn();
robot2.traceOn();
robot1.drivexyToNB(6, 5, radius, trackwidth); // line from (0, 0) to (6, 5)
robot2.drivexyTo(12, 5, radius, trackwidth);   // line from (6, 0) to (12, 5)
robot1.drivexyWait();

robot1.traceOff();
robot2.traceOff();
robot1.drivexyToNB(0, 10, radius, trackwidth); // line from (6, 5) to (0, 10)
robot2.drivexyTo(6, 10, radius, trackwidth);   // line from (12, 5) to (6, 10)
robot1.drivexyWait();

robot1.traceOn();
robot2.traceOn();
robot1.drivexyToNB(6, 15, radius, trackwidth); // line from (0, 10) to (6, 15)
robot2.drivexyTo(12, 15, radius, trackwidth);   // line from (6, 10) to (12, 15)
robot1.drivexyWait();

/* end recording x and y positions */
robot1.recordxyEnd(numDataPoints1);
robot2.recordxyEnd(numDataPoints2);

/* plot the data */
plot.mathCoord();
plot.title("Position");
plot.label(PLOT_AXIS_X, "X (inches)");
plot.label(PLOT_AXIS_Y, "Y (inches)");
plot.axisRange(PLOT_AXIS_X, -5, 15);
plot.axisRange(PLOT_AXIS_Y, 0, 20);
plot.data2DCurve(xdata1, ydata1, numDataPoints1);
int datanum = 0, pointType = 7, pointSize = 1;

```

## B.7. Trace and Record the Positions of Multiple Linkbot-Is

```

plot.plotType(PLOT_PLOTTYPE_POINTS, datanum);
plot.pointType(datanum, pointType, pointSize, "green");
plot.data2DCurve(xdata2, ydata2, numDataPoints2);
datanum = datanum + 1;
plot.plotType(PLOT_PLOTTYPE_POINTS, datanum);
plot.pointType(datanum, pointType, pointSize, "red");
plot.sizeRatio(1);
plot.plotting();

```

Program B.12: Recording and plotting the positions of the traced trajectories for two Linkbot-Is.

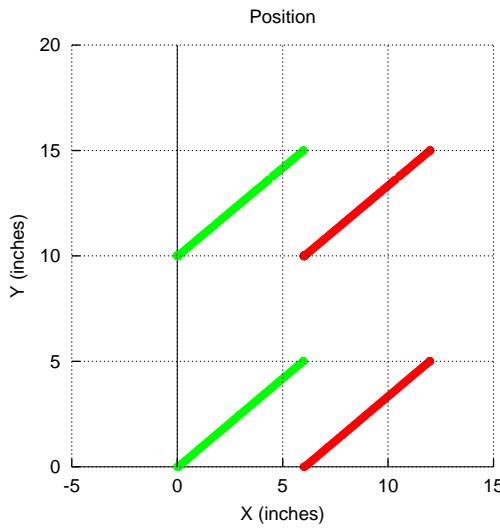


Figure B.28: The plot for the traced trajectories for two robots from Program B.12.

Do Exercise 2, on 307.

**B.7.1 Exercises**

1. Write a program `traceon4.ch` to trace two letters 'A' in RoboSim as shown in Figure B.29. The horizontal line for the first letter 'A' can be drawn from the point  $(-2.5, 5)$  to the point  $(2.5, 5)$ . The horizontal line for the second letter 'A' is from the point  $(7.5, 5)$  to the point  $(12.5, 5)$ .

## B.8. Move Multiple Linkbot-Is Along Different Trajectories

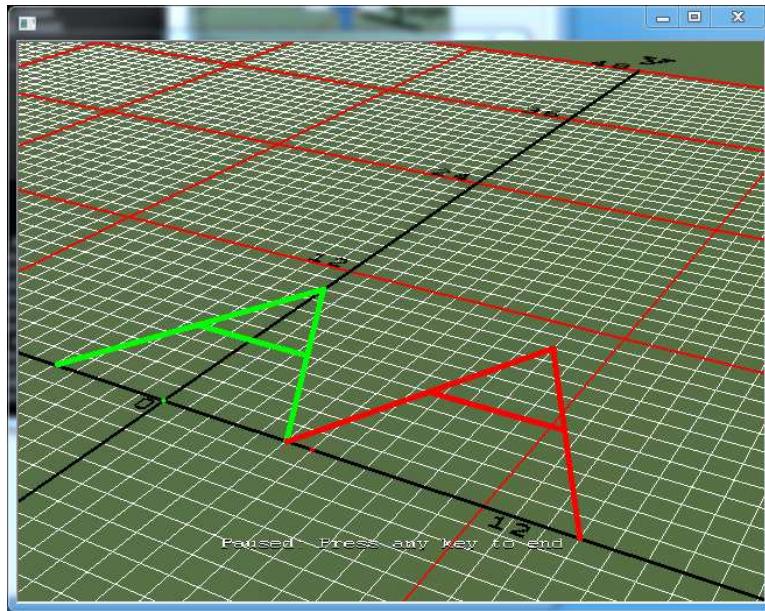


Figure B.29: Moving two virtual Linkbot-Is to trace two letters of 'A'.

2. Based on the program `traceon4.ch` developed in Exercise 2, write a program `recordxy4.ch` to record and plot the traced trajectories for two Linkbot-Is with two letters of 'A' as shown in Figure B.30.

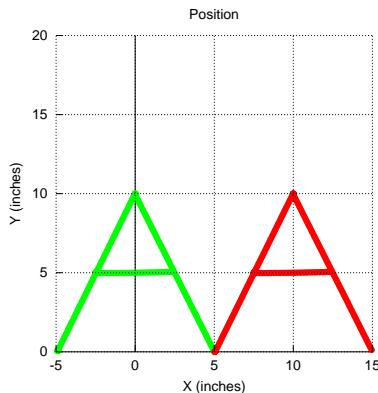


Figure B.30: A plot generated by the program `recordxy4.ch`.

## B.8 Move Multiple Linkbot-Is Along Different Trajectories

In section B.2, we learned how to drive a single Linkbot-I along a trajectory specified by a function using the member function `drivexyToFunc()` or by an expression using the member function `drivexyToExpr()`. Since the Linkbot must travel to many more points, these functions are actually implemented using the member function `drivexyTo()` using a loop.

## B.8. Move Multiple Linkbot-Is Along Different Trajectories

The use of a **for** loop together with a user-defined function is helpful for calculating the next point and then calling **drivexyTo()** multiple times in succession. Details for the **for** are described in section A.3 in Appendix A.

```
/* File: polynomial.ch
Note: This program uses drivexyTo() available in RoboSim only.
Set the initial position (x, y) in RoboSim GUI to (-6, 5.5) for the robot.

A robot moves along a polynomial curve y = 0.5(x+5)(x-5) for x from -6 to 6.
Plot the polynomial y for x from -6 to 6 with 500 points.
The range of x-axis is from -12 to 12.
The range of y-axis is from -15 to 12.
The tics range for x and y axes is 1. */
#include <chplot.h> /* for CPlot */
#include <linkbot.h> /* for CLinkbotI */

double func(double x) {
    return 0.5*(x+5)*(x-5);
}

CPlot plot;
CLinkbotI robot;
double radius = 1.75;      // radius of 1.75 inches
double trackwidth = 3.69;   // the track width, the distance between two wheels
double x, y;               // x and y coordinates

/* connect to the paired robot and move to the zero position */
robot.connect();
robot.resetToZero();
robot.setSpeed(3, 1.75);

/* move the robot along the polynomial curve */
for(x=-6; x<=6.1; x=x+0.2) {
    y = func(x);
    printf("drivexyTo(x, y) = (%lf, %lf)\n", x, y);
    robot.drivexyTo(x, y, radius, trackwidth);
}

/* plot the polynomial curve */
plot.mathCoord();
plot.title("y = 0.5(x+5)(x-5)");
plot.label(PLOT_AXIS_X, "x");
plot.label(PLOT_AXIS_Y, "y");
plot.axisRange(PLOT_AXIS_X, -12, 12);
plot.axisRange(PLOT_AXIS_Y, -15, 12);
plot.ticsRange(PLOT_AXIS_X, 1);
plot.ticsRange(PLOT_AXIS_Y, 1);
plot.func2D(-6, 6, 500, func);
plot.plotting();
```

Program B.13: Moving a Linkbot-I to follow a polynomial curve using **drivexyTo()** and a **for** loop.

Program B.13 shows how this can be done to drive a virtual Linkbot-I along the trajectory of a parabola. Before running Program B.13, set the initial position of the Linkbot-I in the RoboSim GUI to  $(-6, 5.5)$ . In Program B.13 a function `func ()` is used to define this quadratic equation, which calculates the  $y$ -coordinate for each point the virtual Linkbot-I travels to on the parabola. The function `func ()` is defined as

## B.8. Move Multiple Linkbot-Is Along Different Trajectories

