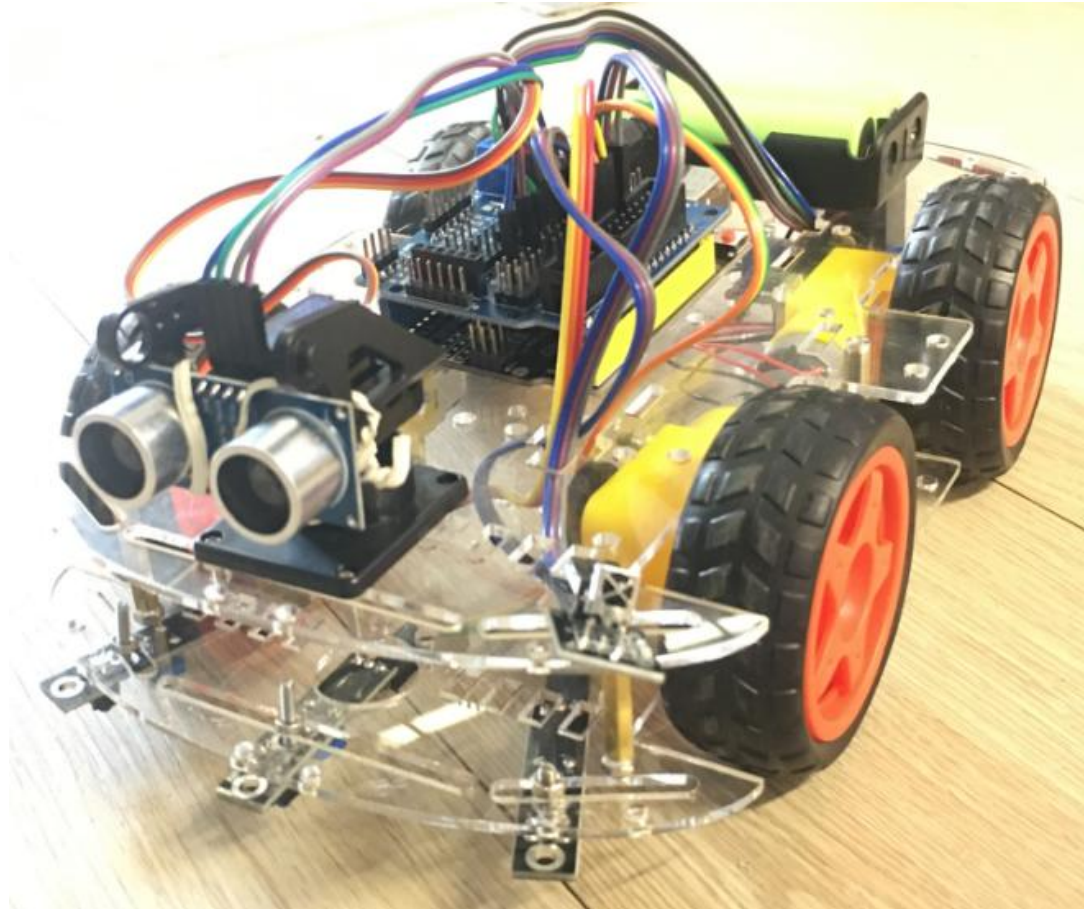


LROBRUYA

**4WD Smart Robot Car Kit**

# LROBRUYA

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## Content

Preface .....	4
Packing list .....	6
How to Install Arduino IDE .....	7
How to Install Arduino Driver .....	22
How to Add Arduino Libraries .....	38
Blink Test .....	46
Lesson 1 Installation Method .....	62
Lesson 2 Servo .....	66
Lesson 3 Ultrasonic Sensor Module .....	72
Lesson 4 L298N Motor Driver .....	79
Lesson 5 Ultrasound Obstacle Avoidance Car .....	84
Lesson 6 Follow Car .....	87
Lesson 7 IR Receiver Module .....	90
Lesson 8 IR Remote Control Car .....	95
Lesson 9 Line-Tracking sensor .....	100
Lesson 10 Line-Tracking Car .....	107
Lesson 11 Bluetooth Module .....	110
Lesson 12 Bluetooth Multifunctional Robot Car .....	125



## Preface

### Company Profile

Founded in 2014, Shenzhen Lonten Technology Co., Ltd. focuses on the design, research production of Electronics Module for robotics related products. Consisting of professional researchers and skilled engineers, our R&D team constantly strives for creative function and excellent user experience. The company's R&D investments on arduino kits raspberry pi kits, as well as 3D printer and robots that back up STEAM education.

### Customer Service

Our self-owned factory is certificated with BSCI and SO, covering an area of 5,000 square meters, and achieving an annual production capacity of over 10,000 units. Our products are all certified to CE, FCC, and ROHS standards, have exported to more than 100 countries including, but not limited to France, the United States of America, Australia, Russia, the United Kingdom, Germany, Singapore, Egypt, and India, bringing technological innovation to all walks of life.



---

By the way, We also look forward to hearing from you and any of your critical comment or suggestions. Pls email us by [lonten3@qq.com](mailto:lonten3@qq.com) or [info@lontentech.com](mailto:info@lontentech.com), if you have any questions or suggestions.

As a continuous and fast growing company. We keep striving our best to offer you excellent products and quality service.

## **Our Store**

store: <https://www.lontentech.com/>

Brand: LONTEN

## **Product Catalog**

<https://www.lontentech.com/collections/steam-robot>

## **Tutorial**

This tutorial include codes, libraries and detailed user documentation.








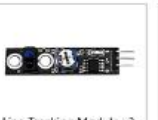










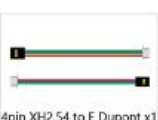




# LROBRUYA

## Packing list



Smart Car Kit

<https://www.lontentech.com>

 R3 x1	 Expanding Board x1	 Remote x1	 Ultrasonic x1	 SG90 Servo x1	 Bluetooth x1
 IR Avoid Module x2	 Line Tracking Module x3	 Motor x4	 Tire x4	 Photoresistive sensor x2	 Servo Holder x1
 Ultrasonic Holder x1	 USB Cable x1	 Battery Case x1	 Bottom Acrylic Layer x1	 Upper Acrylic Layer x1	 Adhesive Tape x1
 4pin XH2.54 to F Dupont x1 3pin XH2.54 to F Dupont x2	 3pin F-F Dupont*5	 Tie x3	 Screw bag	 Screwdriver x1	



## How to Install Arduino IDE

### Introduction

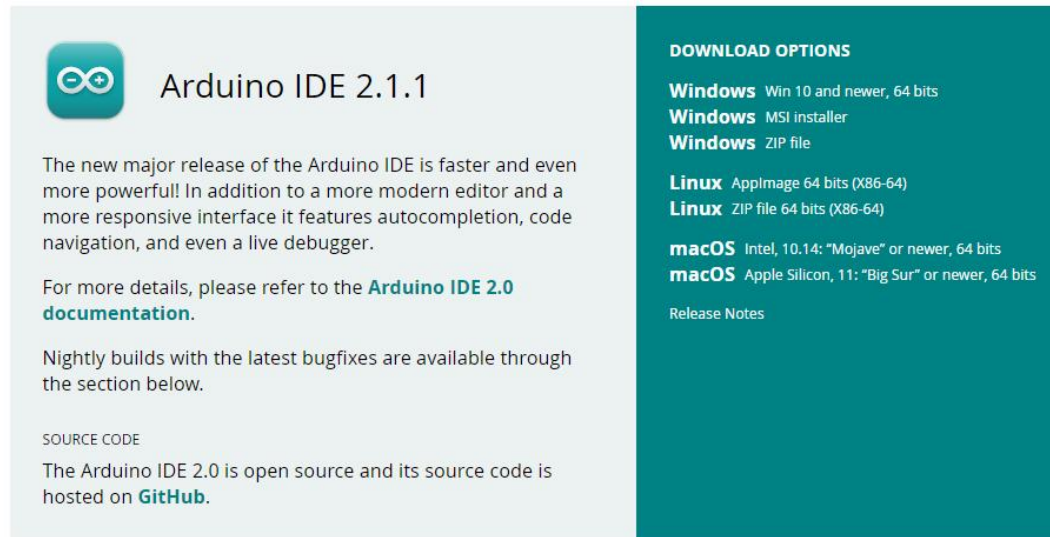
The Arduino Integrated Development Environment (IDE) is the software side of the Arduino platform.

In this Project, you will learn how to setup your computer to use Arduino and how to set about the Projects that follow.

The Arduino software that you will use to program your Arduino is available for Windows, Mac and Linux. The installation process is different for all three platforms and unfortunately there is a certain amount of manual work to install the software.

**STEP 1:** Go to <https://www.arduino.cc/en/software>.

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## Arduino IDE 2.1.1

The new major release of the Arduino IDE is faster and even more powerful! In addition to a more modern editor and a more responsive interface it features autocompletion, code navigation, and even a live debugger.

For more details, please refer to the [Arduino IDE 2.0 documentation](#).

Nightly builds with the latest bugfixes are available through the section below.

SOURCE CODE

The Arduino IDE 2.0 is open source and its source code is hosted on [GitHub](#).

### DOWNLOAD OPTIONS

**Windows** Win 10 and newer, 64 bits  
**Windows** MSI installer  
**Windows** ZIP file

**Linux** AppImage 64 bits (X86-64)  
**Linux** ZIP file 64 bits (X86-64)

**macOS** Intel, 10.14: "Mojave" or newer, 64 bits  
**macOS** Apple Silicon, 11: "Big Sur" or newer, 64 bits

[Release Notes](#)

**The version available at this website is usually the latest version, and the actual version may be newer than the version in the picture.**

**STEP2: Download the development software that is compatible with the operating.**

system of your computer. Take Windows as an example here.



