

My Project

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Chapter 1

RBE3001Team6

Team 6 RBE 3001 Private Repository

Chapter 2

Todo List

Member **b7**

- make a nice array or something
- make for rest of buttons

Member **clearADC** (int channel)

Create the corresponding function to clear the last ADC calculation register and disconnect the input to the ADC if desired.

Member **degreesPerJoint2Val**

- change these to constants

Member **gotoXY** (int x, int y)

Use kinematic equations to move the end effector to the desired position.

Member **inPosition** (int theta1, int theta2)

- pass in the threshold to use

Member **setFrequencyForPostScale** (int Frequency)

- make more generic

Member **upperAngle**

- get rid of these globals

Member **waitForButton7** ()

- make more generic

Member **y_coord**

- get rid of these globals

Chapter 3

File Index

3.1 File List

Here is a list of all documented files with brief descriptions:

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Chapter 4

File Documentation

4.1 ADC.c File Reference

ADC setup function definitions.

```
#include "RBELib/RBELib.h"
#include "include/definitions.h"
```

Functions

- [ISR](#) (ADC_vect)
ISR for updating ADC readings Runs when ADC reading completes based on configured ADC settings.
- void [initADC](#) (int channel)
Initializes the ADC and makes one channel active.
- void [clearADC](#) (int channel)
Disables ADC functionality and clears any saved values (globals).
- unsigned short [getADC](#) (int channel)
Get the analog value from the configured channel.
- void [changeADC](#) (int channel)
Change the channel the ADC is sampling if using interrupts.

Variables

- volatile unsigned short [adch](#)
- volatile unsigned short [adcl](#)
- volatile unsigned short [readNewChannel](#)

4.1.1 Detailed Description

ADC setup function definitions.

This has everything needed to configure the ADC for 10 bit operation and reading the values.

Author

cpbove@wpi.edu

Date

28-Jan-2016

Version

1.0

4.1.2 Function Documentation

4.1.2.1 void changeADC (int *channel*)

Change the channel the ADC is sampling if using interrupts.

Parameters

<i>channel</i>	The ADC channel to switch to.
----------------	-------------------------------

4.1.2.2 void clearADC (int *channel*)

Disables ADC functionality and clears any saved values (globals).

This still needs to be tested.

Parameters

<i>channel</i>	The ADC channel to disable.
----------------	-----------------------------

Todo Create the corresponding function to clear the last ADC calculation register and disconnect the input to the ADC if desired.

4.1.2.3 unsigned short getADC (int *channel*)

Get the analog value from the configured channel.

Parameters

<i>channel</i>	The ADC channel to run a conversion on.
----------------	---

Returns

adcVal The 10 bit value returned by the ADC conversion.

4.1.2.4 void initADC (int *channel*)

Initializes the ADC and makes one channel active.

Enables ADC to use interrupts

Parameters

<i>channel</i>	The ADC channel to initialize
----------------	-------------------------------

4.1.2.5 ISR (ADC_vect)

ISR for updating ADC readings Runs when ADC reading completes based on configured ADC settings.

Parameters

<i>ADC_vect</i>	Interrupt vector for ADC on chip
-----------------	----------------------------------

4.1.3 Variable Documentation**4.1.3.1 adch**

for storing the adch register value after an interrupt

4.1.3.2 adcl

for storing the adch register value after an interrupt

4.1.3.3 readNewChannel

used to make sure we read the new channel after we switch channels

4.2 arm.c File Reference

arm library

```
#include "include/arm.h"
#include "include/definitions.h"
#include "math.h"
```