```
/* define the function func() */
double func(double x) {
    return 0.5*(x+5)*(x-5);
}
```

After the virtual Linkbot-I is connected and reset to the zero position, the lines

```
for(x=-6; x<=6.1; x=x+0.2) {
    y = func(x);
    printf("drivexyTo(x, y) = (%lf, %lf)\n", x, y);
    robot.drivexyTo(x, y, radius, trackwidth);
}
```

use a **for** loop to repeat the program statements that drive the virtual Linkbot-I to each point along its trajectory. Each time the loop repeats, the value of the  $x$ -coordinate is incremented by 0.2, and the corresponding  $y$ -coordinate is calculated using `func()`. Then the  $x$  and  $y$  coordinates are printed to the input/output pane, and `drivexyTo()` is used to drive the Linkbot-I to these coordinates. Since the value of the  $x$ -coordinate is incremented by 0.2 each iteration, the **for** loop repeats a total of 60 times, and the virtual Linkbot-I is driven a total of 60 points along the trajectory of the parabola. Although `drivexyTo()` drives the Linkbot-I in a straight line between the points, the points are close enough together that these lines appear as a smooth curve in the RoboSim GUI.

The output from Program B.13 is the same as that from Programs B.5 and B.4, as shown in Figures B.13 and B.14.

 Do Exercise 1 on page 312.

Just as it is possible to drive two virtual Linkbot-Is along two separate straight-lines simultaneously as shown in Program B.10, it is also possible to simultaneously drive two virtual Linkbot-Is along two separate polynomial curves. Program B.14 demonstrates how to do this using `drivexyToNB()`. Before running Program B.14, set the initial positions of robot 1 and robot 2 to  $(-6, 5.5)$  and  $(6, 5.5)$  in the RoboSim GUI.

## B.8. Move Multiple Linkbot-Is Along Different Trajectories

```

/* File: polynomial2.ch
Note: This program uses drivexyToNB() and drivexyWait() available in RoboSim only.
Set the initial position (x, y) in RoboSim GUI to (-6, 5.5) for robot1.
Set the initial position (x, y) in RoboSim GUI to (6, 5.5) for robot2.

robot1 moves along a polynomial curve y = 0.5(x+5)(x-5) for x from -6 to 6.
robot2 moves along a polynomial curve y = 0.5(x-7)(x-17) for x from 6 to 18.
Plot the polynomial y for x from -6 to 6 with 500 points.
The range of x-axis is from -12 to 24.
The range of y-axis is from -15 to 12.
The tics range for x and y axes is 1. */

#include <chplot.h> /* for CPlot */
#include <linkbot.h> /* for CLinkbotI */

double func(double x) {
    return 0.5*(x+5)*(x-5);
}

double func2(double x) {
    return 0.5*(x-7)*(x-17);
}

CPlot plot;
CLinkbotI robot1;
CLinkbotI robot2;
double radius = 1.75; // radius of 1.75 inches
double trackwidth = 3.69; // the track width, the distance between two wheels
double x, y1, y2; // x and y coordinates

/* connect to the paired robot and move to the zero position */
robot1.connect();
robot1.resetToZeroNB();
robot2.connect();
robot2.resetToZero();

/* change the default green color to red for robot 1 */
robot1.setLEDColor("red");

/* move the robot along the polynomial curve */
for(x=-6; x<=6; x=x+0.2) {
    y1 = func(x);
    y2 = func2(x+12);
    robot1.drivexyToNB(x, y1, radius, trackwidth);
    robot2.drivexyTo(x+12, y2, radius, trackwidth);
    robot1.drivexyWait();
}

/* plot the polynomial curve */
plot.mathCoord();
plot.title("");
plot.label(PLOT_AXIS_X, "x");
plot.label(PLOT_AXIS_Y, "y");
plot.axisRange(PLOT_AXIS_X, -12, 24);
plot.axisRange(PLOT_AXIS_Y, -15, 12);
plot.ticsRange(PLOT_AXIS_X, 1);
plot.ticsRange(PLOT_AXIS_Y, 1);
plot.func2D(-6, 6, 500, func);
plot.legend("y = 0.5(x+5)(x-5)", 0);
plot.func2D(6, 18, 500, func2);
plot.legend("y = 0.5(x-7)(x-17)", 1);
plot.plotting();

```

## B.8. Move Multiple Linkbot-Is Along Different Trajectories

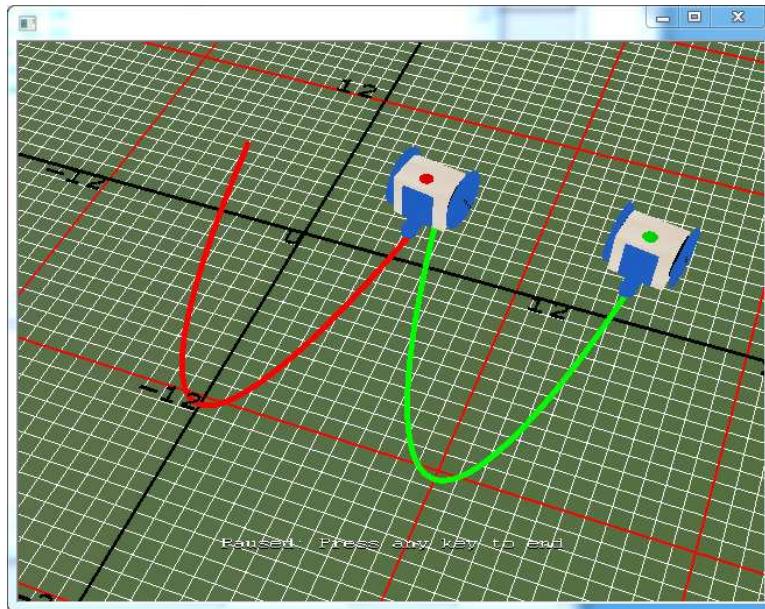


Figure B.31: The RoboSim scene with the robot trajectories of two polynomials from Program B.14.

Program B.13 demonstrated how to drive a single virtual Linkbot-I along the trajectory of a parabola. Program B.14 is very similar to Program B.13, except that two virtual Linkbot-Is are driven along different parabolic trajectories at the same time. The red color for the trajectory of the first robot is set by the member function call

```
robot1.setLEDColor("red");
```

by default, the color for the trajectory of the second robot is the green.

As in Program B.13, the user-defined function `func()` is used to calculate the  $y$ -coordinates of the points on the first parabola. For the second parabola, the new user-defined function `func2()`, is defined by the following program statements.

```
double func2(double x) {
    return 0.5*(x-7)*(x-17);
}
```

This function takes in an argument `x` of type `double`, which specifies the  $x$ -coordinate of the next point. It returns a value of type `double`, which is the corresponding  $y$ -coordinate. `func2()` calculates these  $y$ -coordinates using the following quadratic equation.

$$y = 0.5(x - 7)(x - 17) = 0.5x^2 - 12x + 59.5$$

The two virtual Linkbot-Is are driven along their parabolic trajectories using the following `for` loop

```
for(x=-6; x<=6; x=x+0.2) {
    y1 = func(x);
    y2 = func2(x+12);
    robot1.drivexyToNB(x, y1, radius, trackwidth);
    robot2.drivexyTo(x+12, y2, radius, trackwidth);
    robot1.drivexyWait();
}
```

The `for` loop in Program B.14 is similar to the `for` loop in Program B.13. The difference is that in Program B.14 the statements repeated in the `for` loop calculate the  $y$ -coordinates of the next points for `robot1`

## B.8. Move Multiple Linkbot-Is Along Different Trajectories

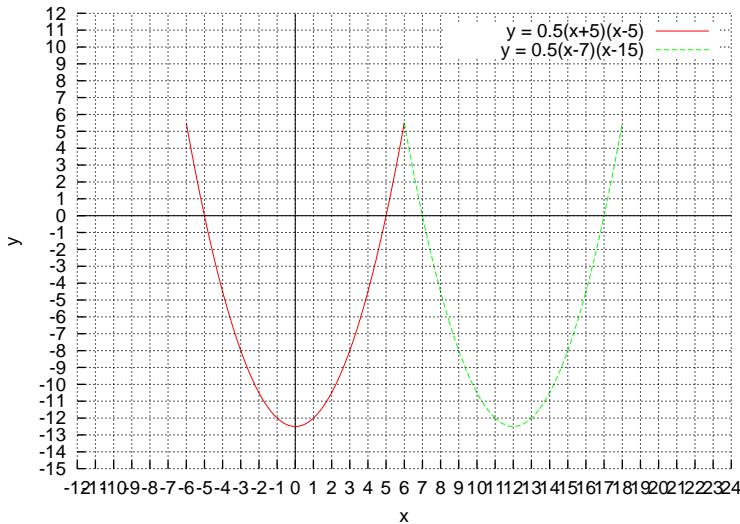


Figure B.32: The plot for two polynomials traveled by two robot from Program B.14.

and `robot2`, using `func()` and `func2()`, respectively. Then both `robot1` and `robot2` are driven to their new points simultaneously. Since the non-blocking member function `drivexyToNB()` is used to drive `robot1`, `drivexyWait()` is called to ensure that `robot1` will finish its motion before the next iteration of the `for` loop. As in Program B.13, the `for` loop will iterate a total of 60 times, so each Linkbot-I will drive through a total of 60 points. Both parabolas will look similar, except that the parabolic trajectory of `robot2` will be from (6, 5.5) to (18, 5.5). Figure B.31 shows the parabolic trajectories of `robot1` and `robot2`.

The trajectories of the two virtual Linkbot-Is are plotted, in a manner similar to Program B.13. In Section 11.6, it has been demonstrated that the motion of two Linkbot-Is can be plotted on the same graph. This is also done in Program B.14. To allow room for both parabolas, the line