# LROB RUYA

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## DOWNLOAD OPTIONS

**Windows** Win 10 and newer, 64 bits 

**Windows** MSI installer

**Windows** ZIP file

**Linux** Appliance 64 bits (X86-64)

**Linux** ZIP file 64 bits (X86-64)

**macOS** Intel, 10.14: "Mojave" or newer, 64 bits

**macOS** Apple Silicon, 11: "Big Sur" or newer, 64 bits

[Release Notes](#)

Click Windows Win 10 and newer, 64 bits.

# LROBBUYA





Click JUST DOWNLOAD.


Also version 2.1.1 is available in the material we provided, and the versions of our materials are the latest versions when this course was made.


# LROBROYA

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 `arduino-ide_2.1.1_Linux_64bit`

 `arduino-ide_2.1.1_macOS_64bit`

 `arduino-ide_2.1.1_Windows_64bit`

 `arduino-ide_2.1.1_Windows_64bit`

## Installing Arduino (Windows)

**Install Arduino with the exe. Installation package.**

 `arduino-ide_2.1.1_Windows_64bit`

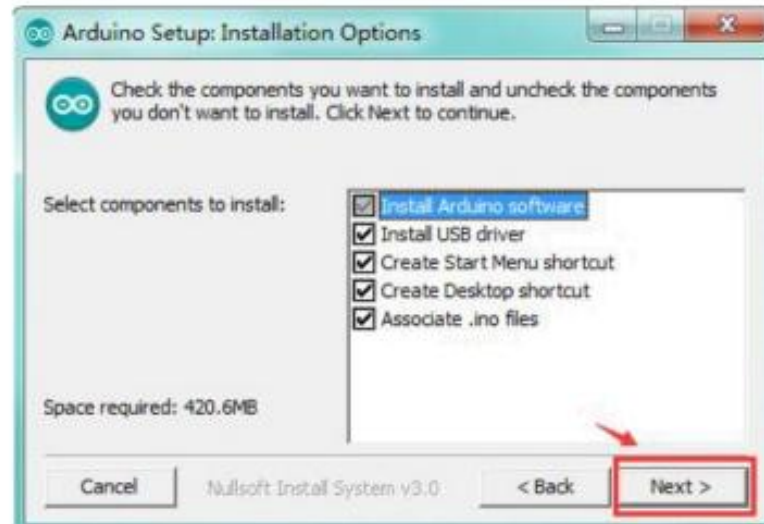
# LROBROYA



Click I Agree to see the following interface.

# LROBROYA

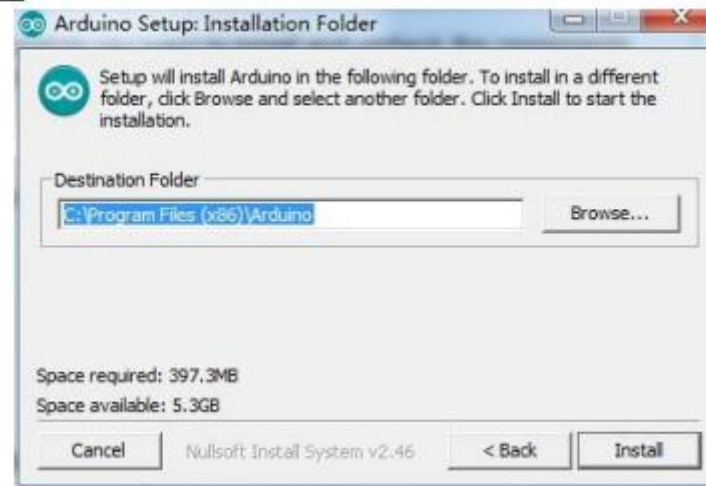
---



Click Next

# LROBROYA

---



You can press Browse... to choose an installation path or directly type in the directory you want.

# LROBROYA

---



Click Install to initiate installation

# LROBROYA

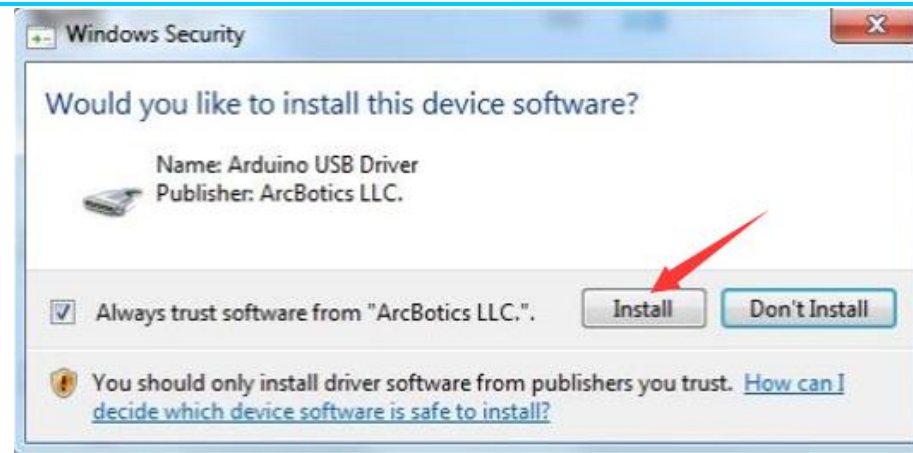
---



Finally, the following interface appears, click Install to finish the installation.



# LROBROYA

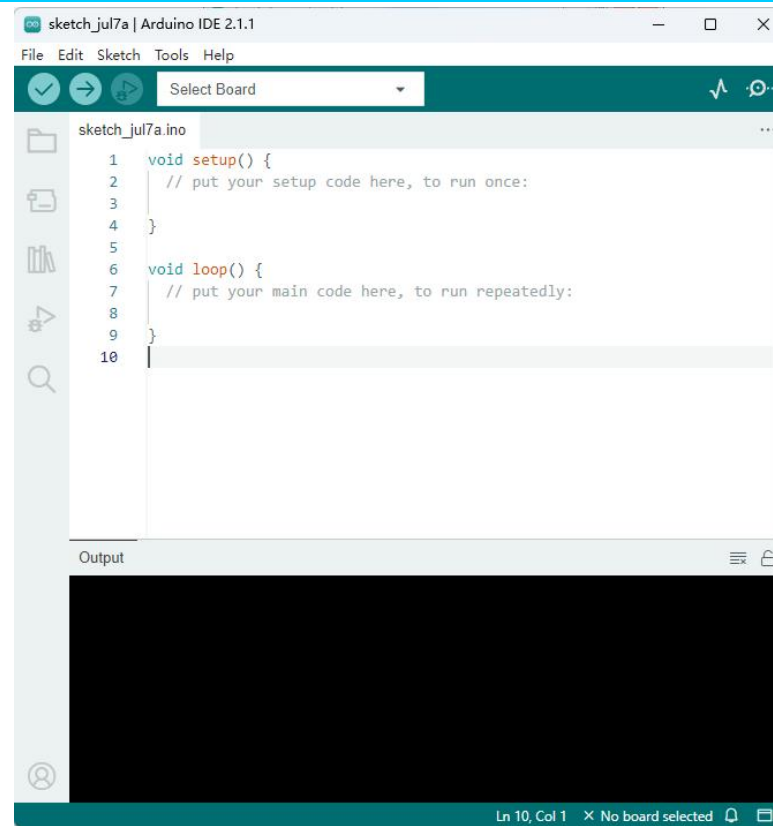


Next, the following icon appears on the desktop



Double-click to enter the desired development environment

# LROBROYA



You may directly choose the installation package for installation and skip the contents below and jump to the next section.

But if you want to learn some methods other than the installation package, please continue to read the section.

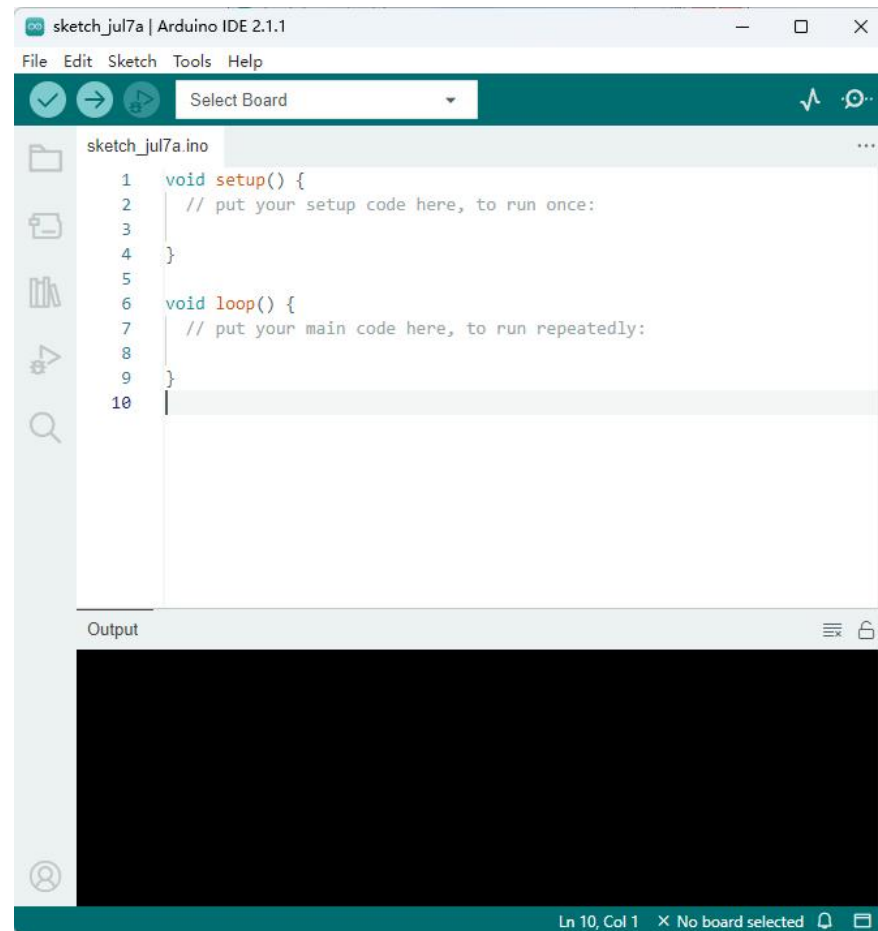
# LROBROYA

Unzip the zip file downloaded, Double-click to open the program and enter the desired development environment.