Functions

- [ISR \(TIMER0_COMPA_vect\)](#)
Timer ISR that runs at 100Hz.
- void [initArm](#) ()
initialize the arm variables
- void [setupTimer](#) ()
sets a 100Hz timer up on Timer 0
- void [serviceArm](#) ()
runs functions critical to arm operation. Call as often as possible.
- float [getJointAngle](#) (int joint)
gets the current, calibrated joint angle of the passed joint number
- int [getCurrent](#) (int joint)
gets motor current of specified joint
- float [getAverageCurrent](#) (int command, int current)
Function for managing the currents gathered and averaging them when asked.
- void [setJointAngles](#) (int lowerJoint, int upperJoint)
updates globals with new desired ones
- float [getTimeSeconds](#) ()
gets the time in seconds
- void [calcXY](#) ()
calculates forward kinematics for arm and updates global position
- BOOL [inPosition](#) (int theta1, int theta2)
check if the arm is in the angle position specified
- BOOL [doneMoving](#) ()
checks if the arm is in desired position
- void [setPosition](#) (float x, float y)
calculates IK values and sets angles
- int [calibratedIRVal](#) (int IRDist)
uses a polynomial to calibrate the IR distance readings

Variables

- float [degreesPerJoint1Val](#)
- float [degreesPerJoint2Val](#)
- float [x_coord](#)
- float [y_coord](#)
- float [L2L2](#)
- float [L3L3](#)
- int [lowerAngle](#)
- int [upperAngle](#)
- volatile BOOL [servicePID](#)
- volatile unsigned long [timerCount](#)

4.2.1 Detailed Description

arm library

Author

cpbove@wpi.edu

Date

30-Jan-2016

Version

1.0

4.2.2 Function Documentation

4.2.2.1 int calibratedIRVal (int *IRDist*)

uses a polynomial to calibrate the IR distance readings

Parameters

<i>IRDist</i>	distance reading in mm
---------------	------------------------

Returns

calibrated IR distance in mm

4.2.2.2 BOOL doneMoving ()

checks if the arm is in desired position

Returns

true if in desired position

4.2.2.3 float getAverageCurrent (int *command*, int *current*)

Function for managing the currents gathered and averaging them when asked.

Parameters

<i>current</i>	Current to be added to the stored values
<i>command</i>	Command of what to be done with the function, either resetCurrent,addCurrent,retrieveAverageCurrent

Returns

current in mA

4.2.2.4 int getCurrent (int *joint*)

gets motor current of specified joint

Parameters

<i>joint</i>	The joint to get the current for
--------------	----------------------------------

Returns

current in mA

4.2.2.5 float getJointAngle (int *joint*)

gets the current, calibrated joint angle of the passed joint number

Parameters

<i>joint</i>	1 or 2 of the joint to get the angle for
--------------	--

Returns

angle of joint in degrees (generally 0 to 180)

4.2.2.6 float getTimeSeconds ()

gets the time in seconds

Returns

time in seconds

4.2.2.7 BOOL inPosition (int *theta1*, int *theta2*)

check if the arm is in the angle position specified

Parameters

<i>theta1</i>	angle of first joint
<i>theta2</i>	angle of second joint

Returns

TRUE if arm is between

Todo pass in the threshold to use

4.2.2.8 ISR (TIMER0_COMPA_vect)

Timer ISR that runs at 100Hz.

set flags for servicing at fixed intervals.

Parameters

<i>TIMER0_COMPA_vect</i>	Interrupt vector for timer0 vector on AVR
--------------------------	---

4.2.2.9 void setJointAngles (int *lowerJoint*, int *upperJoint*)

updates globals with new desired ones

Parameters

<i>lowerJoint</i>	position for the lower joint 1
<i>upperJoint</i>	position for the upper joint 2