```
plot.axisRange(PLOT_AXIS_X, -12, 24);
```

sets a larger range on the x-axis, from  $-12$  to  $24$ . The additional statement

```
plot.func2D(6, 18, 500, func2);
```

plots the function `func2()` for `robot2` in the range  $[6, 18]$ , using 500 points. Figure B.32 shows the generated plot.

Note that non-blocking member functions `drivexyToFuncNB()` and `drivexyToExprNB()` are not available.

Do Exercise 2 on page 313.

### B.8.1 Summary

1. Call the member functions `drivexyTo()`, `drivexyToNB()`, and `drivexyWait()` in a loop to drive multiple Linkbot-Is simultaneously along different trajectories.

### B.8.2 Terminology

### B.8.3 Exercises

1. Write a program `polynomial3.ch`, using the member function `drivexyTo()` and a `for` loop, based on Program B.13, that drives a virtual Linkbot-I along the trajectory of a parabola from  $(-6, -5.5)$  to

## B.8. Move Multiple Linkbot-Is Along Different Trajectories

(6, -5.5), as shown in Figure B.15 on page 285.

2. Write a program `polynomial4.ch`, based on Program B.14, that drives two virtual Linkbot-Is along the trajectory of two parabolas, from (-6, -5.5) to (6, -5.5) for `robot1` and from (6, -5.5) to (18, -5.5) for `robot2`. These parabolas will open downward, with the vertex of the first at (0, 12.5) and the vertex of the second at (12, 12.5). Use the **CPlot** member functions `axisRange()`, `ticsRange()`, and `func2D()` to generate a plot of the trajectories of the two virtual Linkbot-Is.

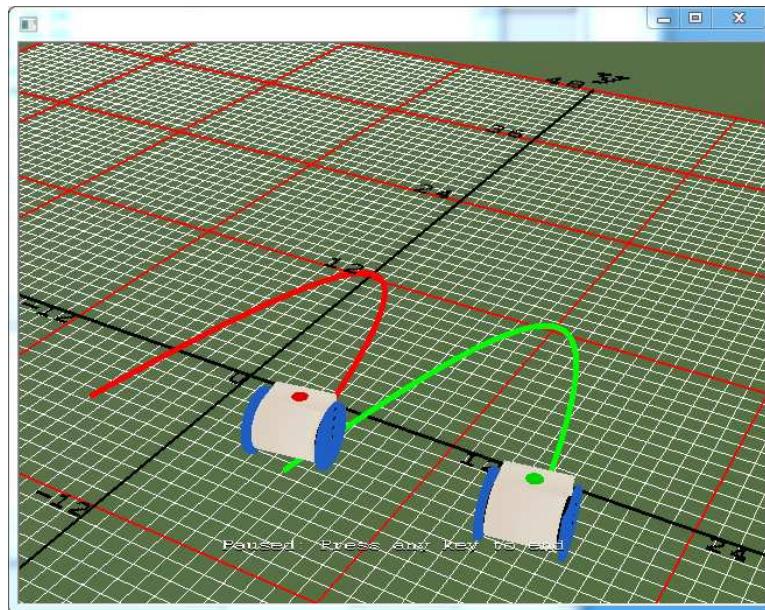


Figure B.33: The RoboSim scene with the robot trajectories for program `polynomial4.ch`

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## APPENDIX C

---

# Colors Available for Use with the Member Functions `setLEDColor()` and `getLEDColor()`

This appendix lists all the possible color names that can be used to set and get the LED color using member functions `setLEDColor()` and `getLEDColor()`. Each name must be enclosed with quotation marks when used as the argument for `setLEDColor()`. The name of each color is listed along with its corresponding RGB values in Table C.1 below.

Table C.1: The colors available for use with `setLEDColor()` and `getLEDColor()`.

Color Name	Red	Green	Blue
aliceBlue	240	248	255
antiqueWhite	250	235	215
aqua	0	255	255
aquamarine	127	255	212
azure	240	255	255
beige	245	245	220
bisque	255	228	196
black	0	0	0
blanchedAlmond	255	235	205
blue	0	0	255
blueViolet	138	43	226

(Continued)

Table C.1: (Continued)

<b>Color Name</b>	<b>Red</b>	<b>Green</b>	<b>Blue</b>
brown	165	42	42
burlyWood	222	184	135
cadetBlue	95	158	160
chartreuse	127	255	0
chocolate	210	105	30
coral	255	127	80
cornflowerBlue	100	149	237
cornSilk	255	248	220
crimson	220	20	60
darkBlue	0	0	139
darkCyan	0	139	139
darkGoldenrod	184	134	11
darkGray	169	169	169
darkGreen	0	100	0
darkKhaki	189	183	107
darkMagenta	139	0	139
darkOliveGreen	85	107	47
darkOrange	255	140	0
darkOrchid	153	50	204
darkRed	139	0	0
darkSalmon	233	150	122
darkSeaGreen	143	188	143
darkSlateBlue	72	61	139
darkSlateGray	47	79	79
darkTurquoise	0	206	209
darkViolet	148	0	211
deepPink	255	20	147
deepSkyBlue	0	191	255
dimGray	105	105	105
dodgerBlue	30	144	255
fireBrick	178	34	34
floralWhite	255	250	240
forestGreen	34	139	34
fuchsia	255	0	255
gainsboro	220	220	220
ghostWhite	248	248	255
gold	255	215	0
goldenrod	218	165	32
gray	128	128	128
green	0	255	0
greenYellow	173	255	47

(Continued)

Table C.1: (Continued)

Color Name	Red	Green	Blue
honeydew	240	255	240
hotPink	255	105	180
indigo	75	0	130
ivory	255	255	240
khaki	240	230	140
lavender	230	230	250
lavenderBlush	255	240	245
lawnGreen	124	252	0
lemonChiffon	255	250	205
lightBlue	173	216	230
lightCoral	240	128	128
lightCyan	224	255	255
lightGoldenrodYellow	250	250	210
lightGray	211	211	211
lightGreen	144	238	144
lightPink	255	182	193
lightSalmon	255	160	122
lightSeaGreen	32	178	170
lightSkyBlue	135	206	250
lightSlateGray	119	136	153
lightSteelBlue	176	196	222
lightYellow	255	255	224
limeGreen	50	205	50
linen	250	240	230
magenta	255	0	255
maroon	128	0	0
mediumAquamarine	102	205	170
mediumBlue	0	0	205
mediumOrchid	186	85	211
mediumPurple	147	112	219
mediumSeaGreen	60	179	113
mediumSlateBlue	123	104	238
mediumSpringGreen	0	250	154
mediumTurquoise	72	209	204
mediumVioletRed	199	21	133
midnightBlue	25	25	112
mintCream	245	255	250
mistyRose	255	228	225
moccasin	255	228	181
navajoWhite	255	222	173
navy	0	0	128
oldLace	253	245	230
olive	128	128	0

(Continued)

Table C.1: (Continued)

<b>Color Name</b>	<b>Red</b>	<b>Green</b>	<b>Blue</b>
oliveDrab	107	142	35
orange	255	165	0
orangeRed	255	69	0
orchid	218	112	214
paleGoldenrod	238	232	170
paleGreen	152	251	152
paleTurquoise	175	238	238
paleVioletRed	219	112	147
papayaWhip	255	239	213
peachPuff	255	218	185
peru	205	133	63
pink	255	192	203
plum	221	160	221
powderBlue	176	224	230
purple	128	0	128
red	255	0	0
rosyBrown	188	143	143
royalBlue	65	105	225
saddleBrown	139	69	19
salmon	250	128	114
sandyBrown	244	164	96
seaGreen	46	139	87
seaShell	255	245	238
sienna	160	82	45
silver	192	192	192
skyBlue	135	206	235
slateBlue	106	90	205
slateGray	112	128	144
snow	255	250	250
springGreen	0	255	127
steelBlue	70	130	180
tan	210	180	140
teal	0	128	128
thistle	216	191	216
tomato	255	99	71
turquoise	64	224	208
violet	238	130	238
wheat	245	222	179
white	255	255	255
whiteSmoke	245	245	245
yellow	255	255	0
yellowgreen	154	205	50

---

---

## APPENDIX D

---

# Quick References to Ch

This appendix summarizes Ch features used in this book.

### D.1 Reserved Keywords and Names

CPlot double else if int printf pow return robotRecordData\_t scanf sqrt while

### D.2 Punctuators

+ - \* / ( ) . \ " # & { }

### D.3 Comments