arduino-ide\_2.1.1\_Windows\_64bit

名称	修改日期	类型	大小
drivers	2023/7/5 21:45	文件夹	
examples	2023/7/5 21:45	文件夹	
hardware	2023/7/5 21:45	文件夹	
java	2023/7/5 21:45	文件夹	
lib	2023/7/5 21:45	文件夹	
libraries	2023/7/5 21:45	文件夹	
reference	2023/7/5 21:45	文件夹	
tools	2023/7/5 21:45	文件夹	
tools-builder	2023/7/5 21:45	文件夹	
arduino	2017/6/1 0:58	应用程序	395 KB
arduino.l4j	2017/6/1 0:58	配置设置	1 KB
arduino_debug	2017/6/1 0:58	应用程序	393 KB
arduino_debug.l4j	2017/6/1 0:58	配置设置	1 KB
arduino-builder	2017/6/1 0:58	应用程序	3,214 KB
libusb0.dll	2017/6/1 0:58	应用程序扩展	43 KB
msvcp100.dll	2017/6/1 0:58	应用程序扩展	412 KB
msvcr100.dll	2017/6/1 0:58	应用程序扩展	753 KB
revisions	2017/6/1 0:58	文本文档	83 KB
uninstall	2023/7/5 21:45	应用程序	404 KB

# LROBROYA

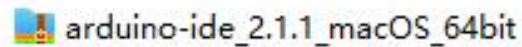




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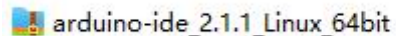
## Installing Arduino (Mac OS X)

Download and Unzip the zip file, double click the Arduino.app to enter Arduino IDE; the system will ask you to install Java runtime library if you don't have it in your computer. Once the installation is complete you can run the Arduino IDE.



## Installing Arduino (Linux)

You will have to use the make install command. If you are using the Ubuntu system, it is recommended to install Arduino IDE from the software center of Ubuntu.

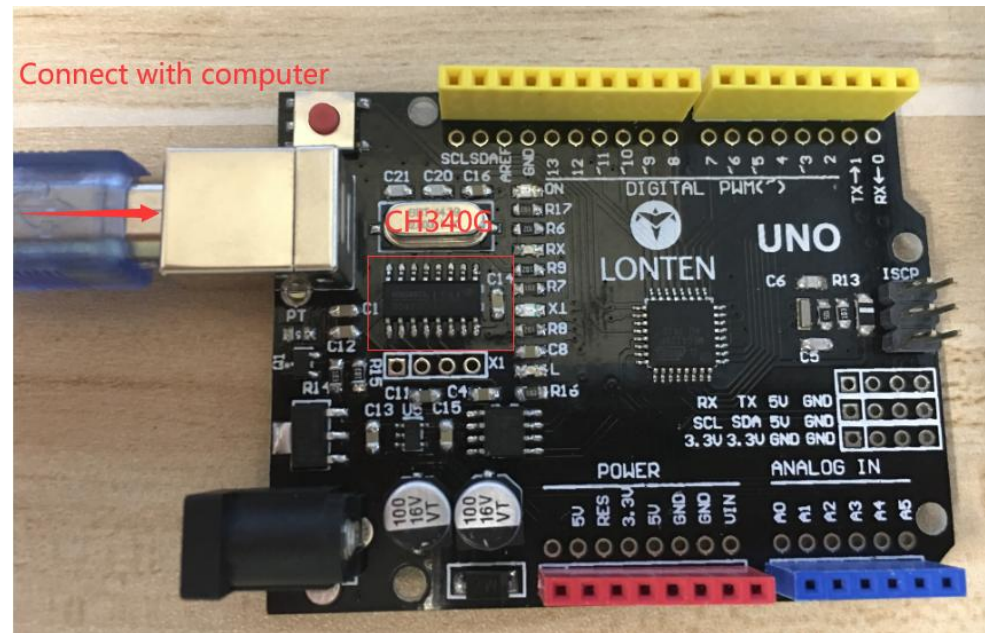


# LROBBUYA

## How to Install Arduino Driver

For Windows

Arduino UNO(serial conversion chip is CH340G)





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The USB to serial port chip of this control board is CH340G. So you need to install the driver for the chip. You can click the driver file [here](#).

In different systems, the driver installation is similar. Here we start to install the driver on the Win10 system. You can find the “USB\_Drive\_CH341\_3\_1” folder in the information we provide, this is the driver file we want to install.

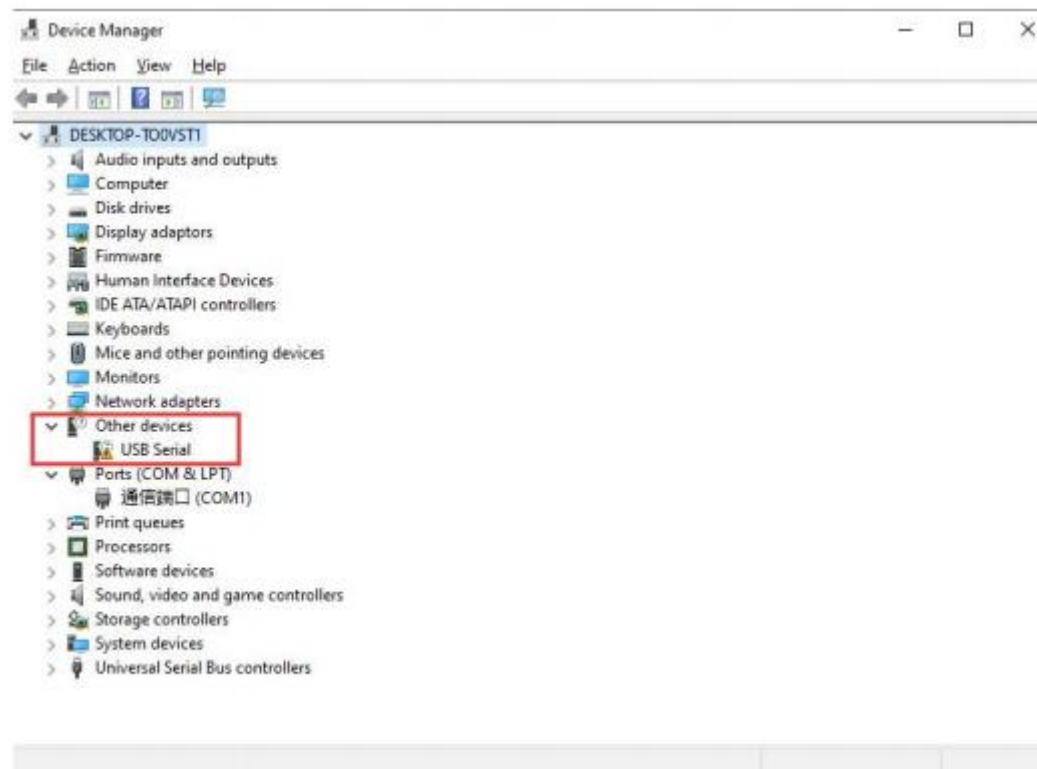


Plug one end of your USB cable into the Arduino UNO CH340 Board and the other into a USB socket on your computer.

When you connect the Arduino UNO CH340 Board to your computer at the first time, right click your “My Computer”—>for “Properties”—>click the “Device manager”, under Other devices, you should see the “USB-Serial” or “Unknown device ”.Or you can search for "devi" in your computer, or you can open the device manager of your

# LROBROYA

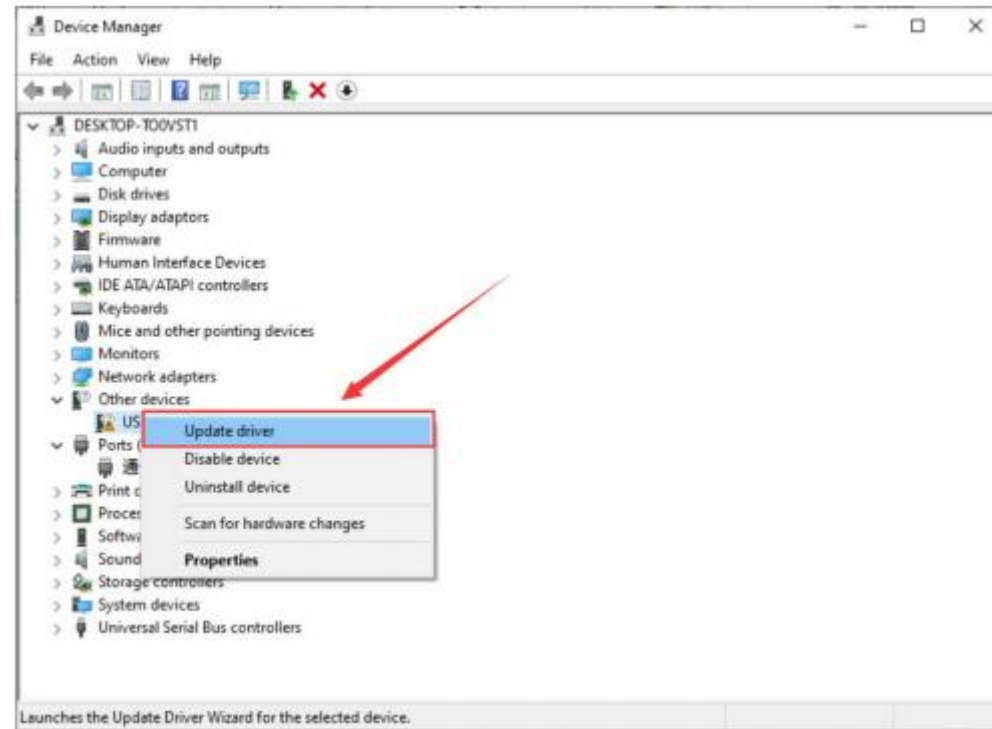
computer.



