

Lesson 7 - Control The Robot Arm

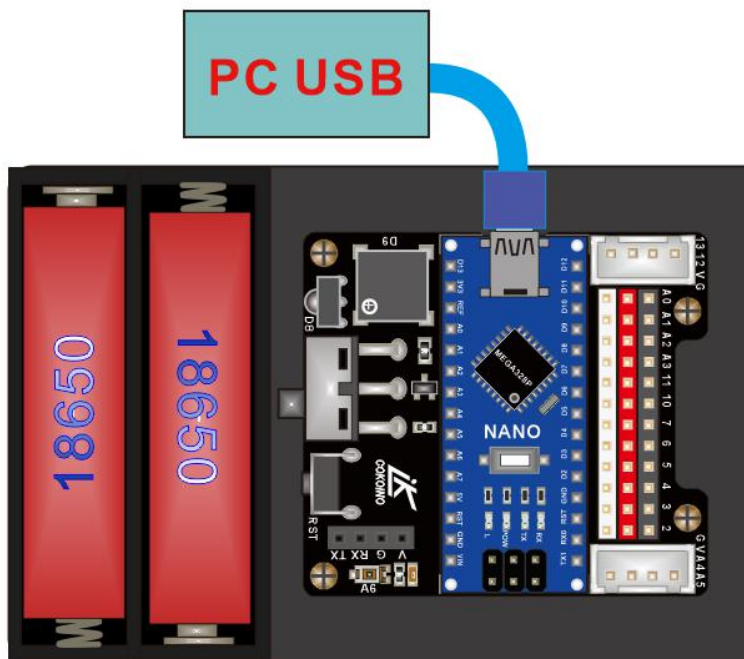
1. Upload the code

After the robotic arm is assembled, install two 18650 batteries to it and turn on the power switch of the nano shield, connect the nano board to the USB port of the PC.

NOTE:

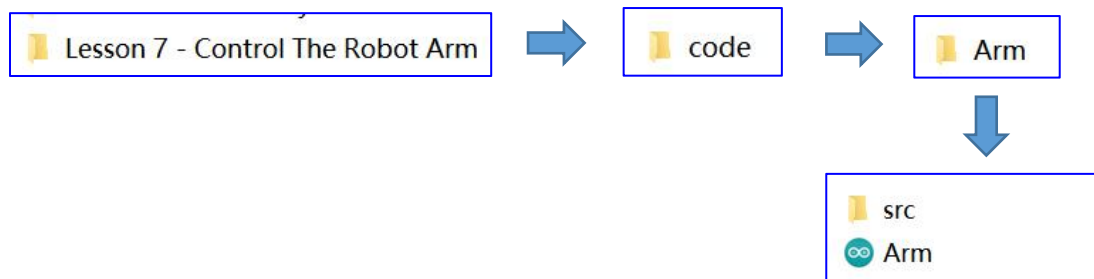
Turn on the power switch of the shield since the current provided by the usb is not enough to drive the servos

