

# Lab 1: Introduction to Raspberry Pi, Basic I/O and ADC

Christian Landrum & Wyatt Probst

## Exercise 1

### 1.1: Setup the Raspi

Exercise 1 was setting up the Raspi, connecting to Wifi and SSH into Raspi



Figure 1: Wifi Connection

## Exercise 2

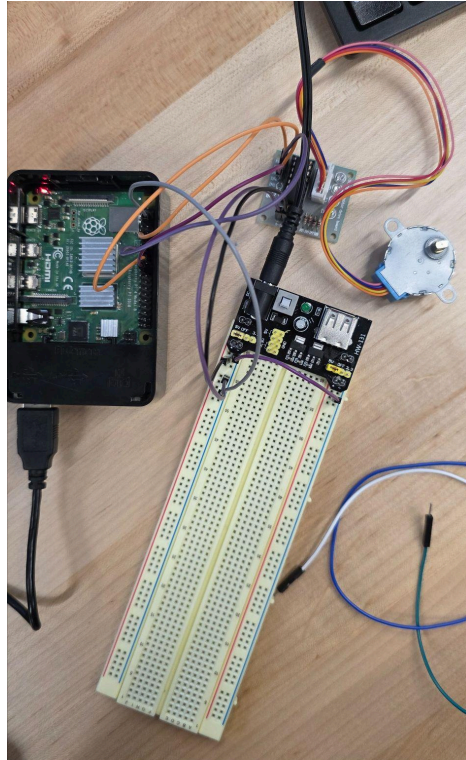
### 2.1 Screenshots of Linux History

```
pi@raspberrypi: ~  
File Edit Tabs Help  
179 g++ joystick.cc -std=c++11 -o Lab3EX3B_bonus Lab3EX3B_bonus.cpp  
180 ./Lab3EX3B_bonus  
181 nano wpa_supplicant.conf  
182 sudo chmod +x setup_wifi.sh  
183 sudo restart  
184 sudo reboot  
185 sudo apt install code -y  
186 ifconfig  
187 sudo service ssh start  
188 pwd  
189 mkdir ECEN4213Lab1  
190 cd ECEN4213Lab1  
191 nano exe1.txt  
192 ls  
193 cp exe1.txt exe_1.txt  
194 rm exe1.txt  
195 ls  
196 cd ..  
197 rm ECEN4213Lab1  
198 rm -r ECEN4213Lab1  
199 mkdir group_5  
200 hist  
201 history  
pi@raspberrypi:~ $
```