Then right-click on the device and select the top menu option (Update Driver Software...) shown as the figure below.

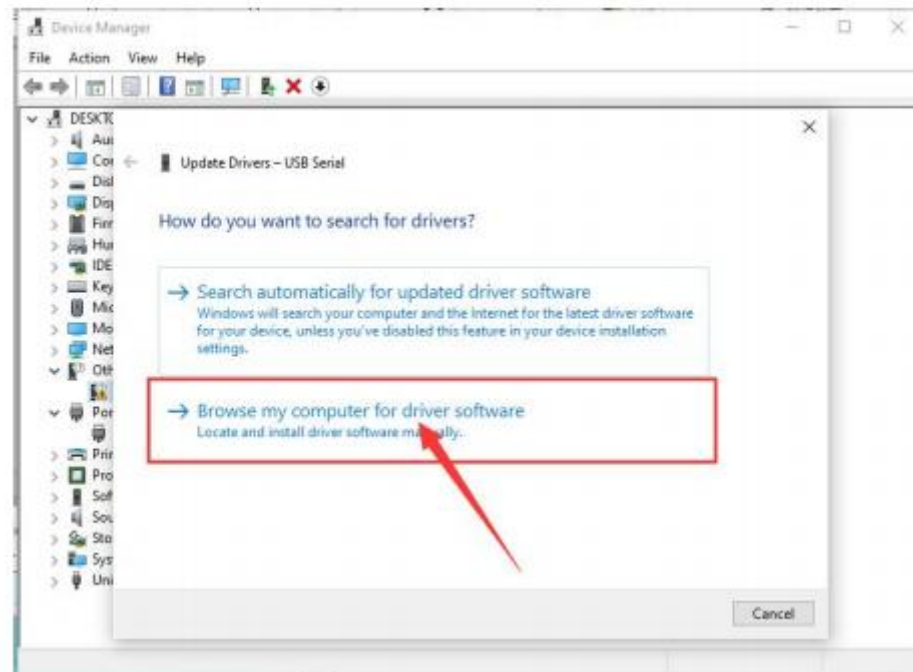


# LROBBUYA



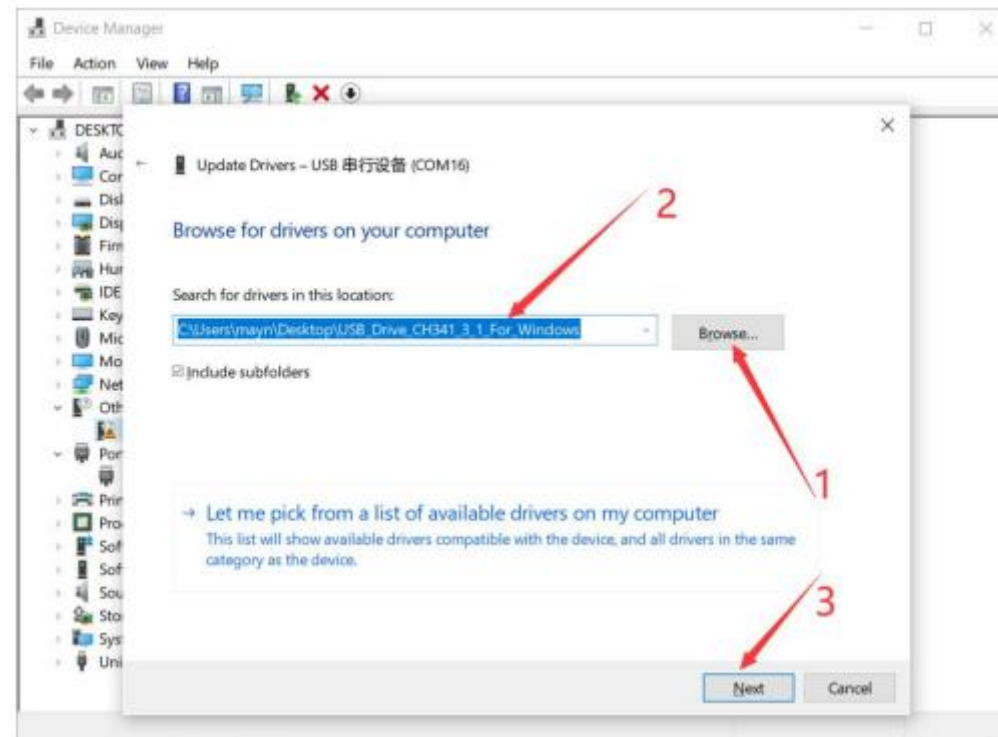
Then it will be prompted to either “Search Automatically for updated driver software” or “Browse my computer for driver software”. Shown as below. In this page, select “Browse my computer for driver software”.

# LROBROYA



After that, select the browse option and navigate to the drive folder "USB\_Drive\_CH341\_3\_1", which can be found in the information we provide. (Note that the file path selects the location of the .For example, I store this driver file on the computer desktop, so the file path I choose is `C:\Users\mayn\Desktop\USB_Drive_CH341_3_1_For_Windows` )

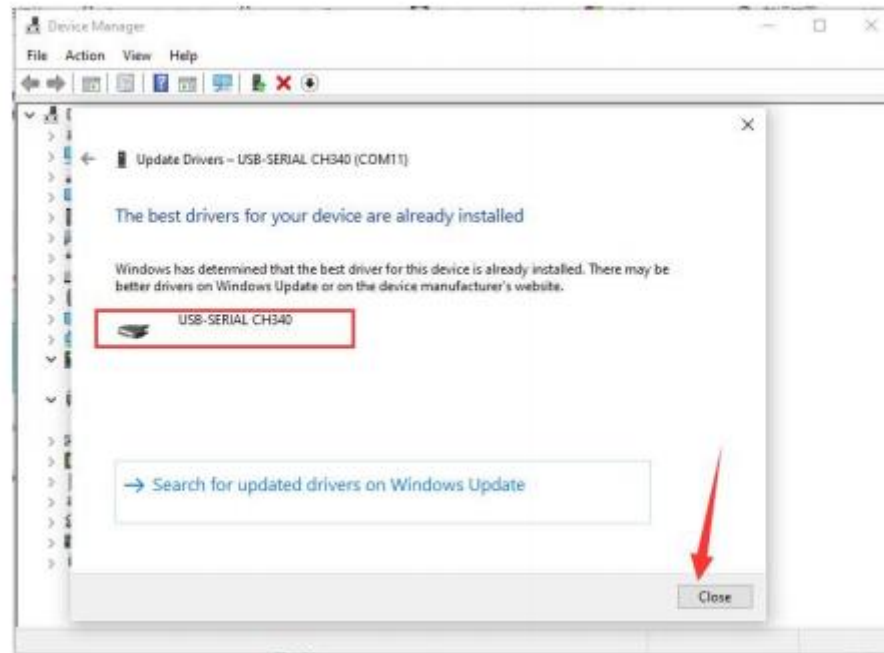
# LROBROYA



Once the software has been installed, you will get a confirmation message.

Installation completed, click “Close”.

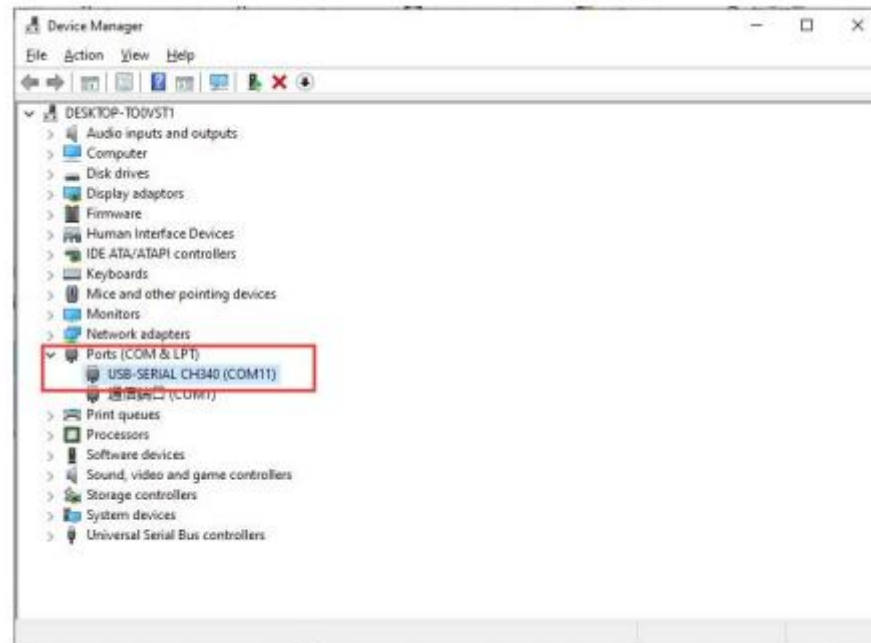
# LROBROYA



Up to now, the driver is installed well. Then you can right click “My Computer”—>for “Properties”—>click the “Device manager”, you should see the device as the figure shown below. Or you can search for "devi" in your computer, or you can open the device manager of your computer.

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**For MAC System**

**Arduino UNO(serial conversion chip is CH340G)**

Plug one end of your USB cable into the Arduino UNO CH340 Board and the other into a USB socket on your computer.