4.2.2.10 void setPosition (float *x*, float *y*)

calculates IK values and sets angles

Parameters

<i>x</i>	desired x position
<i>y</i>	desired y position

4.2.3 Variable Documentation**4.2.3.1 degreesPerJoint1Val**

for storing the degrees per adc value for joint 1

4.2.3.2 degreesPerJoint2Val

for storing the degrees per adc value for joint 2

Todo change these to constants

4.2.3.3 L2L2

constant for optimizing Link 2 Length 2

4.2.3.4 L3L3

constant for optimizing Link 3 Length 2

4.2.3.5 lowerAngle

for storing the current lowerAngle of the arm

4.2.3.6 servicePID

flag - TRUE if PID controller needs to be serviced, FALSE otherwise

4.2.3.7 timerCount

for keeping time. increments in 0.01 seconds

4.2.3.8 upperAngle

for storing the current upperAngle of the arm

Todo get rid of these globals

4.2.3.9 x_coord

for storing the current x coordinate of the arm

4.2.3.10 y_coord

for storing the current y coordinate of the arm

Todo get rid of these globals

4.3 button.c File Reference

button setup function

```
#include "RBELib/RBELib.h"
#include "include/button.h"
```

Functions

- void `setupButtons` (`__8bitreg_t *DDxn`, `__8bitreg_t *PORTxn`, `__8bitreg_t *PINxbits`, `BOOL enablePullup`)
sets registers to configure the buttons as inputs
- void `serviceButtons` ()
runs functions critical to button operation. Call as often as possible.
- unsigned char `lastButtonPressed` ()
determines what button was pressed last

Variables

- `__8bitreg_t * PINybits`
- unsigned char `b4`
- unsigned char `b5`
- unsigned char `b6`
- unsigned char `b7`

4.3.1 Detailed Description

button setup function

To read buttons, check `PINxbits._Py`

Author

`cpbove@wpi.edu`

Date

28-Jan-2016

Version

1.0

4.3.2 Function Documentation

4.3.2.1 unsigned char lastButtonPressed ()

determines what button was pressed last

Returns

number of last button pressed

4.3.2.2 void setupButtons (`__8bitreg_t * DDxn`, `__8bitreg_t * PORTxn`, `__8bitreg_t * PINxbits`, `BOOL enablePullup`)

sets registers to configure the buttons as inputs

Parameters

<i>*DDxn</i>	Pointer to the digital port (DDxn) that buttons are connected to
<i>*PORTxn</i>	Pointer to the PORTxn register for the buttons
<i>*PINxbits</i>	Pointer to the PINx register for the buttons
<i>enablePullUp</i>	Set true to enable pull up resistors on the buttons

4.3.3 Variable Documentation**4.3.3.1 b4**

storing last state of button 4

4.3.3.2 b5

storing last state of button 5

4.3.3.3 b6

storing last state of button 6

4.3.3.4 b7

storing last state of button 7

Todo make a nice array or something
make for rest of buttons

4.3.3.5 *PINybits

pointer to the PINbits the buttons are connected to

4.4 DAC.c File Reference

DAC library.

```
#include "RBELib/RBELib.h"
```


Functions

- void `setDAC` (int DACn, int SPIVal)
Set the DAC to the given value on the chosen channel.

4.4.1 Detailed Description

DAC library.

Author

`cpbove@wpi.edu`

Date

30-Jan-2016

Version

1.0

4.4.2 Function Documentation

4.4.2.1 void setDAC (int DACn, int SPIVal)

Set the DAC to the given value on the chosen channel.

Parameters

<i>DACn</i>	The channel (0-3) that you want to set.
<i>SPIVal</i>	The value you want to set it to.

4.5 definitions.c File Reference

defines for our team

```
#include "RBElib/RBElib.h"
#include "include/definitions.h"
```

Functions

- int `abs` (int a)
take absolute value of passed integer
- BOOL `betweenTwoVals` (int value, int lower, int upper)
check if passed value is between lower and upper bounds

4.5.1 Detailed Description

defines for our team

some basic useful functions that our team uses.