Make sure your two 18650 batteries have enough power

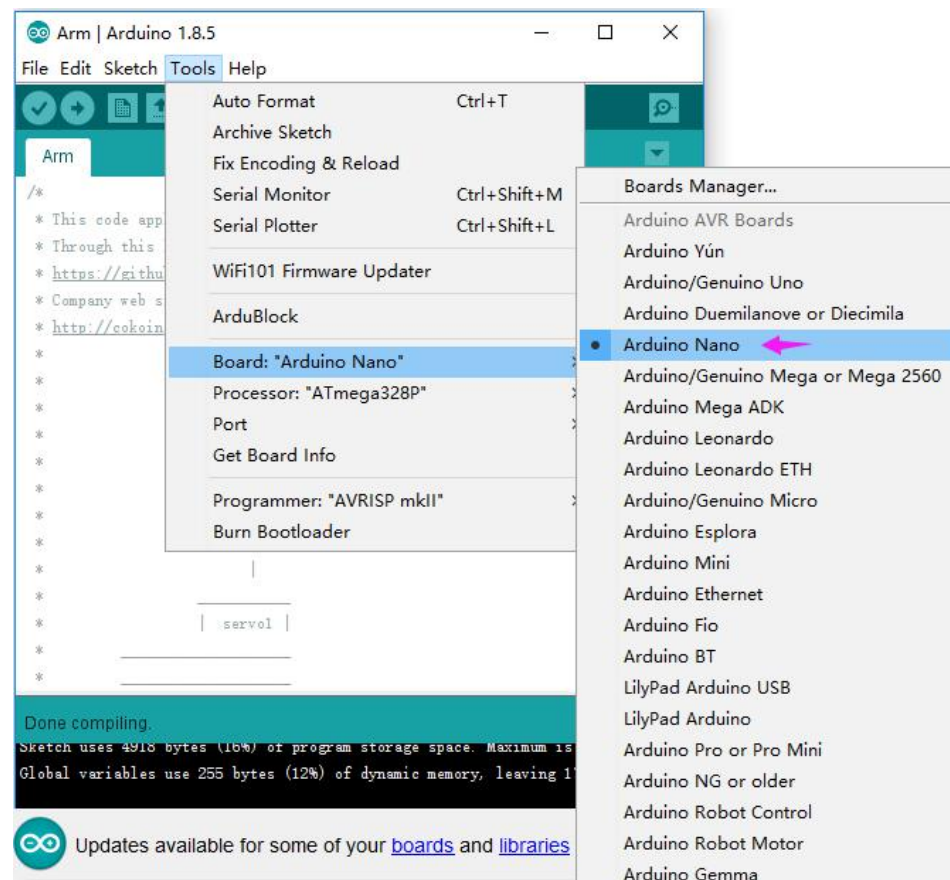


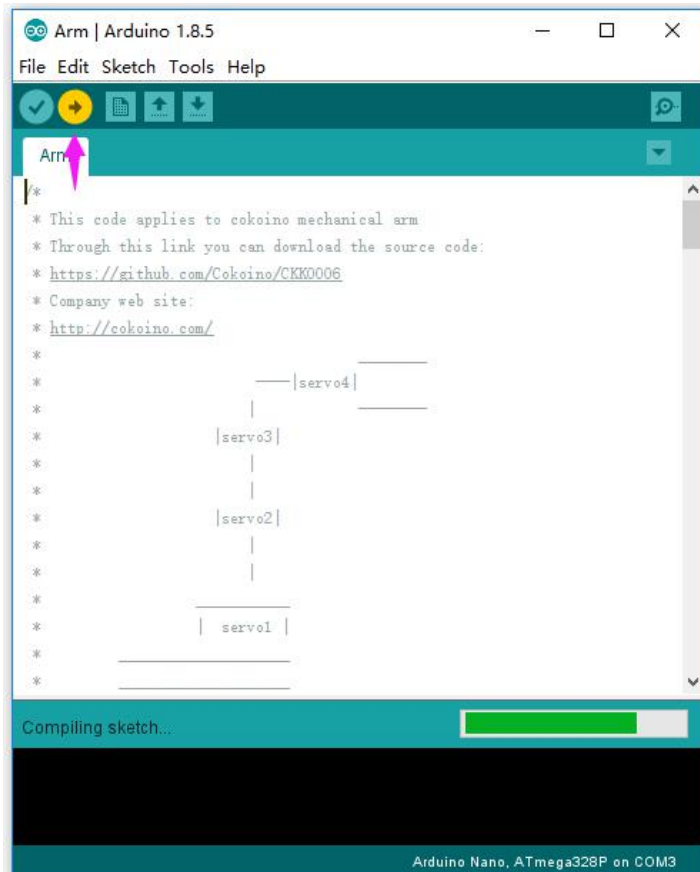
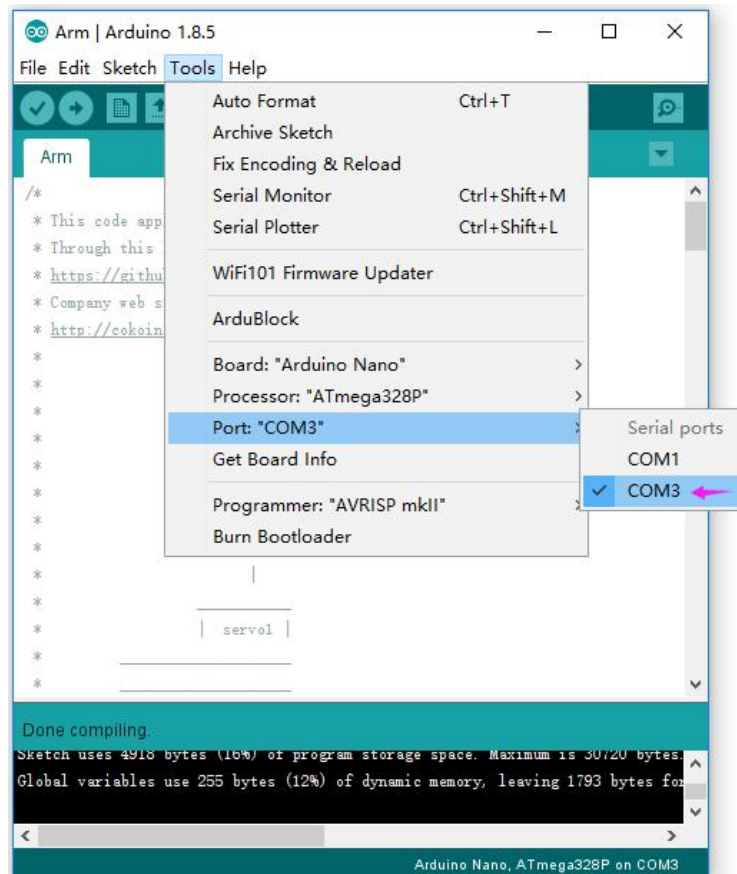
Find the "**Arm**" code from the following path, open it with the Arduino IDE and select the board type and com port of the IDE.