# LROBROYA

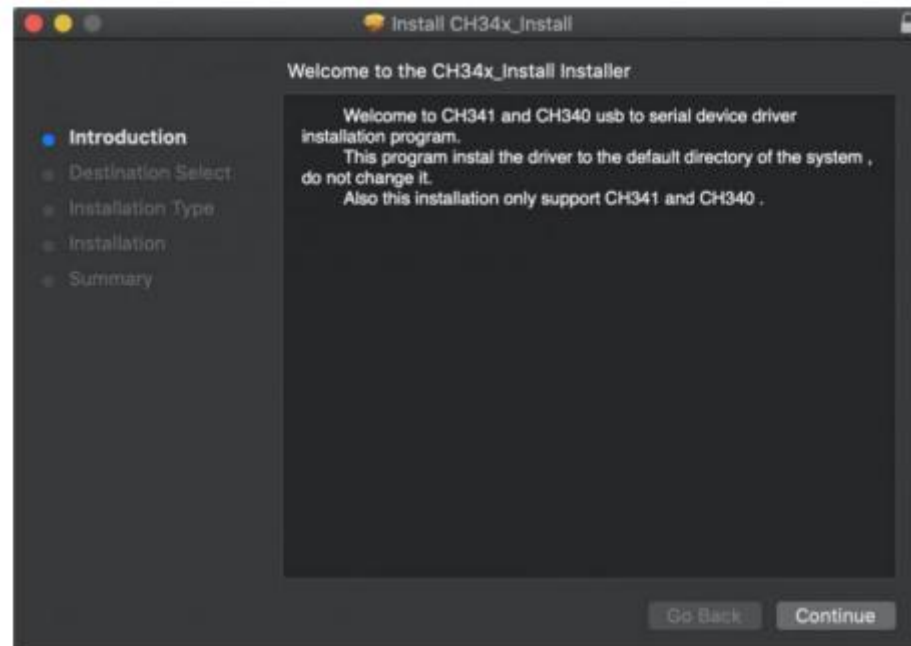
---



Double-click installation package and tap Continue

# LROBROYA

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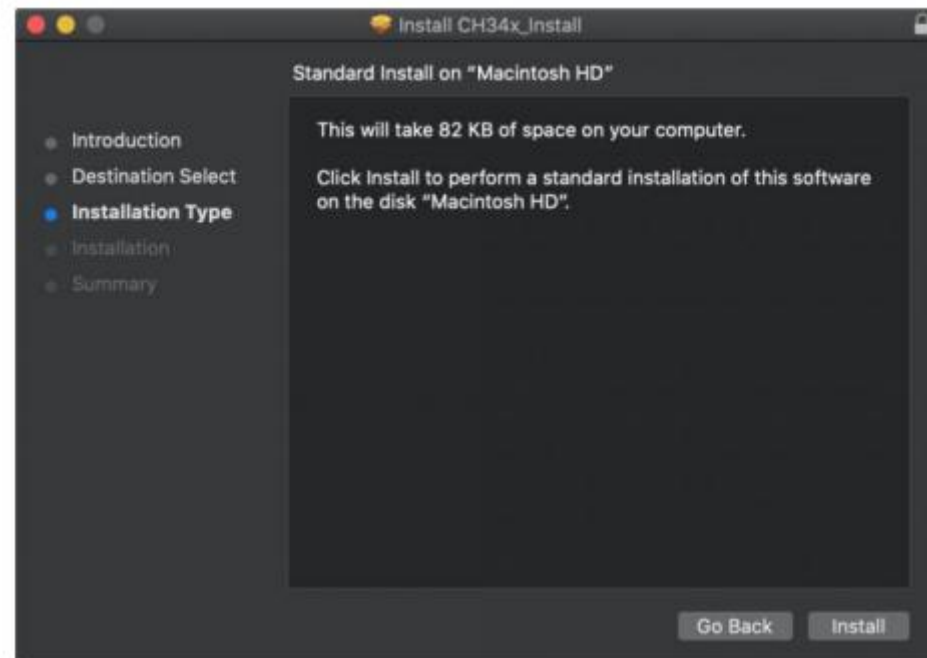


Click Install



# LROBRUYA

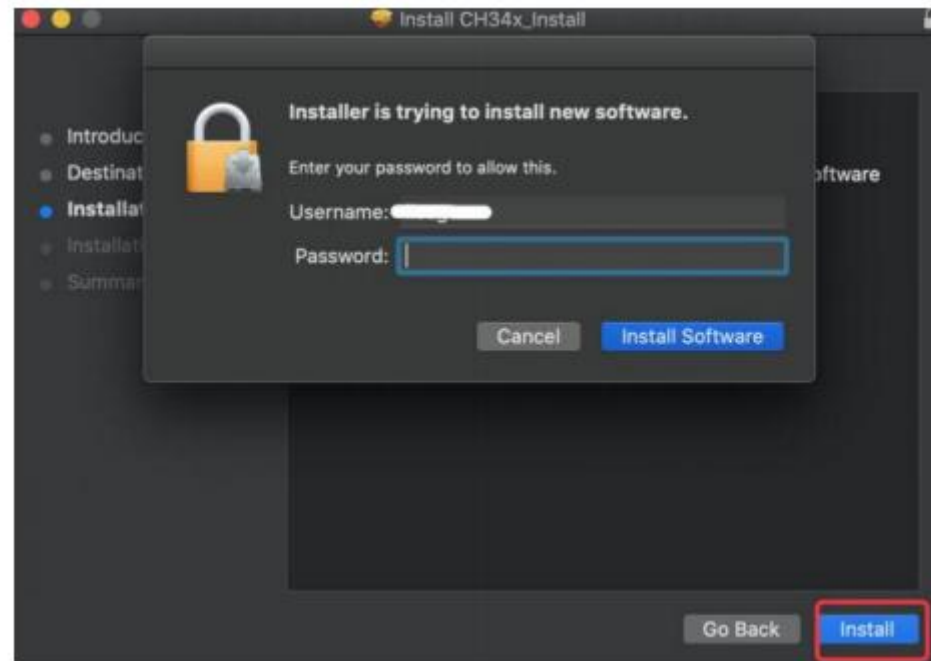
---



Input your user password and click Install Software

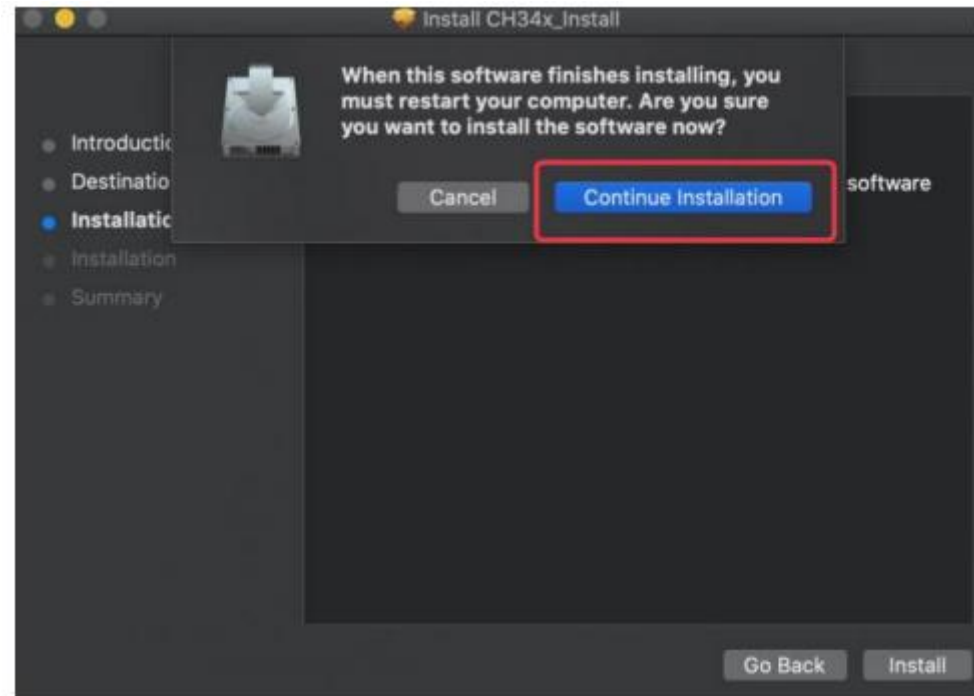
# LROBROYA

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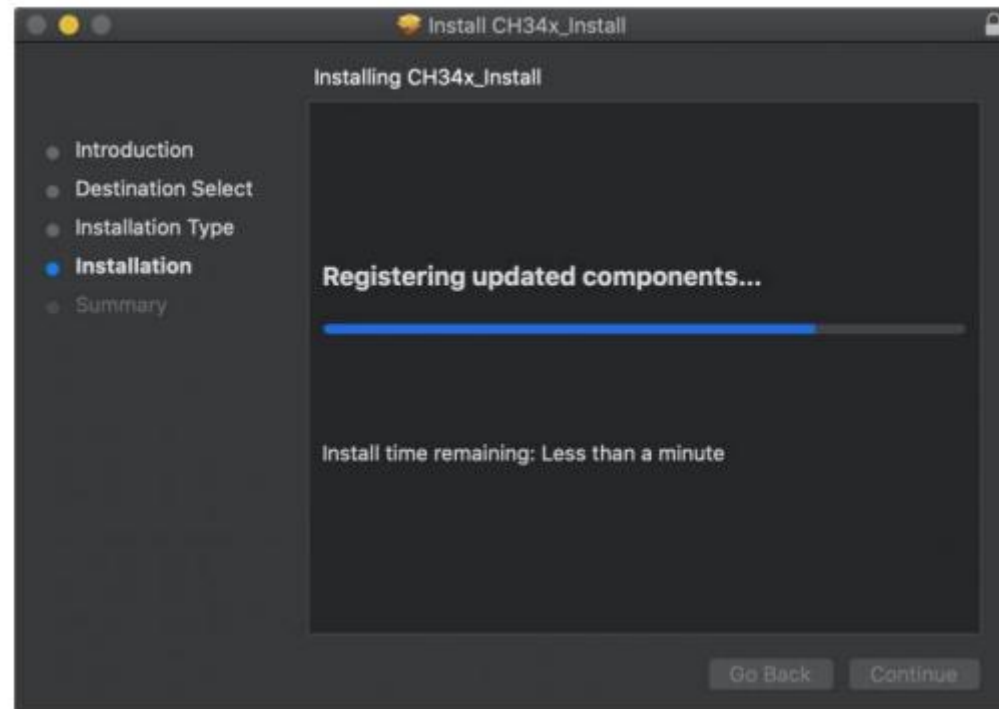
Tap Continue Installation