```
/* This is a comment */  
int i; // this is also a comment
```

### D.4 Header Files

#include <math.h> for the macro **M\_PI** for  $\pi$ .  
#include <chplot.h> for the plotting class **CPlot**.  
#include <linkbot.h> for the robot classes **CLinkbotI** and **CLinkbotL**.

## D.5 Declaration of Variables for Integers and Decimals

```
int i, n=10;           // variables for integers
double x, y=1.2;       // variables for decimals
```

## D.6 Declaration of Functions

```
/* define a function func(x) for f(x)=2x-3 */
double func(double x) {
    return 2*x - 3;
}
```

## D.7 The if-else Statement

```
if(x<0) {
    y = 2*x;
}
else {
    y = 3*x;
}
```

## D.8 The while Loop

```
i=0;
while(i < num) {
    sum = sum + i;
    i = i + 1;
}
```

## D.9 Input Function **scanf()** and Output Function **printf()**

```
printf("i= %d, x = %lf\n", i, x); // print integer i and decimal x
printf("%.2lf\n", x);           // print two digits after the decimal point
printf("%E\n", x);             // print x in scientific notation
scanf("%d", &i);              // get the user input for i
scanf("%d%lf", &i, &x);        // get the user input for i and x
```

## D.10. Math Operators

Print special characters using "\n" for a newline character and "%%" for the percent symbol %.

```
printf("Hello, World\n");
printf("We sell Yogurt with 10%% discount\n"); // with 10% discount
```

## D.10 Math Operators

Description	Operator in math	Operator in Ch	Operation
addition	+	+	$x + y$
subtraction	-	-	$x - y$
multiplication	$\times$	*	$x * y$
multiplication	.	*	$x * y$
division	$\div$	/	$x / y$

Unless the result of a division operation is a whole number, to get the correct numerical result, one of the numbers must be inputted as a decimal number. For example, the math expression  $\frac{2(3+4)}{5-6}$  can be inputted in Ch as  $2.0 * (3+4) / (5-6)$ .

## D.11 Relational Operators

<    <=    ==    >=    >    !=

## D.12 Math Functions **sqrt()**, **pow()**, and **abs()**

The square root function **sqrt(x)** is for  $\sqrt{x}$ . The exponential function **pow(x, y)** is for  $x^y$ . The absolute function **abs(x)** is for  $|x|$ .

```
y = sqrt(x);
y = pow(x, 3);
y = abs(x);
```

## D.13 Member Functions of the Plotting Class **CPlot**

This document uses several member functions of the plotting class **CPlot** to create and manipulate plots. Detailed information for member functions of the class **CPlot** can be found in the section for the header file **chplot.h** in *Ch Reference Guide*, which is available in a PDF file **chref.pdf** by clicking the command Help->Help in ChIDE. The usages of the member functions in this document are summarized in this appendix.

**plot.arrow(x\_head, y\_head, x\_tail, y\_tail)**

adds an arrow to a plot. The arrow points from  $(x\_tail, y\_tail)$  to  $(x\_head, y\_head)$ . For example,

```
plot.arrow(x1, y1, x2, y2);
```

D.13. Member Functions of the Plotting Class **CPlot**

This member function can be used to draw arrows in x and y axes.

**plot.axisRange(axis, minimum, maximum)**

sets the minimum and maximum value for an axis. The first argument `axis` specifies which axis. The commonly used macros for the argument `axis` are **PLOT\_AXIS\_X** and **PLOT\_AXIS\_Y** for x-axis and y-axis, respectively. The second argument `minimum` is for the minimum value of the axis. The third argument `maximum` is for the maximum value of the axis. For example,

```
plot.axisRange(PLOT_AXIS_X, -10, 10);
plot.axisRange(PLOT_AXIS_Y, -10, 10);
```

**plot.enhanceText()**

sets a plot to use the enhanced text for strings such as title, labels, and legends. Special symbols for the enhanced text can be found in *Ch Reference Guide*, available in a PDF file `chref.pdf` by clicking the command Help->Help in ChIDE. For example,

```
plot.enhanceText();
```

The strings "/Symbol \u243" and "/Symbol \u263" represent  $\leq$  and  $\geq$ , respectively. The string "{/Symbol @{\u140}\u326}x" is used to print a square root function sign  $\sqrt{x}$ . To print a superscript on a plot, the symbol `^` is used, such as `x^2` for  $x^2$ .

**plot.func2D(x0, xf, num, func)**

plots a function defined as `func()` in the range `[x0, xf]` with the number of points specified by the argument `num`. For example,

```
plot.func2D(-10, 10, 500, func);
```

**plot.label(axis, "string")**

adds a label to an axis. For example,

```
plot.label(PLOT_AXIS_X, "x");
plot.label(PLOT_AXIS_Y, "y=2x+5");
```

**plot.legend("legend", num)**

adds a legend to the plot. The first argument is a string for the legend. The second argument is the number of the data set associated with the legend. Numbering of data sets starts with zero. For example,

```
plot.legend("y=2x+5", 0);
```

**plot.line(x1, y1, x2, y2)**

draws a straight line between the two end points `[x1, y1]` and `[x2, y2]`. For example,

```
plot.line(-10, 150, 10, 250);
```

D.13. Member Functions of the Plotting Class **CPlot****plot.lineType(num, lineType, lineWidth, "grey")**

specifies a line type. The first argument num specifies the data set, to which the line type, width, and color apply. The second argument lineType is an integer index representing the line type for drawing. Use the same value for different curves making each curve with the same style to have the same color by default. The third argument lineWidth, with an integer value, is a scaling factor for the line width. The actual line width in the plot is lineWidth multiplied by the default width. The fourth argument in the string specifies the color. For example,

```
plot.lineType(0, 1, 2, "green");
```

**plot.mathCoord()**

sets the attributes for a mathematical coordinate system. For example,

```
plot.mathCoord();
```

**plot.plotting()**

generates a plot. For example,

```
plot.plotting();
```

**plot.plotType(PLOT\_PLOTTYPE\_LINE, num)**

specifies the plot type as a line for the data set num. For example,

```
plot.plotType(PLOT_PLOTTYPE_LINE, 0);
```

**plot.plotType(PLOT\_PLOTTYPE\_FILLEDCURVES, num, "y1=-20", "color")**

specifies the plot type for filling an area. The second argument num specifies the data set to which the filled curve applies. The third argument specifies an axis for filling the area. The fourth argument specifies the color to fill the area. The example below

```
plot.plotType(PLOT_PLOTTYPE_FILLEDCURVES, 0, "y1=-20", "yellow");
```

specifies that the plot fills the area with the color grey between the curve, created by the data points in the first data set, and the horizontal line  $y = -20$ .

**plot.point(x, y)**

draws a point at the coordinate (x, y). For example,

```
plot.point(-10, 10);
```

**plot.pointType(anum, pointType, pointSize, "color")**

specifies the point type, size, and color for point(s).

*num* The first argument specifies the data set to which the point type, size, and col or apply. The second argument pointType in integer represents the desired point type. The third argument is the point size multiplied by the default size. The last argument is color for the point. For example,

```
plot.pointType(num, 7, 2, "green");
```

D.13. Member Functions of the Plotting Class **CPlot****plot.sizeRatio(ratio)**

sets the x and y aspect ratio for the plot. For example,

```
plot.sizeRatio(1);
```

**plot.text("string", PLOT\_TEXT\_CENTER, x, y)**

adds the text "string" at (x, y). For example,

```
plot.text("x", PLOT_TEXT_CENTER, x, y);
```

**plot.ticsRange(axis, incr)**

specifies the incremental value for tick marks for an axis.