Note: The src folder cannot be moved, it must be placed in the Arm folder with the "**Arm**" code, otherwise, your code will not be uploaded.



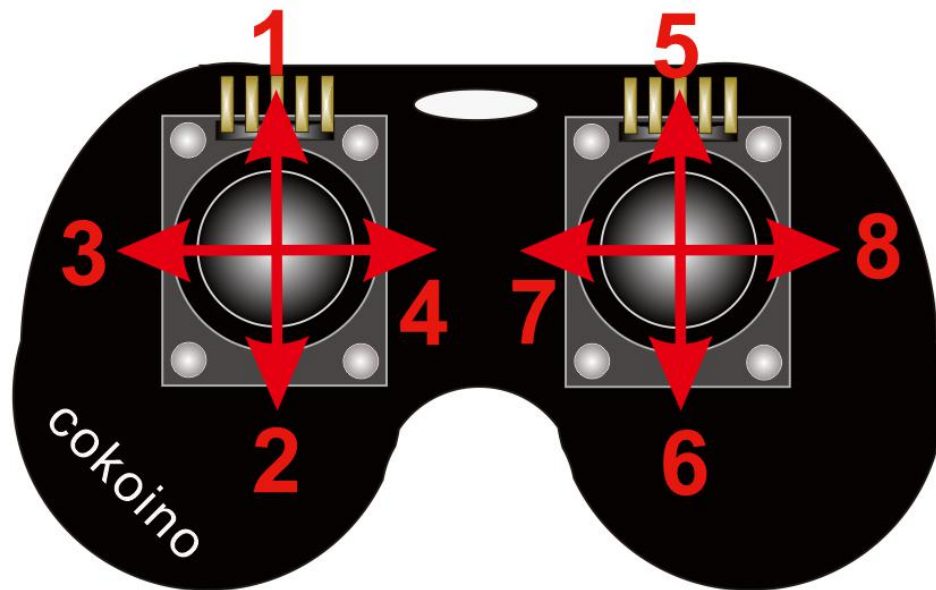
Open the Arm code with Arduino IDE, select the correct board type and com port, and upload the code.