# LROBROYA



Wait to install

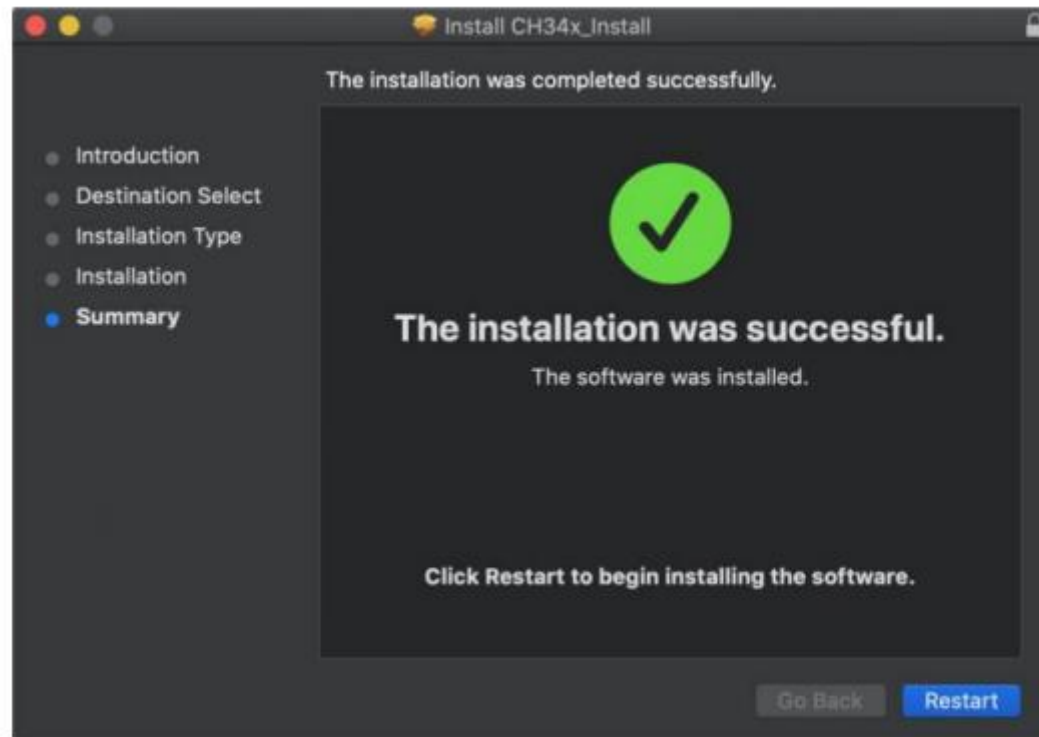
# LROBROYA



Click Restart after the installation is finished

# LROBBUYA

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## How to Add Arduino Libraries

### Installing Additional Arduino Libraries

Once you are comfortable with the Arduino software and using the built-in functions, you may want to extend the ability of your Arduino with additional libraries.

### What are Libraries?

Libraries are a collection of code that makes it easy for you to connect to a sensor, display, module, etc. For example, the built-in Liquid Crystal library makes it easy to talk to character LCD displays. There are hundreds of additional libraries available on the Internet for download.

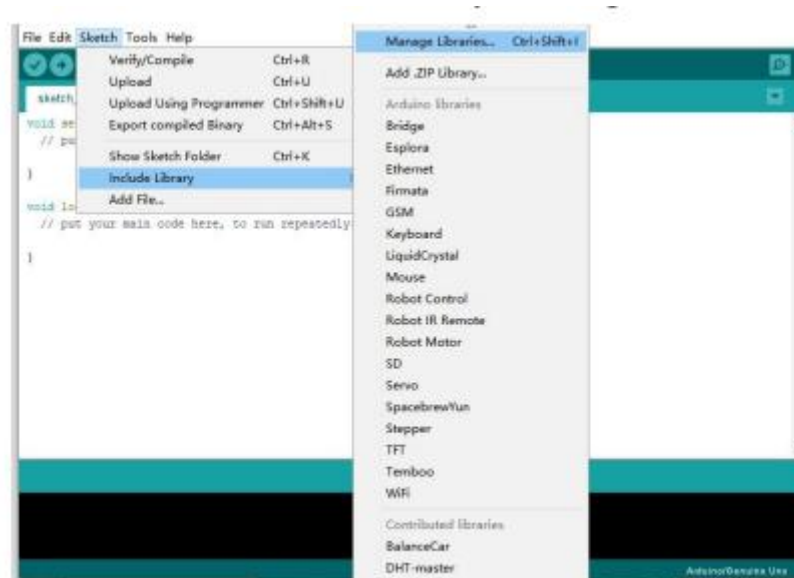
The built-in libraries and some of these additional libraries are listed in the reference. To use the additional libraries, you will need to install them.

### How to Install a Library

# LROBROYA

## Using the Library Manager

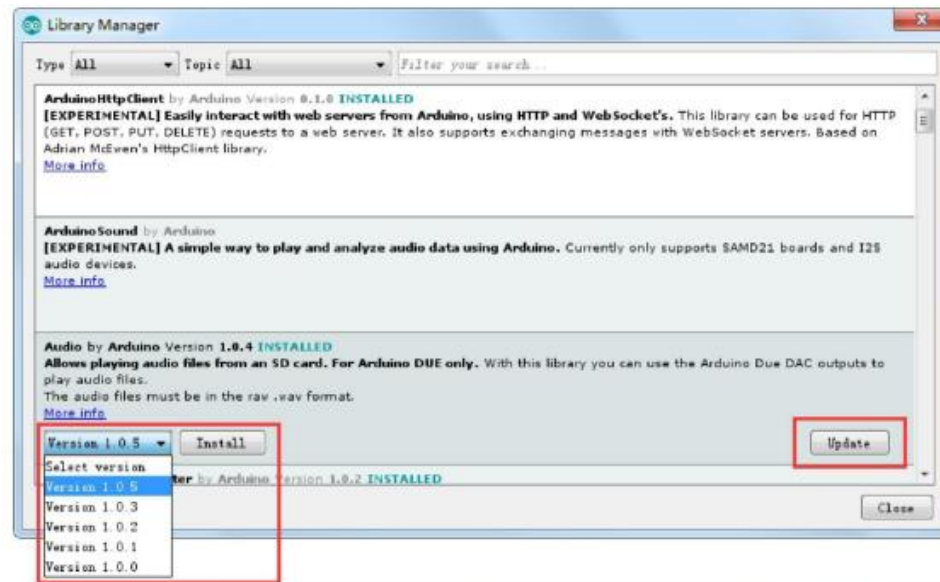
To install a new library into your Arduino IDE you can use the Library Manager (available from IDE version 1.8.0). Open the IDE and click to the "Sketch" menu and then Include Library > Manage Libraries.



# LROBROYA

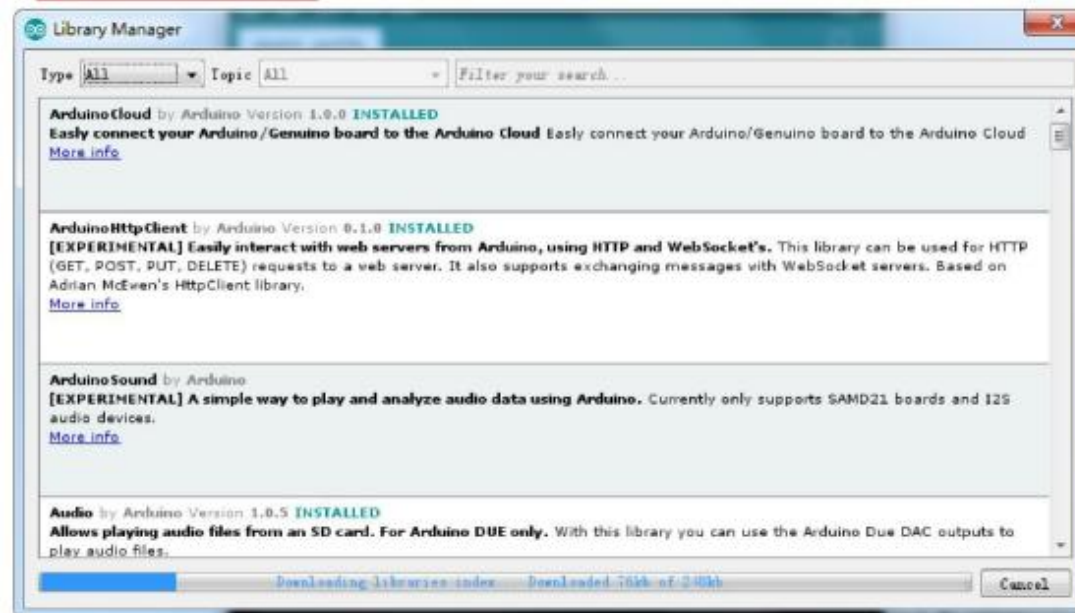
Then the library manager will open and you will find a list of libraries that are already installed or ready for installation. In this example we will install the Bridge library. Scroll the list to find it, then select the version of the library you want to install. Sometimes only one version of the library is available. If the version selection menu does not appear, don't worry: it is normal.

There are times you have to be patient with it, just as shown in the figure. Please refresh it and wait.





# LROBRUYA



Finally click on install and wait for the IDE to install the new library.