```
plot.ticsRange(PLOT_AXIS_X, 1);
plot.ticsRange(PLOT_AXIS_Y, 5);
```

**plot.title("plot title")**

adds a title, specified in a string, to the plot. For example,

```
plot.title("Ch plot title");
```

---

---

## APPENDIX E

---

# Quick Reference to Linkbot Member Functions

Some data types and member functions of the classes **LinkbotI**, **LinkbotL**, **CLinkbotIGroup**, and **CLinkbotLGroup** are defined in the header file **linkbot.h**. This appendix summarizes these data types and member functions used to control the Linkbots.

### E.1 Data Types

The data types defined in the header file **linkbot.h** are described in this section. These data types are used by the Linkbot library to represent certain values, such as joint id's and motor directions.

Data Type	Description
<b>robotJointId_t</b>	An enumerated value that indicates a Linkbot joint.
<b>robotRecordData_t</b>	Recorded time, angle, distance, x or y coordinate.

The data type **robotJointId\_t** is used to identify a joint on the Linkbot. Valid values for this type are listed in the table below:

Value	Description
<b>JOINT1</b>	Joint number 1 on the Linkbot.
<b>JOINT2</b>	Joint number 2 on the Linkbot.
<b>JOINT3</b>	Joint number 3 on the Linkbot.

The data type **robotRecordData\_t** is used for the member functions **recordDistanceBegin()**, **recordAngleBegin()**, and **recordxyBegin()**.

## E.2 Member Functions Available in both Classes **CLinkbotI** and **CLinkbotL**

Member functions available in both classes **CLinkbotI** and **CLinkbotL** are listed in this section. A page number following a member function indicates where the member function is introduced. If there is no page number following a member function, the function has not been presented in this book.

### **robot.blinkLED(delay, numBlinks)**

blinks the on-board LED. The argument `delay` is the amount of time between blinks. The argument `numBlinks` is the number of times to blink the LED. For example,

```
robot.blinkLED(0.1, 10);
```

### **robot.connect(), page 35**

connects a robot to be controlled. For example,

```
robot.connect();
```

### **robot.connectWithSerialID("serialID")**

connects a robot to be controlled using the serial ID. The program then does not depend on the configuration set up by BaroboLink. For example,

```
robot.connectWithSerialID("BNC2");
```

### **robot.closeGripper(), page 242**

closes a gripper. For example,

```
robot.closeGripper();
```

### **robot.delaySeconds(seconds), page 92**

makes a program pause for the number of seconds specified before moving to the next line of code. For example,

```
robot.delaySeconds(3);
```

### **robot.disconnect()**

disconnects from a remote Linkbot. For example,

```
robot.disconnect();
```

### **robot.enableRecordDataShift(), page 178**

enables the shifting of recorded data. By default, the record functions only record data while the Linkbot is in motion (data shifted). For example,

```
robot.enableRecordDataShift();
```

### **robot.disableRecordDataShift(), page 178**

disables the shifting of recorded data. By default, the record functions only record data while the Linkbot is in motion (data shifted). For example,

```
robot.disableRecordDataShift();
```

E.2. Member Functions Available in both Classes **CLinkbotI** and **CLinkbotL****robot.getAccelerometerData(x, y, z), page 156**

measures the magnitude of gravitational forces in the X, Y and Z directions and stores values in variables x, y, and z.

```
robot.getAccelerometer(x, y, z);
```

**robot.getBatteryVoltage(voltage), page 158**

measures the battery voltage and stores value in variable voltage.

```
robot.getBatteryVoltage(voltage);
```

**robot.getLEDColor(color), page 147**

passes the color of the robot's LED to the variable color. For example,

```
string_t color;
robot.getLEDColor(color);
```

**robot.getLEDColorRGB (r, g, b), page 148**

passes the color of the robot's LED in RGB values to variables r, g, and b. For example,

```
robot.getLEDColorRGB (r, g, b);
```

**robot.getJointAngle(id, angle), page 87**

gets the joint angle of a Linkbot 10 times and stores the average of the 10 joint angles (in degrees) in the variable angle. id is used to specify which joint to monitor and is written as **JOINT1**, **JOINT2**, or **JOINT3** for the respective joints. For example,

```
robot.getJointAngle(JOINT1, angle);
```

**robot.getJointAngles(angle1, angle2, angle3), Page 89**

is the same as **getJointAngle()**, but it gets the average angle value for both movable joints of a robot. Values for the average angle of each joint will be stored in the respective variables angle1, angle2, and angle3. For example,

```
robot.getJointAngles(angle1, NaN, angle3);
```

**robot.getJointAngleInstant(id, angle)**

gets a joint angle of a Linkbot (in degrees) in the variable angle. id is used to specify which joint to monitor and is written as **JOINT1**, **JOINT2**, or **JOINT3** for the respective joints. For example,

```
robot.getJointAngleInstant(JOINT1, angle);
```

**robot.getJointAnglesInstant(angle1, angle2, angle3)**

is the same as **getJointAngle()**, but it gets the angle values for both movable joints of a robot. Values for the angle of each joint will be stored in the respective variables angle1, angle2, and angle3. For example,

```
robot.getJointAnglesInstant(angle1, NaN, angle3);
```

**robot.getJointSafetyAngle(angle)**

gets the current joint safety angle limit of a robot. The default joint safety angle is 10 degrees. For example,

E.2. Member Functions Available in both Classes **CLinkbotI** and **CLinkbotL**

```
robot.getJointSafetyAngle(angle);
```

**robot.getJointSafetyAngle(seconds)**

gets the current joint safety limit timeout of a robot. The default joint safety limit timeout is 0.5 second. For example,

```
robot.getJointSafetyAngleTimeout(seconds);
```

**robot.getJointSpeed(id, speed), page 94**

gets the speed (deg/sec) of a robot's joint and stores the value in the variable `speed`.

```
robot.getJointSpeed(JOINT1, speed);
```

**robot.getJointSpeedRatio(id, ratio), page 96**

gets the speed ratio of a robot's joint and records value in the variable `ratio`. Speed ratio is the current speed compared to the maximum speed (240 degrees per second). For example,

```
robot.getJointSpeedRatio(JOINT3, ratio);
```

**robot.getJointSpeedRatios(ratio1, NaN, ratio3), page 97**

gets the speed ratios of moving joints of a robot and records values in the variables `ratio1` and `ratio3`. For example,

```
robot.getJointSpeedRatios(ratio1, NaN, ratio3);
```

**robot.getJointSpeeds(speed1, speed2, speed3), page 95**

gets the speed of both moving joints of a robot and stores value in the respective variable for that joint. For example,

```
robot.getJointSpeeds(speed1, NaN, speed3);
```

**robot.holdJoint(id), page 241**

holds a joint of the robot. For example,

```
robot.holdJoint(JOINT1);
```

**robot.holdJoints(), page 189**

holds all the joints of the robot. For example,

```
robot.holdJoints();
```

**robot.holdJointsAtExit(), page 114**

holds all the joints of the robot when the program finishes (exits). For example,

```
robot.holdJointsAtExit();
```

**robot.isConnected()**

checks if currently connected to a remote robot. For example,

```
if(robot.isConnected()) {
    printf("connecting to the robot successful\n");
}
```

E.2. Member Functions Available in both Classes **CLinkbotI** and **CLinkbotL****robot.isMoving()**

checks if the robot is moving any of its joints. For example,

```
if(robot.isMoving()) {
    printf("robot is moving\n");
}
```

**robot.move(angle1, angle2, angle3), page 36**

moves a robot's joints relative to their current positions by corresponding values of angle1, angle2, and angle3. For example,

```
linkboti.move(90, NaN, -90);
linkbotl.move(NaN, 30, 90);
```

**robot.moveForeverNB()**

moves joints forever, while allowing the next lines of code to begin before the function **moveForeverNB()** has finished executing. For example,

```
robot.moveForeverNB();
```

**robot.moveJoint(id, angle), page 91**

is the same as the **move()** function but allows you to specify just one joint to move. For example,

```
robot.moveJoint(JOINT3, 90);
```

**robot.moveJointNB(id, angle), page 164**

A non-blocking version of **moveJoint()**.

**robot.moveJointByPowerNB(id, power), page 207**

moves a joint by setting the motor power of the joint. The specified power can be an integer from -100 to +100. For example,

```
robot.moveJointByPowerNB(JOINT1, 90);
```

**robot.moveJointForeverNB(id), page 189**

moves joints forever, while allowing the next lines of code to begin before the function **moveJointForeverNB()** has finished executing. For example,

```
robot.moveJointForeverNB(JOINT1);
```

**robot.moveJointTime(id, seconds), page 113**

move a joint for a specified time in seconds. For example,

```
robot.moveJointTime(JOINT1, 5);
```

**robot.moveJointTimeNB(id, seconds), page 183**

A non-blocking version of **moveJointTime()**.

**robot.moveJointTo(id, angle), page 90**

is the same as the **moveTo()** function but allows you to specify just one joint to move. For example,

```
robot.moveJointTo(JOINT2, 90);
```

E.2. Member Functions Available in both Classes **CLinkbotI** and **CLinkbotL****robot.moveJointToNB(id, angle), page 171**

A non-blocking version of **moveJointTo()**.

**robot.moveJointToByTrackPos(id, angle)**

is the same as the **moveToByTrackPos()** function but allows you to specify just one joint to move.

For example,