Author

cpbove@wpi.edu

Date

3-Feb-2016

Version

1.0

4.5.2 Function Documentation

4.5.2.1 int abs (int *a*)

take absolute value of passed integer

Parameters

<i>a</i>	The number to take the absolute value of
----------	--

4.5.2.2 BOOL betweenTwoVals (int *value*, int *lower*, int *upper*)

check if passed value is between lower and upper bounds

Parameters

<i>value</i>	the number to check with
<i>lower</i>	the lower bound to check against
<i>upper</i>	the upper bound to check against

Returns

true if value is between upper and lower numbers

4.6 encoder.c File Reference

encoder library

```
#include "include/encoder.h"
#include "include/definitions.h"
```

Functions

- void [singleByteWrite](#) (unsigned char op_code, unsigned char data, int joint)
write a single byte to encoder
- void [slaveSelect](#) (int joint)
sets the chip select low for the passed joint
- void [slaveDeselect](#) (int joint)
sets the chip select high for the passed joint
- void [waitForTransmissionEnd](#) ()
holds processor until transmission has finished

4.6.1 Detailed Description

encoder library

Author

LSI Computer Systems, modified by cpbove@wpi.edu

Date

16-Feb-2016

Version

1.0

4.6.2 Function Documentation

4.6.2.1 void singleByteWrite (unsigned char op_code, unsigned char data, int joint)

write a single byte to encoder

Parameters

<i>op_code</i>	one of the defined operation codes
<i>data</i>	data to write to the encoder
<i>joint</i>	1 or 2 for the encoder joint to read

4.6.2.2 void slaveDeselect (int joint)

sets the chip select high for the passed joint

Parameters

<i>joint</i>	1 or 2 to deselect
--------------	--------------------

4.6.2.3 void slaveSelect (int *joint*)

sets the chip select low for the passed joint

Parameters

<i>joint</i>	1 or 2 to select
--------------	------------------

4.7 FSM.c File Reference

Finite State Machine library.

```
#include "include/FSM.h"
#include "include/arm.h"
#include "RBELib/RBELib.h"
#include "include/gripper.h"
#include "math.h"
```

Functions

- void [finiteStateMachine](#) ()
runs FSM for the final project

4.7.1 Detailed Description

Finite State Machine library.

computes motions for the arm and monitors the conveyor belt to complete the final project. It detects when a block is placed on the belt, determines its X position and velocity, calculates the time the arm needs to grab the block, grabs the block, determines whether the block is light or heavy, then places the block accordingly and gets ready for another block.

Author

cpbove@wpi.edu

Date

27-Feb-2016

Version

1.0

4.8 gripper.c File Reference

gripper library

```
#include "RBELib/RBELib.h"
#include "include/gripper.h"
```

Functions

- void `closeGripper` ()
Closes the gripper.
- void `openGripper` ()
Opens the gripper.
- void `startConveyor` ()
starts the conveyor belt servo
- void `stopConveyor` ()
stops the conveyor belt servo

4.8.1 Detailed Description

gripper library

Author

`cpbove@wpi.edu`

Date

27-Feb-2016

Version

1.0

4.9 lab1.c File Reference

Lab1 functions.

```
#include "RBELib/RBELib.h"
#include "include/definitions.h"
#include "include/lab1.h"
```

Functions

- void `initPart2and7Timer ()`
Configures Timer0 for Parts 2 and 7 of lab, prints header for logging.
- void `initSignalGeneratorTimer ()`
Configures Timer1 for Part 4 of lab(signal generation), prints header for logging.
- void `outputSetup ()`
Configures outputs for generating signals on pins.
- void `waitForButton7 ()`
Holds processor until button 7 is pressed.
- void `waitForChar (char c)`
Holds the processor until the right character is received from USART.
- void `ADCToSerial (int channel)`
Streams timestamp, adcval, potmv, and potangle to PC w/ USART Transmits timestamps, ADC value in counts, pot output in millivolts, and pot angle in degrees over the serial port to the screen in the Terminal.
- void `ADCToSerialPart7 (int channel)`
Streams timestamp and ADC values to the serial port for 1 second Transmits timestamps, ADC value in counts in degrees over the serial port to the screen in the Terminal.
- void `setFrequencyForPostScale (int Frequency)`
Configures postscaler in ISR based on inputted frequency.
- void `signalGeneratorMain (int channel)`
Generates signals w/particular duty cycles set by pot.
- void `triangleSignalGengerator ()`
generates triangle waves through DAC

Variables

- volatile unsigned long `timer0Count`
- volatile unsigned long `timer2Count`
- volatile unsigned `timer2CountSub`
- unsigned `postScale`

4.9.1 Detailed Description

Lab1 functions.