Downloading may take time depending on your connection speed. Once it has finished, an Installed tag should appear next to the Bridge library.

You can close the library manager.

# LROBROYA

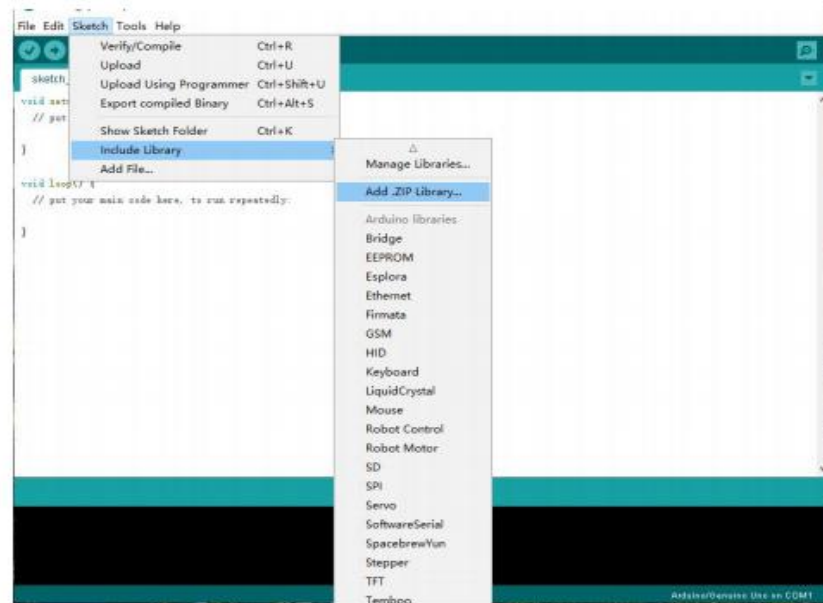


You can now find the new library available in the Include Library menu. If you want to add your own library open a new issue on [Github](#).

## Importing a .zip Library

# LROBROYA

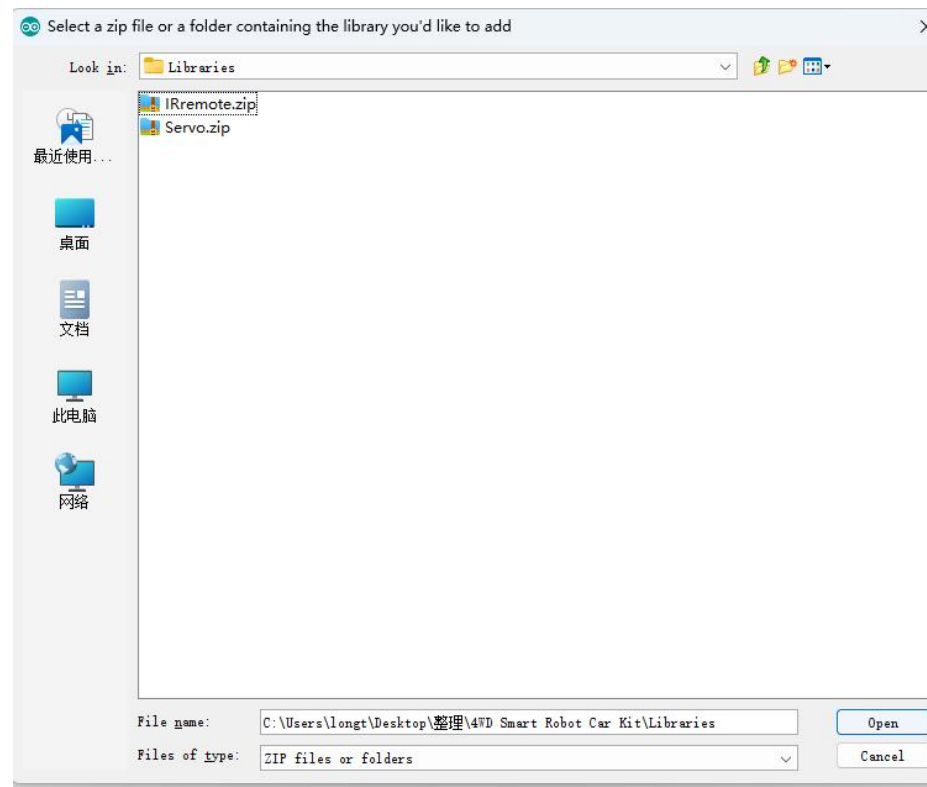
Libraries are often distributed as a ZIP file or folder. The name of the folder is the name of the library. Inside the folder will be a .cpp file, a .h file and often a keywords.txt file, examples folder, and other files required by the library. Starting with version 1.0.5, you can install 3rd party libraries in the IDE. Do not unzip the downloaded library, leave it as is. In the Arduino IDE, navigate to Sketch > Include Library. At the top of the drop down list, select the option to "Add .ZIP Library".



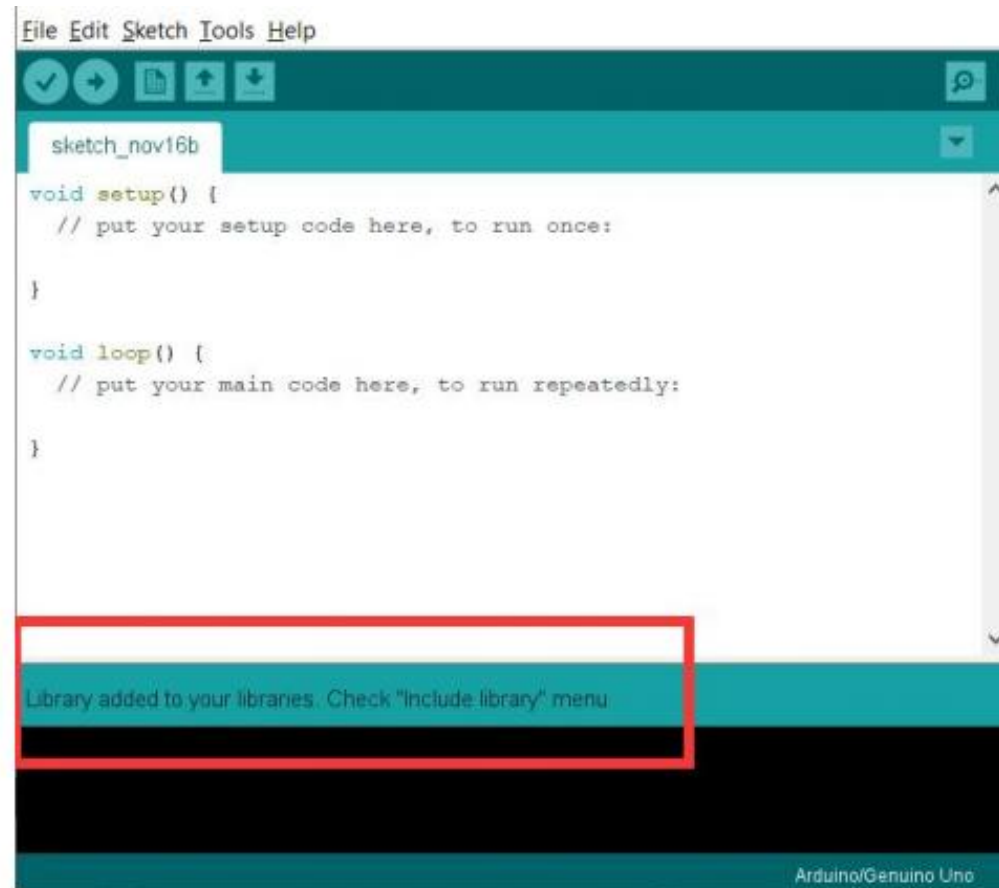
# LROBROYA

You will be prompted to select the library you would like to add.

Navigate to the .zip file's location and open it.



# LROBROYA





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Return to the Sketch > Import Library menu. You should now see the library at the bottom of the drop-down menu. It is ready to be used in your sketch. The zip file will have been expanded in the libraries folder in your Arduino sketches directory. **NB: the Library will be available to use in sketches, but examples for the library will not be exposed in the File > Examples until after the IDE has restarted.**

## Blink Test

### Overview

In this Project, you will learn how to program your UNO R3 controller board to blink the Arduino's built-in LED, and how to download programs by basic steps.

### Component Required:

LONTEN Uno R3 Board\* 1



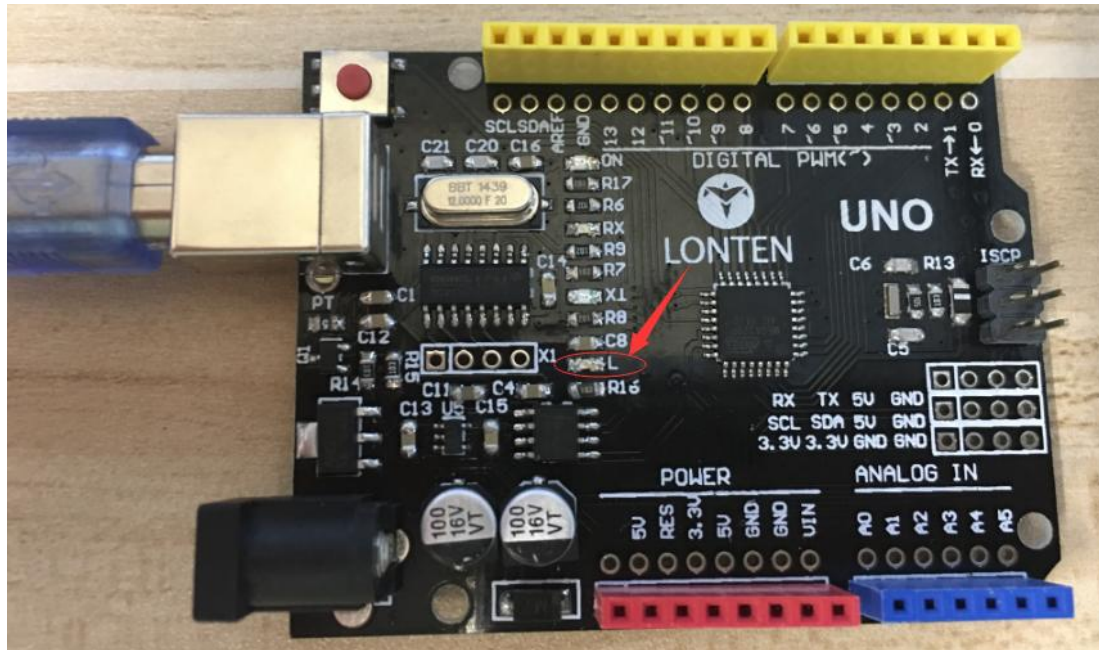
---

## Principle

The UNO R3 board has rows of connectors along both sides that are used to connect to several electronic devices and plug-in 'shields' that extends its capability.