```
robot.moveJointToByTrackPos(JOINT2, 90);
```

**robot.moveJointToByTrackPosNB(id, angle)**

A non-blocking version of **moveJointToByTrackPos()**.

**robot.moveJointWait(id), page 165**

pauses the program until the movement of the specified joint, `id`, has stopped its current motion. For example,

```
robot.moveJointWait(JOINT1);
```

**robot.moveNB(angle1, angle2, angle3), page 169**

A non-blocking version of **move()**.

**robot.moveTo(seconds), page 112**

moves joints for a specified time in seconds. For example,

```
robot.moveTo(5);
```

**robot.moveToNB(seconds)**

A non-blocking version of **moveTime()**.

**robot.moveTo(angle1, angle2, angle3), page 86**

moves the respective joints of a robot to the absolute position of the specified angles. This is different from the **move()** function which moves the joints an angle relative to its current position. For example,

```
robot.moveTo(120, NaN, -120);
```

**robot.moveToNB(angle1, angle2, angle3), page 170**

A non-blocking version of **moveTo()**.

**robot.moveToByTrackPos(angle1, angle2, angle3), page 205**

moves the respective joints of a robot to the absolute position of the specified angles by tracking the positions during the motion. This is different from the **moveTo()** function which moves the joints based on the specified joint speed. For example,

```
robot.moveToByTrackPos(120, NaN, -120);
```

**robot.moveToByTrackPosNB(angle1, angle2, angle3), page 205**

A non-blocking version of **moveToByTrackPos()**.

**robot.moveToZero()**

moves all joints of a robot to their zero position. Unlike **resetToZero()**, **moveToZero()** will rewind each joint to zero position even for multiple turns. For example,

E.2. Member Functions Available in both Classes **CLinkbotI** and **CLinkbotL**

```
robot.moveToZero();
```

**robot.moveToZeroNB()**

A non-blocking version of **moveToZero()**.

**robot.moveWait(), page 166**

pauses the program until the movement of *all* the joints of a robot have finished moving.

**robot.openGripper(angle), page 242**

opens a gripper with a specified angle in degrees. For example,

```
robot.openGripper(90);
```

**robot.recordAngleBegin(id, timedata, angledata, timeinterval), page 109**

begins recording data points of time and joint angle stored in the variables, `timedata` and `angledata`. `id` specifies which joint to record data for and `timeinterval` is used to tell how often the program should record data points (in seconds). For example,

```
robot.recordAngleBegin(JOINT1, timedata, angledata, 0.1);
```

**robot.recordAngleEnd(id, numDataPoints), page 110**

ends the recording started by the member function **recordAngleBegin()** and passes the number of data points collected in the variable `numDataPoints`. For example,

```
robot.recordAngleEnd(JOINT1, numDataPoints);
```

**robot.relaxJoint(id)**

relaxes a joint of robot. For example,

```
robot.relaxJoint(JOINT1);
```

**robot.relaxJoints(), page 207**

relaxes all joints of robot. For example,

```
robot.relaxJoints();
```

**robot.resetToZero(), page 36**

resets the robot's joints to their absolute zero positions.

**robot.resetToZeroNB(), page 168**

A non-blocking version of **resetToZero()**.

**robot.setBuzzerFrequencyOff(), page 151**

turns off the robot buzzer. For example,

```
robot.setBuzzerFrequencyOff();
```

**robot.setBuzzerFrequencyOn(frequency), page 151**

turns on the robot buzzer with a specified frequency (in Hz). For example,

```
robot.setBuzzerFrequencyOn(450);
```

E.2. Member Functions Available in both Classes **CLinkbotI** and **CLinkbotL****robot.setLEDColor("color"), pages 42**

sets the robot LED to the specified color. For example,

```
robot.setLEDColor("blue");
```

**robot.setLEDColorRGB(r, g, b), page 148**

sets the color of the robot's LED in RGB values. For example,

```
robot.setLEDColorRGB(160, 32, 240);
```

**robot.setJointSafetyAngle(angle), page 243**

sets the joint safety angle in degrees for a robot. The default joint safety angle is 10 degrees. For example,

```
robot.setJointSafetyAngle(50);
```

**robot.setJointSafetyAngleTimeout(seconds)**

sets the joint safety angle limit timeout of a robot in seconds. The default joint safety angle limit timeout is 0.5 seconds. For example,

```
robot.setJointSafetyAngleTimeout(1.5);
```

**robot.setJointSpeed(id, speed), page 94**

sets the speed of a robot joint in degrees per second. For example,

```
robot.setJointSpeed(JOINT1, 90);
```

**robot.setJointSpeedRatio(id, ratio), page 96**

sets the speed ratio of a robot joint. For example,

```
robot.setJointSpeedRatio(JOINT3, speedratio);
```

**robot.setJointSpeedRatios(ratio1, NaN, ratio3), page 98**

sets the speed ratios of moving joints of a robot. For example,

```
robot.setJointSpeedRatios(ratio1, NaN, ratio3);
```

**robot.setJointSpeeds(speed1, speed2, speed3), page 95**

sets the speed of both moving joints of a robot in degrees per second. For example,

```
robot.setJointSpeeds(speed1, NaN, speed3);
```

**robot.systemTime(time), page 115**

records the time in seconds since the system last started (Windows) or since 00:00:00 January 1, 1970 (Mac OS X and Linux). For example,

```
robot.systemTime(time1);
... (Code to be timed) ...
robot.systemTime(time2);
elapsedtime = time2 - time1;
```

## E.3 Member Functions Available only in the Class **CLinkbotI**

Member functions available only in class **CLinkbotI** for a two-wheel robot are listed in this section.

### **robot.driveBackward(angle), page 38**

drives both joints of a Linkbot-I backward by the specified angle. For example,

```
robot.driveBackward(360);
```

### **robot.driveBackwardNB(angle), page 174**

A non-blocking version of **driveBackward()**.

### **robot.driveDistance(distance, radius), page 72**

drives a two wheel robot a specified distance given its wheel radius. For example,

```
robot.driveDistance(10, 1.75);
```

### **robot.driveDistanceNB(distance, radius), page 174**

A non-blocking version of **driveDistance()**.

### **robot.driveForeverNB(), page 188**

drives a Linkbot-I forever, while allowing the next lines of code to begin before the function **driveForeverNB()** has finished executing. For example,

```
robot.driveForeverNB();
```

### **robot.driveForward(angle), page 38**

drives both joints of a Linkbot-I (a two wheel robot) forward by the specified angle. For example,

```
robot.driveForward(360);
```

### **robot.driveForwardNB(angle), page 174**

A non-blocking version of **driveForward()**.

### **robot.driveTime(seconds), page 136**

drives a Linkbot-I for a specified time in seconds. For example,

```
robot.driveTime(5);
```

### **robot.driveTimeNB(seconds), page 182**

A non-blocking version of **driveTime()**.

### **robot.getDistance(distance, radius), page 122**

records the distance that a Linkbot-I has moved using a specified wheel radius. For example,

```
robot.getDistance(distance, 1.75);
```

### **robot.recordDistanceBegin(id, time, distance, radius, timeInterval), page 126**

begins recording the time and distance of a robot joint in variables `time` and `distance` (of type **robotRecordData\_t**) given the specified wheel radius. `timeInterval` is the time interval between measurements. For example,

## E.4. Member Functions Available in Both Classes **CLinkbotIGroup** and **CLinkbotLGroup**

```
robot.recordDistanceBegin(JOINT1, timedata, distances, 1.75, 0.1);
```

### **robot.recordDistanceEnd(id, numDataPoints), page 126**

ends the **recordDistanceBegin()** function and passes the number of data points collected in the variable **numDataPoints**. For example,

```
robot.recordDistanceEnd(JOINT1, numDataPoints);
```

### **robot.recordDistanceOffset(offset), page 129**

creates an offset so that when the **recordDistanceBegin()** function is called, each distance value will add an offset value. For example,

```
robot.recordDistanceOffset(2);
```

### **robot.setSpeed(speed, radius), page 119**

sets joints 1 and 3 of a Linkbot-I to the desired speed with the specified wheel radius. For example,

```
robot.setSpeed(4, 1.75);
```

### **robot.turnLeft(angle, radius, trackwidth), page 73**

turns a two wheel robot left by a specified angle, given the wheel radius and trackwidth (distance between the two wheels). For example,

```
robot.turnLeft(90, 1.75, 3.69);
```

### **robot.turnLeftNB(angle, radius, trackwidth), page 174**

A non-blocking version of **turnLeft()**.

### **robot.turnRight(angle, radius, trackwidth), page 73**

turns a two wheel robot left or right by a specified angle, given the wheel radius and trackwidth. For example,