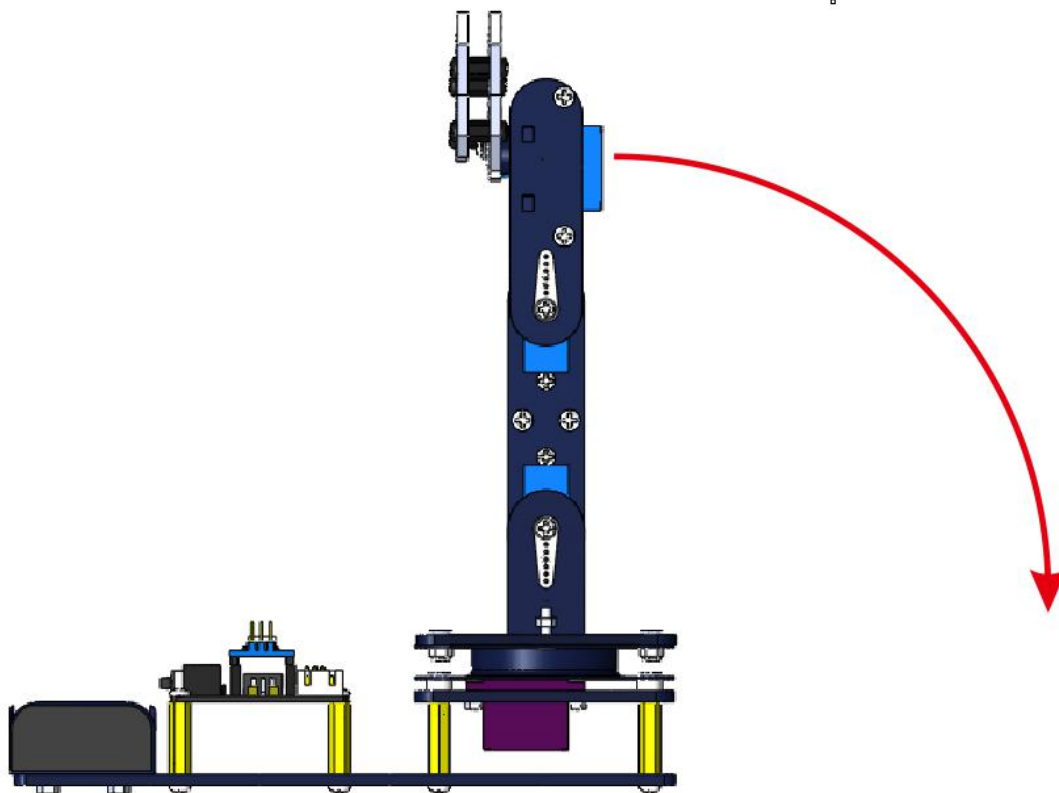


2. How to control the robotic arm

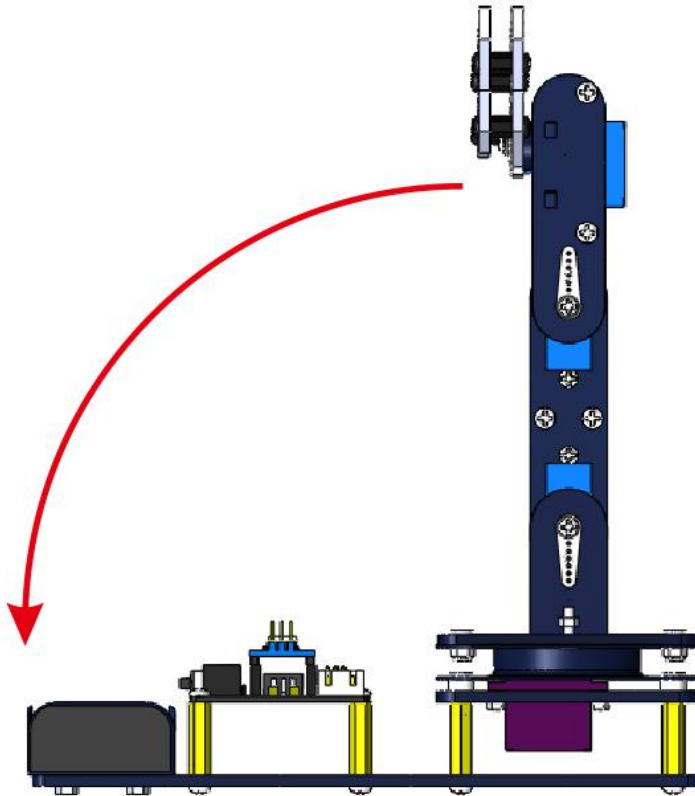
The following explains how the joystick controller controls the robot work by marking the direction of the joystick controller with numbers.:



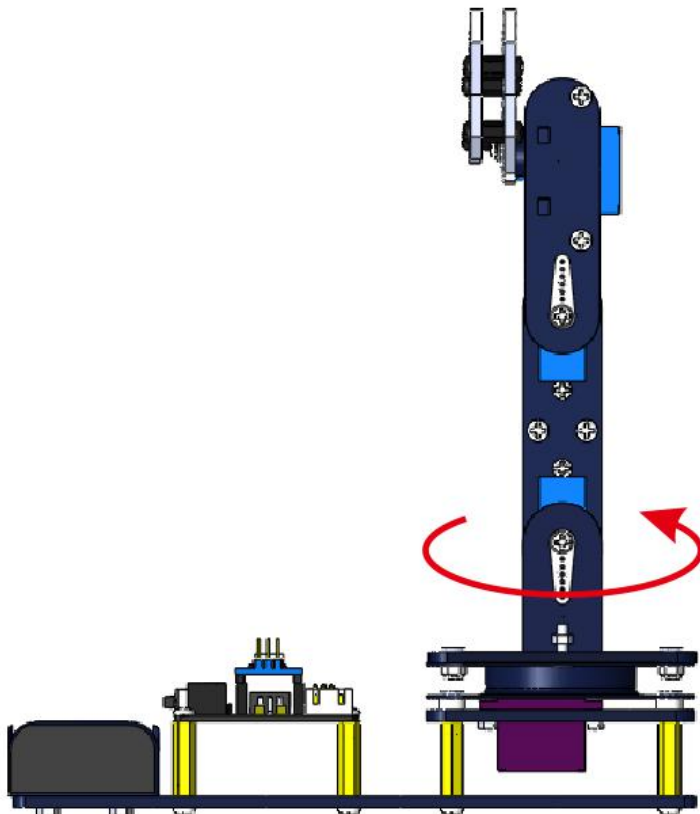
Number 1: The robotic arm stretches forward