This includes all the functions needed for Lab1.

Authors

`cpbove@wpi.edu jlhonicker@wpi.edu dmmurray@wpi.edu`

Date

28-Jan-2016

Version

1.0

4.9.2 Function Documentation

4.9.2.1 void ADCToSerial (int channel)

Streams timestamp, adcval, potmv, and potangle to PC w/ USART Transmits timestamps, ADC value in counts, pot output in millivolts, and pot angle in degrees over the serial port to the screen in the Terminal.

Parameters

<i>channel</i>	The ADC channel to read from
----------------	------------------------------

4.9.2.2 void ADCToSerialPart7 (int *channel*)

Streams timestamp and ADC values to the serial port for 1 second Transmits timestamps, ADC value in counts in degrees over the serial port to the screen in the Terminal.

Parameters

<i>channel</i>	The ADC channel to read
----------------	-------------------------

4.9.2.3 void setFrequencyForPostScale (int *Frequency*)

Configures postscaler in ISR based on inputted frequency.

Only handles a few frequencies: 1,20,100

Todo make more generic

Parameters

<i>Frequency</i>	The frequency to change to (1, 20, or 100)
------------------	--

4.9.2.4 void signalGeneratorMain (int *channel*)

Generates signals w/particular duty cycles set by pot.

Also reads buttons 5-7 to determine which frequency to output

Parameters

<i>channel</i>	The ADC channel to read the pot from
----------------	--------------------------------------

4.9.2.5 void waitForButton7 ()

Holds processor until button 7 is pressed.

Todo make more generic

4.9.2.6 void waitForChar (char c)

Holds the processor until the right character is received from USART.

Parameters

c	The character to wait for.
---	----------------------------

4.9.3 Variable Documentation

4.9.3.1 postScale

for dividing the ISR output more

4.9.3.2 timer0Count

counts time in 0.01s or 1/225 seconds (depends on active lab part)

4.9.3.3 timer2Count

counts time for outputting signals

4.9.3.4 timer2CountSub

another counter within the Timer2 ISR

4.10 lab2and3.c File Reference

Graveyard for old Lab 2 and 3 functions.

```
#include "include/lab2and3.h"
#include "RBElib/RBElib.h"
#include "include/definitions.h"
#include "include/arm.h"
#include "include/button.h"
```

Functions

- void `printHeaderForJointAngle` ()
prints the header for streaming joint angles
- void `printHeaderForLogging` ()
prints the header for the main logging of step responses
- void `printJointAngle` (int joint)
prints adcval, pot mV, and joint angle of the passed joint number
- void `printLogLineJoint2` (int setPoint)
prints time, setpoint, jointAngle, PID output, and motor current
- void `printJointAnglesAndPos` ()
streams joint angles in degrees and (x,y) tip positions in mm
- int `convertVoltsToDACVal` (float volts)
converts a voltage value to a DAC value
- void `controlArmWithButtons` ()
changes desired joint angle of arm based on button presses for testing
- void `controlPositionWithButtons` ()
changes desired joint angles of arm based on button presses
- void `controlJoint1WithButtons` ()
Lab3 - control motor drive voltages with buttons.
- void `drawTriangleWithButtons` ()
state machine for drawing triangles.
- float `getGs` (int axis)
runs getAccel and converts to G's

4.10.1 Detailed Description

Graveyard for old Lab 2 and 3 functions.