```
robot.turnRight(90, 1.75, 3.69);
```

### **robot.turnRightNB(angle, radius, trackwidth), page 174**

A non-blocking version of **turnRight()**.

## E.4 Member Functions Available in Both Classes **CLinkbotIGroup** and **CLinkbotLGroup**

Member functions available only in classes **CLinkbotIGroup** and **CLinkbotLGroup** are listed first in this section. Most member functions in classes **CLinkbotI** and **CLinkbotL** are available in classes **CLinkbotIGroup** and **CLinkbotLGroup**. They are listed in a table in this section.

### **group.addRobot(name), page 77**

adds a robot using the robot's declared name to the class **CLinkbotIGroup** or **CLinkbotLGroup**. For example,

```
group.addRobot(robot1);
```

E.4. Member Functions Available in Both Classes **CLinkbotIGroup** and **CLinkbotLGroup****group.addRobots(name), page 81**

adds an array of robots to a group using the robot array's declared name. For example,

```
CLinkbotI robot[4];  
group.addRobots(robot);
```

E.4. Member Functions Available in Both Classes **CLinkbotIGroup** and **CLinkbotLGroup**

Member Function Name	Description
<b>addRobot()</b>	Add a Linkbot as a member of the Linkbot group.
<b>addRobots()</b>	Add Linkbots to the Linkbot group.
<b>closeGripper()</b>	Close the gripper.
<b>driveDistance()</b>	Drive each Linkbot-I in the group a certain distance.
<b>driveDistanceNB()</b>	Identical to <b>driveDistance()</b> but non-blocking.
<b>driveBackward()</b>	Drive each Linkbot-I backward.
<b>driveBackwardNB()</b>	Identical to <b>driveBackward()</b> but non-blocking.
<b>driveForeverNB()</b>	Drive each Linkbot-I forever until stopped.
<b>driveForward()</b>	Drive each Linkbot-I forward.
<b>driveForwardNB()</b>	Identical to <b>driveForward()</b> but non-blocking.
<b>driveTime()</b>	Drive each Linkbot-I for a specified time.
<b>driveTimeNB()</b>	Identical to <b>driveTime()</b> but non-blocking.
<b>holdJoint()</b>	Hold a joint for all Linkbots in the group.
<b>holdJoints()</b>	Hold all the joints for all Linkbots in the group.
<b>holdJointsAtExit()</b>	Hold all the joints at exit for all Linkbots in the group.
<b>isConnected()</b>	Check if a robot is connected to a program.
<b>isMoving()</b>	Check if any joint of a robot is moving.
<b>move()</b>	Move two joints of each Linkbot by specified angles.
<b>moveForeverNB()</b>	Move joints forever till stopped.
<b>moveNB()</b>	Identical to <b>move()</b> but non-blocking.
<b>moveJoint()</b>	Move a joint from its current position by an angle.
<b>moveJointNB()</b>	Identical to <b>moveJoint()</b> but non-blocking.
<b>moveJointByPowerNB()</b>	Move a joint by setting the power of the joint motor.
<b>moveJointForeverNB()</b>	Move a joint forever. A joint will move until stopped.
<b>moveJointTime()</b>	Move a joint for a specified time.
<b>moveJointTimeNB()</b>	Identical to <b>moveJointTime()</b> but non-blocking.
<b>moveJointTo()</b>	Set the desired joint position for a joint.
<b>moveJointToNB()</b>	Identical to <b>moveJointTo()</b> but non-blocking.
<b>moveJointToByTrackPos()</b>	Move a joint to the specified position by tracking its position.
<b>moveJointToByTrackPosNB()</b>	Identical to <b>moveJointToByTrackPos()</b> , but non-blocking.
<b>moveJointWait()</b>	Wait until the specified motor has stopped moving.
<b>moveTime()</b>	Move joints for a specified time.
<b>moveTimeNB()</b>	Identical to <b>moveJointTime()</b> but non-blocking.
<b>moveTo()</b>	Move two joints of each Linkbot to specified absolute angles.
<b>moveToNB()</b>	Identical to <b>moveTo()</b> but non-blocking.
<b>moveToByTrackPos()</b>	Move two joints to the specified positions by tracking positions.
<b>moveToByTrackPosNB()</b>	Identical to <b>moveToByTrackPos()</b> , but non-blocking.
<b>moveToZero()</b>	Instructs all motors to go to their zero positions.
<b>moveToZeroNB()</b>	Identical to <b>moveToZero()</b> but non-blocking.
<b>moveWait()</b>	Wait until all motors have stopped moving.
<b>openGripper()</b>	Open the gripper.
<b>relaxJoint()</b>	Relax a joint of the Linkbot.
<b>relaxJoints()</b>	Relax all the joints of the Linkbot.

## E.5. Member Functions Available only in RoboSim

Member Function Name	Description
<b>setJointSpeed()</b>	Set a motor's speed in degrees per second.
<b>setJointSpeeds()</b>	Set all motor speeds in degrees per second.
<b>setJointSpeedRatio()</b>	Set a joint speed to a fraction of its maximum speed.
<b>setJointSpeedRatios()</b>	Set joint speeds to a fraction of their maximum speeds.
<b>setSpeed()</b>	Move the Linkbots at a constant velocity.
<b>turnLeft()</b>	Rotate the Linkbot-Is counter clockwise.
<b>turnLeftNB()</b>	Identical to <b>turnLeft()</b> but non-blocking.
<b>turnRight()</b>	Rotate the Linkbot-Is clockwise.
<b>turnRightNB()</b>	Identical to <b>turnRight()</b> but non-blocking.

## E.5 Member Functions Available only in RoboSim

Member functions for a single Linkbot available only in RoboSim are listed in this section.

### **robot.drivexy(x, y, radius, trackwidth), page 275**

drives a Linkbot-I by x and y relative to its current position in the x-y coordinate system given the radius and track width of the Linkbot-I. For example,

```
robot.drivexy(3, 4, 1.75, 3.69);
```

### **robot.drivexyNB(x, y, radius, trackwidth), page 300**

A non-blocking version of **drivexy()**.

### **robot.drivexyTo(x, y, radius, trackwidth), page 266**

drives a Linkbot-I to the location of (x,y) in the x-y coordinate system given the radius and trackwidth. For example,

```
robot.drivexyTo(3, 4, 1.75, 3.69);
```

### **robot.drivexyToExpr(x0, xf, num, expr, radius, trackwidth), page 283**

drives a Linkbot-I based on an expression with the variable x, for x from x0 to xf with num number of points. The expression t Expr should be a valid Ch expression in terms of the variable x. The radius and track width of the robot are specified by the last two arguments. For example,

```
robot.drivexyToExpr(0, 5, 100, "2+3*x", 1.75, 3.69);
```

### **robot.drivexyToFunc(x0, xf, num, func, radius, trackwidth), page 279**

drives a Linkbot-I based on a function func(), for x from x0 to xf with num number of points. The radius and track width of the Linkbot-I are specified by the last two arguments. For example,

```
double func(double x) {
    return 2+3*x;
}
robot.drivexyToFunc(0, 5, 100, func, 1.75, 3.69);
```

### **robot.drivexyNB(x, y, radius, trackwidth), page 298**

A non-blocking version of **drivexyTo()**.

## E.6. Member Functions Not Presented in This Book

**robot.driveXYWait(), page 299**

pauses the program until the movement of a Linkbot-I by the function **driveXYNB()** or **driveXYToNB()** is finished moving. For example,

```
robot.driveXYWait();
```

**robot.getXY(x, y), page 267**

gets the position of a Linkbot-I in the x-y coordinate system and stores the coordinates in variables **x** and **y**.

**robot.line(x1, y1, z1, x2, y2, z2, linewidth, "color"), page 292**

creates a line in the RoboSim environment from  $(x_1, y_1, z_1)$  to  $(x_2, y_2, z_2)$ . For example,

```
robot.line(9, 18, 0, 15, 18, 0, 4, "purple");
```

**robot.point(x, y, z, pointsize, "color"), page 291**

creates a point in the RoboSim environment to be used as an obstacle or point of reference. Point size can be integers 1 through 5. For example,

```
robot.point(6, 6, 0, 1, "red");
```

**robot.recordXYBegin(xdata, ydata, timeInterval), page 288**

begins recording the position  $(x, y)$  in the x-y coordinate system for a Linkbot-I variables **xdata** and **ydata** (of type **robotRecordData\_t**). **timeInterval** is the time interval between position readings. For example,

```
robot.recordXYBegin(xdata, ydata, 0.1);
```

**robot.recordXYEnd(xdata, ydata, timeInterval), page 288**

ends the **recordXYBegin()** function and passes the number of data points collected in the variable **numDataPoints**. For example,

```
robot.recordXYEnd(numDataPoints);
```

**robot.text(x, y, z, "text"), page 292**

creates text in the RoboSim environment centered at the point  $(x, y, z)$ . For example,

```
robot.text(6, 6, 0, "(6, 6)");
robot.text(12, 18, 0, "This is a wall.");
```

**robot.traceOff(), page 285**

turns off tracing for a Linkbot.

