

task_EdgeSense Class Reference

#include <task_EdgeSense.h>

Inheritance diagram for task_EdgeSense:



Public Member Functions

| |
|--|
| task_EdgeSense (const char *, unsigned portBASE_TYPE, size_t, emstream *) |
| void run (void) |

Detailed Description

This task reads the IR sensors attached to the sumo robot for the purpose of detecting the edge of the competition ring, a white line. If a sensor is triggered, the boolean share IR_flg is changed to true.

Constructor & Destructor Documentation

◆ task_EdgeSense()

```
task_EdgeSense::task_EdgeSense ( const char *          a_name,
                                unsigned portBASE_TYPE a_priority,
                                size_t                  a_stack_size,
                                emstream *              p_ser_dev
                                )
```

This constructor creates a new edge sensing task. Its main job is to call the parent class's constructor which does most of the work.

Parameters

| | |
|---------------------|---|
| a_name | A character string which will be the name of this task |
| a_priority | The priority at which this task will initially run (default: 0) |
| a_stack_size | The size of this task's stack in bytes (default: configMINIMAL_STACK_SIZE) |
| p_ser_dev | Pointer to a serial device (port, radio, SD card, etc.) which can be used by this task to communicate (default: NULL) |

Member Function Documentation

◆ run()

```
void task_EdgeSense::run ( void )
```

This method is called by the RTOS once to run the task loop for ever and ever.

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The documentation for this class was generated from the following files:

- Source/[task_EdgeSense.h](#)
 - Source/[task_EdgeSense.cpp](#)
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