Author

`cpbove@wpi.edu`

Date

3-Mar-2016

Version

1.0

4.10.2 Function Documentation

4.10.2.1 void controlArmWithButtons ()

changes desired joint angle of arm based on button presses for testing

Note

This does not run the PID control, just sets setpoint

4.10.2.2 void controlJoint1WithButtons ()

Lab3 - control motor drive voltages with buttons.

Sets first link to 0, -3, +3, or plus 6 Volts button 4 sets voltage to 0 button 5 sets voltage to -3 button 6 sets voltage to +3 button 7 sets voltage to +6

4.10.2.3 void controlPositionWithButtons ()

changes desired joint angles of arm based on button presses

Note

This does not run the PID control, just sets setpoint

4.10.2.4 int convertVoltsToDACVal (float *volts*)

converts a voltage value to a DAC value

Parameters

<i>volts</i>	to convert to DAC -7.2 to 7.2 volts
--------------	-------------------------------------

Returns

DAC value 0-4095

4.10.2.5 void drawTriangleWithButtons ()

state machine for drawing triangles.

button 4 draws a prescribed triangle button 5 just moves to a pose button 6 records a motion button 7 plays back the motion

Note

This does not run the PID control, just sets setpoint

4.10.2.6 float getGs (int *axis*)

runs getAccel and converts to G's

Parameters

<i>axis</i>	0-2 for x,y,z axis to get g's on
-------------	----------------------------------

Returns

-3.0 to 3.0 g's of force

4.10.2.7 void printJointAngle (int *joint*)

prints adcval,pot mV, and joint angle of the passed joint number

Parameters

<i>joint</i>	1 or 2 of the joint to print data for
--------------	---------------------------------------

4.10.2.8 void printLogLineJoint2 (int *setPoint*)

prints time, setpoint, jointAngle, PID output, and motor current

Parameters

<i>setPoint</i>	the current command to the controller
-----------------	---------------------------------------

4.11 led.c File Reference

LED setup functions.

```
#include "include/led.h"
```

Functions

- void [setupLEDs](#) (__8bitreg_t *DDxn, __8bitreg_t *PORTxn)
configures registers as outputs for the LEDs

4.11.1 Detailed Description

LED setup functions.

Author

cpbove@wpi.edu

Date

28-Jan-2016

Version

1.0

4.11.2 Function Documentation

4.11.2.1 void setupLEDs (__8bitreg_t * DDxn, __8bitreg_t * PORTxn)

configures registers as outputs for the LEDs

Sets all the ports as outputs and then puts them all low to prevent them from turning on unintentionally.

Parameters

*DDxn	Pointer to the digital outputs (DDxn) that buttons will be connected to
*PORTxn	Pointer to the PORTxn that actually writes the outputs
enablePullUp	Set true to enable pull ups on the buttons

4.12 main.c File Reference

Main loop running on board. Runs Lab1 functions.

```
#include "RBELib/RBELib.h"
#include "include/definitions.h"
#include "include/button.h"
#include "include/lab1.h"
#include "include/led.h"
#include "include/arm.h"
#include "include/FSM.h"
#include "include/gripper.h"
#include "include/PC_Interface.h"
```

Functions

- int [main](#) (void)
main loop for AVR chip

4.12.1 Detailed Description

Main loop running on board. Runs Lab1 functions.

This code runs initialization routines and then loops the finite state machine and arm service routines forever to complete the final project for RBE 3001.

Author

cpbove@wpi.edu

Date

3-Mar-2016

Version

1.5

4.13 motors.c File Reference

Motor driving functions for the arm.

```
#include "RBELib/RBELib.h"
#include "include/definitions.h"
#include "include/arm.h"
```

Functions

- void [stopMotors](#) ()
Helper function to stop the motors on the arm.
- void [gotoAngles](#) (int lowerTheta, int upperTheta)
Drive the arm to a desired angle.
- void [gotoXY](#) (int x, int y)
Drive the end effector of the arm to a desired X and Y position in the workspace.
- void [driveLink](#) (int link, int dir)
Drive a link (upper or lower) in a desired direction.
- void [homePos](#) ()
Drive the arm to a "home" position using the potentiometers. This should be called before using the encoders and just goes to a default position. Once this has been called once, you can initialize/clear the encoders.