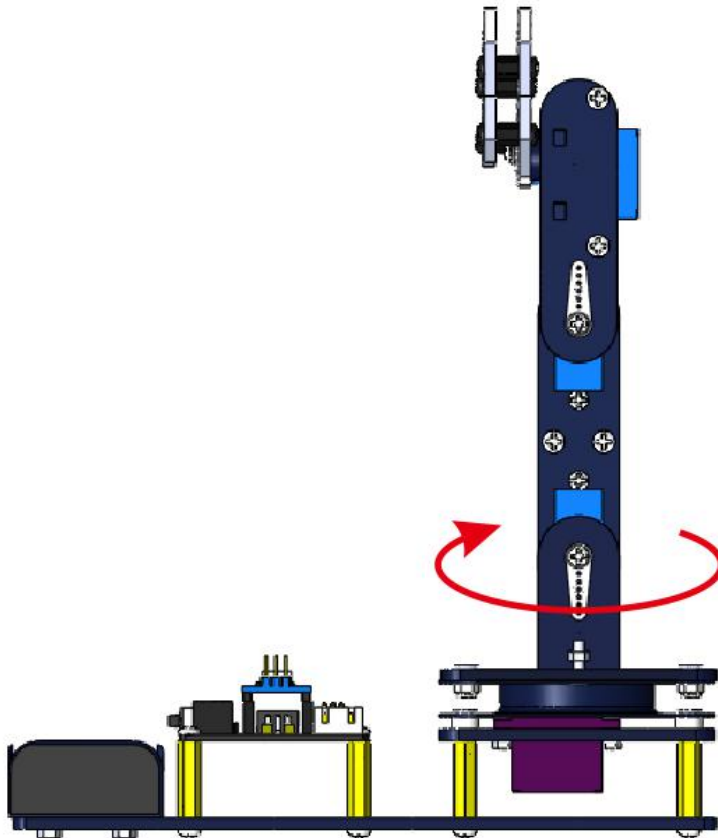
Number 2: Robot arm stretches back



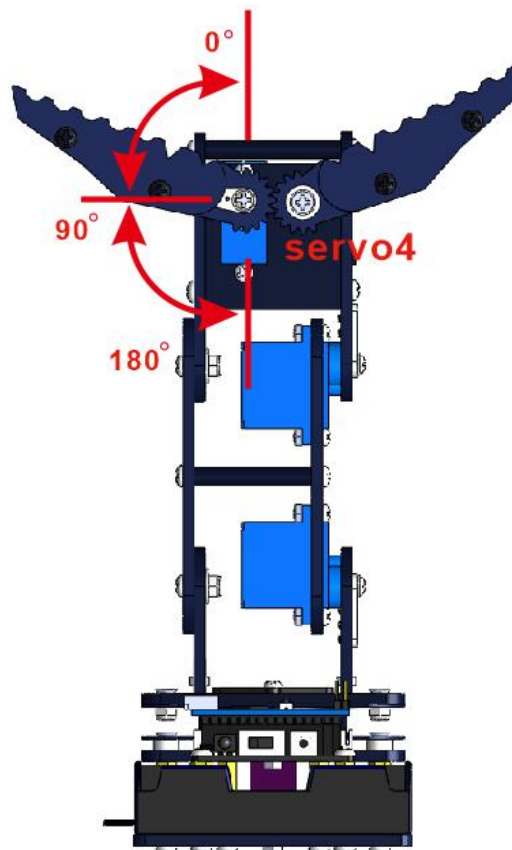
Number 3: The base of the robotic arm rotates to the left



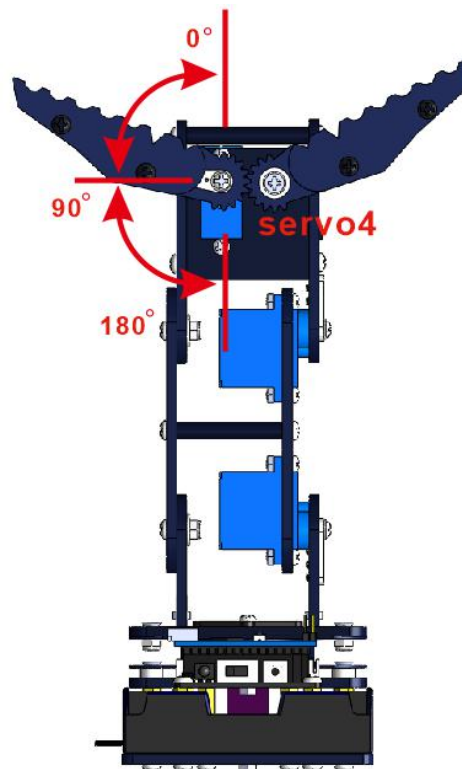
Number 4: The base of the robotic arm rotates to the right



Number 5: Claw of robotic arm close up



Number 6: The claw of the robot arm opens



Number 7: Record an action

Push the right joystick to the left direction once (number 7 direction), and an action will be recorded. In the program we provide, the robotic arm can record up to 10 actions continuously. When the robot records 10 actions, the buzzer will sound once, and then it will start to record 10 actions repeatedly. After 10 actions are completed, the buzzer will sound again. once.

Number 8: Perform recorded actions

Push the right joystick to the right direction (number 8 direction), the buzzer will sound and the robot will perform the recorded action, after the action is completed, the buzzer will sound again.

3. Record more actions

By modifying the numbers in the base code, you can record up to 170 actions, as shown in the image below:

```
Arm | Arduino 1.8.5
File Edit Sketch Tools Help

* arm.JoystickR.read_x();
* arm.JoystickR.read_y();
*/
#include "src/CokoinoArm.h"
#define buzzerPin 9

CokoinoArm arm;
int xL, yL, xR, yR;

const int act_max=170; //Default 10 action, 4 the Angle of servo
int act[act_max][4]; //Only can change the number of action
int num=0, num_do=0;
////////////////////////////////////

Done compiling.
Sketch uses 4920 bytes (16%) of program storage space. Maximum is 30720 bytes.
Global variables use 1535 bytes (74%) of dynamic memory, leaving 513 bytes for
52 Arduino Nano, ATmega328P on COM3
```