```
robot.traceOff();
```

**robot.traceOn(), page 285**

turns on tracing for a Linkbot.

```
robot.traceOn();
```

## E.6 Member Functions Not Presented in This Book

**blinkLED(), connectWithAddress(), disconnect(), getJointAngleInstant(), getJointAnglesInstant(), getJointSafetyAngle(), getJointSafetyAngleTimeout(), isConnected(), isMoving(), moveJointToByTrackPos(), moveJointToByTrackPosNB(), moveTimeNB(), moveForeverNB(), moveToZero(), moveToZeroNB(), relaxJoint(), setJointSafetyAngleTimeout().**

---

---

## APPENDIX F

---

# Common Mistakes in Writing Ch Programs

This appendix summarizes common mistakes in writing programs in Ch.

1. Divide two integers. Note that  $3/2$  is 1 and  $3.0/2$  is 1.5.
2. Miss a semicolon ';' at the end of a programming statement. For example

```
int i, j  
i = 120
```

3. Miss a newline character '\n'. For example,

```
printf("Hello, world");
```

4. Use '/n' for a newline character. For example,

```
printf("Hello, world/n");
```

5. Use '\n' in the function **scanf()**. For example,

```
scanf("%d\n", &n);
```

6. Miss the header file **math.h**

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

for using **M.PI** for  $\pi$ .

7. Miss the header file **chplot.h**

```
#include <chplot.h>
```

for using the plotting class **CPlot**.

8. Use variables without declaring them first.

- (a) Use a variable, `y1`, not defined.
- (b) Use a variable of capital letter. For example,

```
Printf("Hello, world\n");
double subtotal;
Subtotal = 10;
```

9. Use the conversion specifier "%lf", instead of "%d", to output from or input into a variable **int** type.  
For example,

```
int n;
printf("n = %lf\n", n);
scanf("%lf", &n);
```

10. Use the conversion specifier "%d", instead of "%lf", to output from or input into a variable **double** type. For example,

```
double x;
printf("x = %d\n", n);
scanf("%d", &x);
```

11. Miss a **moveWait()** statement at the end of a program. For example,

```
robot1.driveForwardNB(360);
robot2.driveForward(180);
/* without the statement below,
   robot1 will only drive forward 180 degrees. */
robot1.moveWait();
```

---

---

## APPENDIX G

---

# Porting Code to the Latest Version

## G.1 Port Code to BaroboLink v1.6.9, RoboSim v1.8, Robotics Curriculum v1.8

The changes made in BaroboLink v1.6.9 and C-STEM Robotics Curriculum v1.8 on July 27, 2014 are listed in this section.

1. Replace these member functions

```
jumpTo()  
jumpToNB()  
jumpJointTo()  
jumpJointToNB()  
setJointPower()
```

by the following new member functions for Linkbots.

```
moveToByTrackPos()  
moveToByTrackPosNB()  
moveJointToByTrackPos()  
moveJointToByTrackPosNB()  
moveJointByPowerNB()
```

## G.2 Port Code to BaroboLink v1.6.8, RoboSim v1.7, Robotics Curriculum v1.7, Math Curriculum v1.2

The changes made in BaroboLink v1.6.8, RoboSim v1.7, C-STEM Robotics Curriculum v1.7, and C-STEM Math Curriculum v1.2 on July 11, 2014 are listed in this section.

1. Replace these member functions:

```
moveDistance()
moveDistanceNB()
moveForward()
moveForwardNB()
moveBackward()
moveBackwardNB()
moveTime()
moveTimeNB()
moveForeverNB()
movexy()
movexyNB()
movexyTo()
movexyToNB()
movexyToExpr()
movexyToFunc()
movexyWait()
setMotorPower()
```

by these new member functions for controlling two-wheel robots based on the speed of the first joint for Linkbot-I:

```
driveDistance()
driveDistanceNB()
driveForward()
driveForwardNB()
driveBackward()
driveBackwardNB()
driveTime()
driveTimeNB()
driveForeverNB()
drivexy()
drivexyNB()
drivexyTo()
drivexyToNB()
drivexyToExpr()
drivexyToFunc()
drivexyWait()
setJointPower()
```

2. Handling these member functions for controlling Linkbots based on the sign of the speeds for each joint.

```
moveTime()
moveTimeNB()
moveForeverNB()
```

3. Replace

```
getJointAngleAverage()
getJointAnglesAverage()
getJointAngle()
getJointAngles()
```

by

```
getJointAngle()
getJointAngles()
getJointAngleInstant()
getJointAnglesInstant()
```

#### 4. Replace

```
driveTo()
driveToNB()
driveJointTo()
driveJointToNB()
```

by

```
jumpTo()
jumpToNB()
jumpJointTo()
jumpJointToNB()
```

## G.3 Port Code to BaroboLink v1.6.7, RoboSim v1.6, Robotics Curriculum v1.6, Math Curriculum v1.1

#### 1. Replace these member functions:

```
setMovementStateNB()
setJointMovementStateNB()
setMovementStateTime()
setMovementStateTimeNB()
setJointMovementStateTime()
setJointMovementStateTimeNB()
stopAllJoints()
setExitState()
setTwoWheelRobotSpeed()
getColor()
getColorRGB()
setColor()
setColorRGB()
```

by these new member functions:

```

moveTime(time)
moveJointTime(id, time)
moveTimeNB(time)
moveJointTimeNB(id, time)
setSpeed(speed, radius)
moveForeverNB()
moveJointForeverNB(id)
holdJoint(id)
holdJoints()
holdJointsAtExit()
relaxJoint(id)
relaxJoints()
getLEDColor()
getLEDColorRGB()
setLEDColor()
setLEDColorRGB()

```

2. Replace these macros

```

ROBOT_JOINT1
ROBOT_JOINT2
ROBOT_JOINT3

```

by these new macros

```

JOINT1
JOINT2
JOINT3

```

3. Phased out these macros:

```

ROBOT_FORWARD
ROBOT_BACKWARD
ROBOT_HOLD
ROBOT_NEUTRAL

```

4. Phased out this data type:

```
robotJointState_t
```

5. A joint speed can be negative value. When the speed is positive, a joint moves in count clockwise direction. When the speed is negative, a joint moves in clockwise direction.
6. The speed for a two-wheel vehicle can be negative value. If the speed is positive, the robot will move forward. If the speed is negative, the robot will move backward.
7. Replace **setTwoWheelRobotSpeed()** by **setSpeed()**.
8. Replace **stopAllJoints()** by **relaxJoints()**.

9. Replace **setExitState()** by **holdJointsAtExit()**.
10. Replace **getColor()**, **getColorRGB()** **setColor()**, and **setColorRGB()** by **getLEDColor()**, **getLED-ColorRGB()**, **setLEDColor()**, and **setLEDColorRGB()**, respectively.
11. Replace **ROBOT\_JOINT1** by **JOINT1**.
12. Replace

```
robot1.setJointMovementStateTimeNB(ROBOT_JOINT1, ROBOT_FORWARD, time);
robot2.setJointMovementStateTime(ROBOT_JOINT1, ROBOT_FORWARD, time);
robot3.setMovementStateTimeNB(ROBOT_FORWARD, NaN, ROBOT_FORWARD, time);
robot4.setMovementStateTime(ROBOT_FORWARD, NaN, ROBOT_FORWARD, time);
robot5.setJointMovementStateNB(ROBOT_JOINT1, ROBOT_FORWARD);
robot6.setMovementStateNB(ROBOT_FORWARD, NaN, ROBOT_FORWARD);
```

by

```
robot1.moveJointTimeNB(JOINT1, time);
robot2.moveJointTime(JOINT1, time);
robot3.moveToTimeNB(time);
robot4.moveToTime(time);
robot5.moveJointForeverNB(JOINT1);
robot6.moveForeverNB();
```

13. Replace

```
robot5.setJointMovementStateNB(ROBOT_JOINT1, ROBOT_HOLD);
robot6.setMovementStateNB(ROBOT_HOLD, NaN, ROBOT_HOLD);
```

by

```
robot5.holdJoint(JOINT1);
robot6.holdJoints();
```

14. Replace

```
robot1.setSpeed(speed, radius);
robot2.setSpeed(speed, radius);
robot1.setMovementStateTimeNB(ROBOT_BACKWARD, NaN, ROBOT_BACKWARD, time);
robot2.setMovementStateNB(ROBOT_BACKWARD, NaN, ROBOT_BACKWARD);
```

by

```
robot1.setSpeed(-speed, radius);
robot2.setSpeed(-speed, radius);
robot1.moveToTimeNB(time);
robot2.moveForeverNB();
```

---

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