4.13.1 Detailed Description

Motor driving functions for the arm.

Author

Chris Bove

Date

Feb 3, 2016

4.13.2 Function Documentation

4.13.2.1 void [driveLink](#) (int *link*, int *dir*)

Drive a link (upper or lower) in a desired direction.

Parameters

<i>link</i>	Which link to control.
<i>dir</i>	Which way to drive the link. Between -2048 and +2048

4.13.2.2 void gotoAngles (int *lowerTheta*, int *upperTheta*)

Drive the arm to a desired angle.

Parameters

<i>lowerTheta</i>	The desired angle for the lower link.
<i>upperTheta</i>	The desired angle for the upper link.

4.13.2.3 void gotoXY (int *x*, int *y*)

Drive the end effector of the arm to a desired X and Y position in the workspace.

Parameters

<i>x</i>	The desired x position for the end effector.
<i>y</i>	The desired y position for the end effector.

Todo Use kinematic equations to move the end effector to the desired position.

4.14 PC_Interface.c File Reference

library for reading joint values from serial for extra credit

```
#include "include/PC_Interface.h"
#include "string.h"
#include "stdlib.h"
#include "include/arm.h"
#include "include/lab1.h"
```

Functions

- float [getJointCommand](#) (int joint)
returns the converted float from serial line
- void [controlArmWithSerial](#) ()
controls the arm joints with values read from serial

4.14.1 Detailed Description

library for reading joint values from serial for extra credit

Author

cpbove@wpi.edu

Date

3-March-2016

Version

1.0

4.14.2 Function Documentation

4.14.2.1 void controlArmWithSerial ()

controls the arm joints with values read from serial

Note

this should be called at least at 100hz to allow PID to function as it will block other functions until the read completes.

4.14.2.2 float getJointCommand (int *joint*)

returns the converted float from serial line

expects format: a34.58, b23.284,

Returns

joint angle read from serial line

4.15 Periph.c File Reference

peripheral library for encoder and accel

```
#include "RBELib/RBELib.h"  
#include "include/encoder.h"
```

Macros

- `#define ENC_CNTR 0x20`
- `#define ENC_CLR_CMD 0x00`
- `#define ENC_RD_CMD 0x40`

Functions

- signed int [getAccel](#) (int axis)
Find the acceleration in the given axis (X, Y, Z).
- int [IRDist](#) (int chan)
Read an IR sensor and calculate the distance of the block.
- void [enclnit](#) (int chan)
Initialize the encoders with the desired settings.
- void [resetEncCount](#) (int chan)
Reset the current count of the encoder ticks.
- signed long [encCount](#) (int chan)
Finds the current count of one of the encoders.

4.15.1 Detailed Description

peripheral library for encoder and accel

Author

cpbove@wpi.edu with help from Joe St. Germain

Date

15-02-2016

Version

1.0

4.15.2 Macro Definition Documentation

4.15.2.1 `#define ENC_CLR_CMD 0x00`

hex value for clearing the encoder count

4.15.2.2 `#define ENC_CNTR 0x20`

hex value for addressing the CNTR register on the encoder

4.15.2.3 `#define ENC_RD_CMD 0x40`

hex value command for reading the encoder count

4.15.3 Function Documentation

4.15.3.1 signed long `encCount (int chan)`

Finds the current count of one of the encoders.

Parameters

<i>chan</i>	Channel of the encoder (change: Joint 1 or 2)
-------------	---

Returns

count The current count of the encoder.

4.15.3.2 void enclnit (int *chan*)

Initialize the encoders with the desired settings.