Figure 2: Linux Command History

## Exercise 3

### 3.1 Circuit



*Figure 3: Circuit to control Stepper Motor*

## Exercise 4

### 4 Circuit

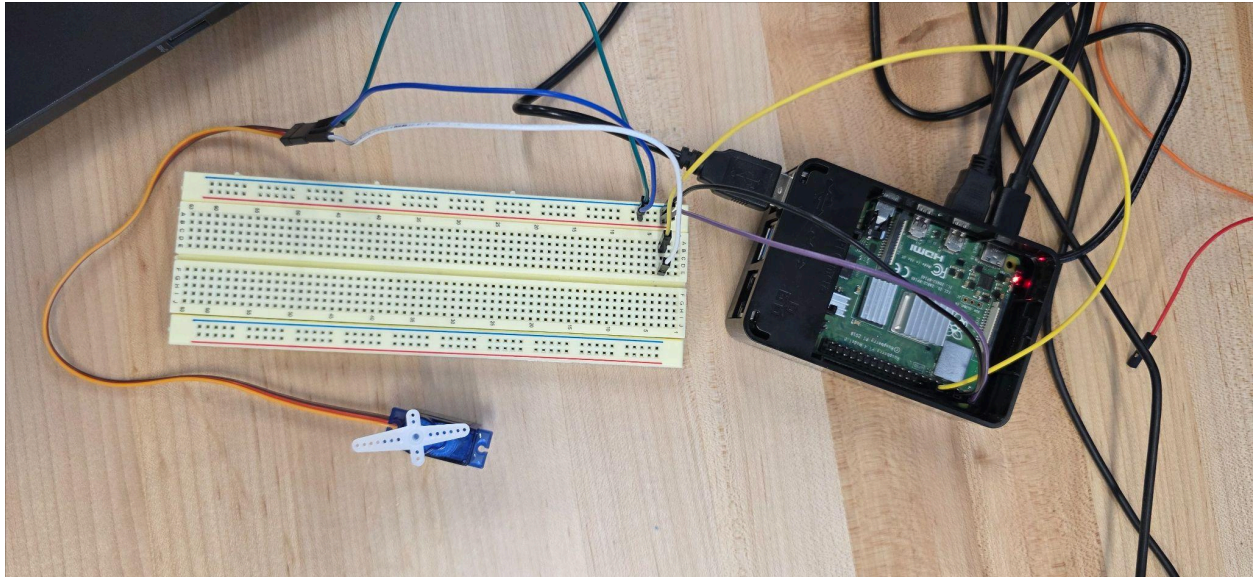
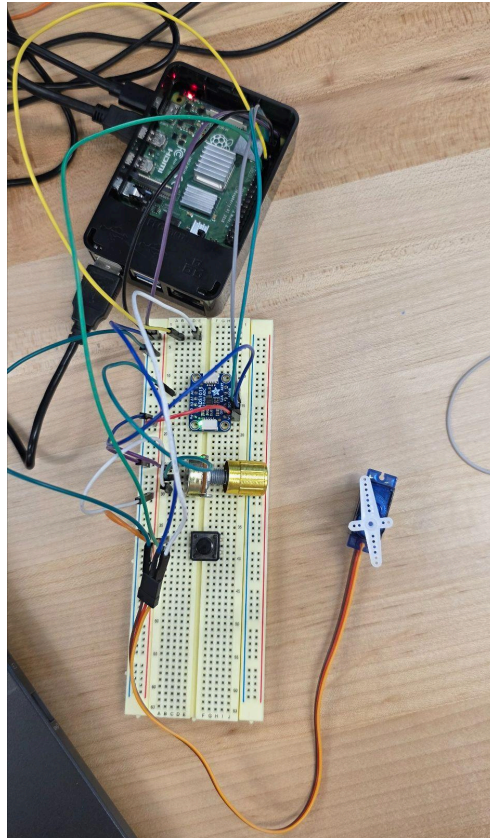


Figure 5: circuit for exercise 4

## Exercise 5

### 5 Circuit



*Figure 7: circuit for exercise 5*

## Supplemental Questions

**Briefly summarize what you learned from this lab.**

In this lab we learned about the various types of motors and how they can be controlled. We also learned about I2C and interrupts and their uses. This lab helped us realize potential use cases for all three types of motors and interrupts.

**What is the advantage of using interrupts?**

Interrupts notify the CPU of an event once it happens instead of wasting time and power constantly polling and waiting for an event to happen.

**Explain the differences between stepper motors and servo motors and DC motors.**

DC motors are continuous with the ability to control speed via the voltage delivered to it, but they have no position control. A servo motor can have speed and position controlled due to its built-in position feedback. Stepper motors have multiple magnetic poles inside of them and are used for their precise movement and high torque.

## ACKNOWLEDGMENTS

I certify that this report is my/our own work, based on my/our personal study and/or research and that I/we have acknowledged all material and sources used in its preparation, whether they be books, articles, reports, lecture notes, and any other kind of document, electronic or personal communication. I/We also certify that this assignment/report has not previously been submitted for assessment anywhere, except where specific permission has been granted from the coordinators involved.

Author-1 Signature **Christian Landrum**

Author-2 Signature **Wyatt Probst**

## REFERENCES

- 1) Lab 1 Slides

- 2) Lab 1 Handout
- 3) Lab 1 Documents