Parameters

<i>chan</i>	Channel to initialize (change: Joint 1 or 2)
-------------	--

Note

leaves the encoder in Byte 4, Quad X1 default state

4.15.3.3 signed int getAccel (int *axis*)

Find the acceleration in the given axis (X, Y, Z).

Parameters

<i>axis</i>	The axis that you want to get the measurement of.
-------------	---

Returns

gVal Value of acceleration.

4.15.3.4 int IRDist (int *chan*)

Read an IR sensor and calculate the distance of the block.

Parameters

<i>chan</i>	The port that the IR sensor is on.
-------------	------------------------------------

Returns

value The distance in mm the block is from the sensor.

4.15.3.5 void resetEncCount (int *chan*)

Reset the current count of the encoder ticks.

Parameters

<i>chan</i>	The channel to clear. (change: Joint 1 or 2)
-------------	--

4.16 PID.c File Reference

The source file for PID constants and calculations.

```
#include "RBELib/RBELib.h"
#include "include/definitions.h"
#include "math.h"
```

Functions

- void [setConst](#) (char link, float Kp, float Ki, float Kd)
Sets the Kp, Ki, and Kd values for 1 link.
- signed int [calcPID](#) (char link, int setPoint, int actPos)
Calculate the PID value.

Variables

- pidConst [pidConsts](#)
Declaration for use in other files.

4.16.1 Detailed Description

The source file for PID constants and calculations.

Sets the PID constants and calculate the PID value.

Author

Chris Bove

Date

2-3-16

4.16.2 Function Documentation

4.16.2.1 signed int calcPID (char *link*, int *setPoint*, int *actPos*)

Calculate the PID value.

Parameters

<i>link</i>	Which link to calculate the error for (Use 'U' and 'L').
<i>setPoint</i>	The desired position of the link.
<i>actPos</i>	The current position of the link.

4.16.2.2 void setConst (char *link*, float *Kp*, float *Ki*, float *Kd*)

Sets the Kp, Ki, and Kd values for 1 link.

Parameters

<i>link</i>	The link you want to set the values for (2 or 3).
<i>Kp</i>	Proportional value.
<i>Ki</i>	Integral value.
<i>Kd</i>	Derivative value.

4.17 pot.c File Reference

The potentiometer functions.

```
#include "RBELib/RBELib.h"
```

Functions

- int [potAngle](#) (int pot)
Find the angle of the given potentiometer.
- int [potVolts](#) (int pot)
Find the voltage value of the given potentiometer.

4.17.1 Detailed Description

The potentiometer functions.

Use these functions to read the values from the pots.

Author

Chris Bove

Date

2-3-16

4.17.2 Function Documentation

4.17.2.1 int potAngle (int *pot*)

Find the angle of the given potentiometer.

Parameters

<i>pot</i>	The pot to check.
------------	-------------------

Returns

angle Angle of the potentiometer.

4.17.2.2 int potVolts (int *pot*)

Find the voltage value of the given potentiometer.

Parameters

<i>pot</i>	The pot to get the value of.
------------	------------------------------

Returns

volts Voltage of potentiometer.

4.18 SPI.c File Reference

arm library

```
#include "RBELib/RBELib.h"
#include "include/definitions.h"
```

Functions

- void [initSPI](#) ()
Initializes the SPI bus for communication with all of your SPI devices.
- unsigned char [spiTransceive](#) (BYTE data)
Send and receive a byte out of the MOSI line.

4.18.1 Detailed Description

arm library

Author

cpbove@wpi.edu

Date

30-Jan-2016

Version

1.0

4.18.2 Function Documentation

4.18.2.1 unsigned char spiTransceive (BYTE *data*)

Send and receive a byte out of the MOSI line.

Please note that even if you do not want to receive any data back from a SPI device, the SPI standard requires you still receive something back even if it is junk data.

Parameters

<i>data</i>	The byte to send down the SPI bus.
-------------	------------------------------------

Returns

value The byte shifted in during transmit

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