It also has a single LED that you can control from your sketches. This LED is built onto the UNO R3 board and is often referred to as the 'L' LED as this is how it is labeled on the board.

# LROBRUYA



In this Project, we will reprogram the UNO board with our own Blink sketch and then change the rate at which it blinks.

In the previous chapter-How to install Arduino IDE, you set up your Arduino IDE and made sure that you could find the right serial port for it to connect to your UNO board. The time has now come to put that connection to the test and program your UNO board.



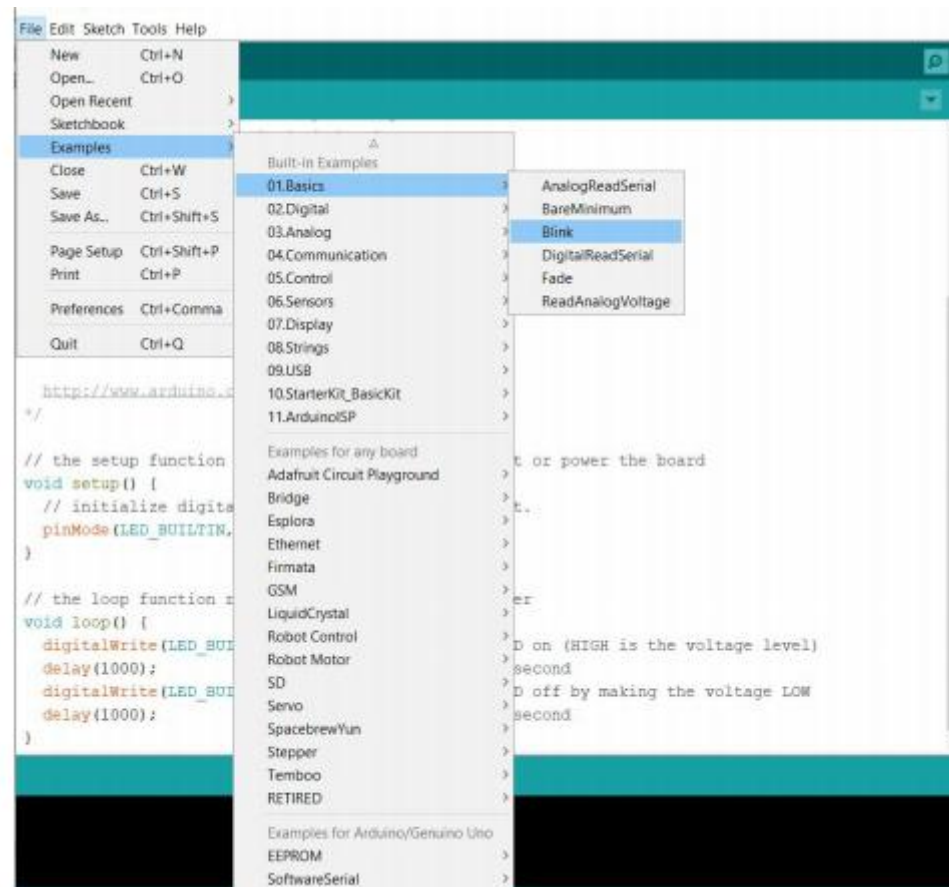


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The Arduino IDE includes a large collection of example sketches that you can load up and use. This includes an example sketch for making the 'L' LED blink.

Load the 'Blink' sketch that you will find in the IDE's menu system under File > Examples > 01.Basics

# LROBROYA



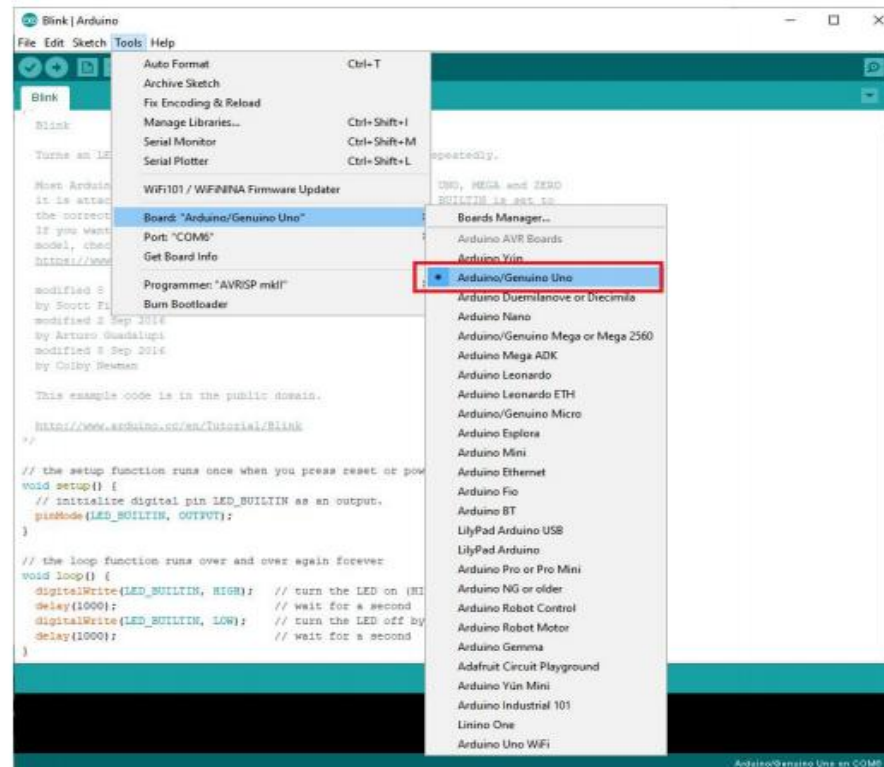
When the sketch window opens, enlarge it so that you can see the entire sketch in the window.

# LROBROYA

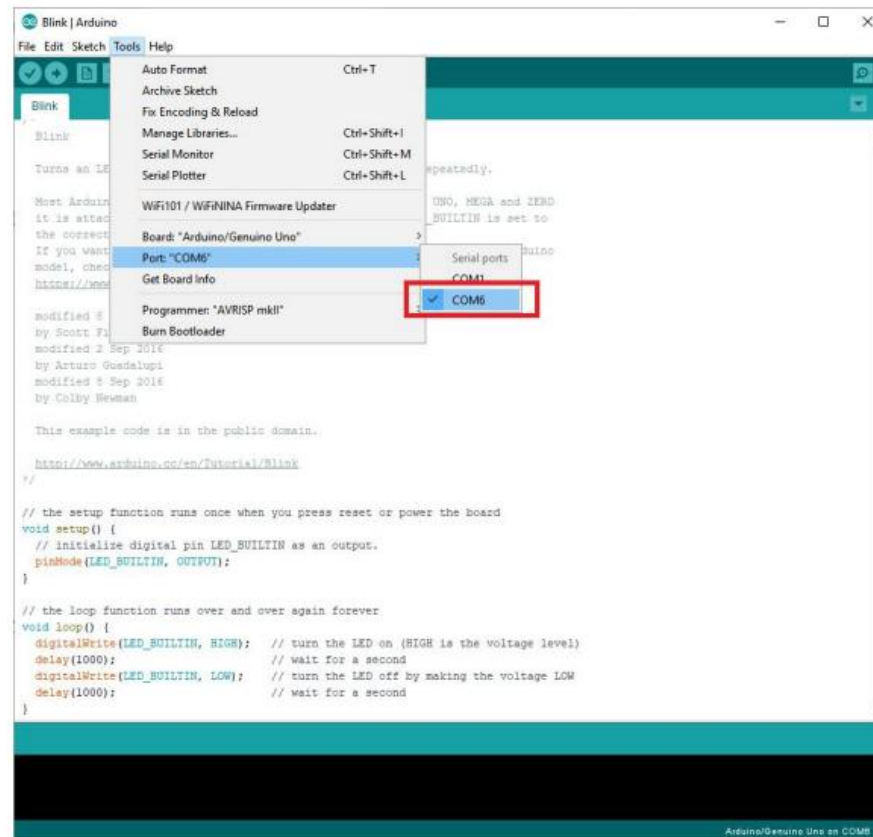
```
File Edit Sketch Tools Help
[Icons] [Serial Monitor Icon]
Blink [Close Icon]
22
23
24 // the setup function runs once when you press reset or power the board
25 void setup() {
26   // initialize digital pin LED_BUILTIN as an output.
27   pinMode(LED_BUILTIN, OUTPUT);
28 }
29
30 // the loop function runs over and over again forever
31 void loop() {
32   digitalWrite(LED_BUILTIN, HIGH); // turn the LED on (HIGH is the voltage level)
33   delay(1000); // wait for a second
34   digitalWrite(LED_BUILTIN, LOW); // turn the LED off by making the voltage LOW
35   delay(1000); // wait for a second
36 }
[Serial Monitor Area]
23 Arduino Uno on COM3
```

# LROBROYA

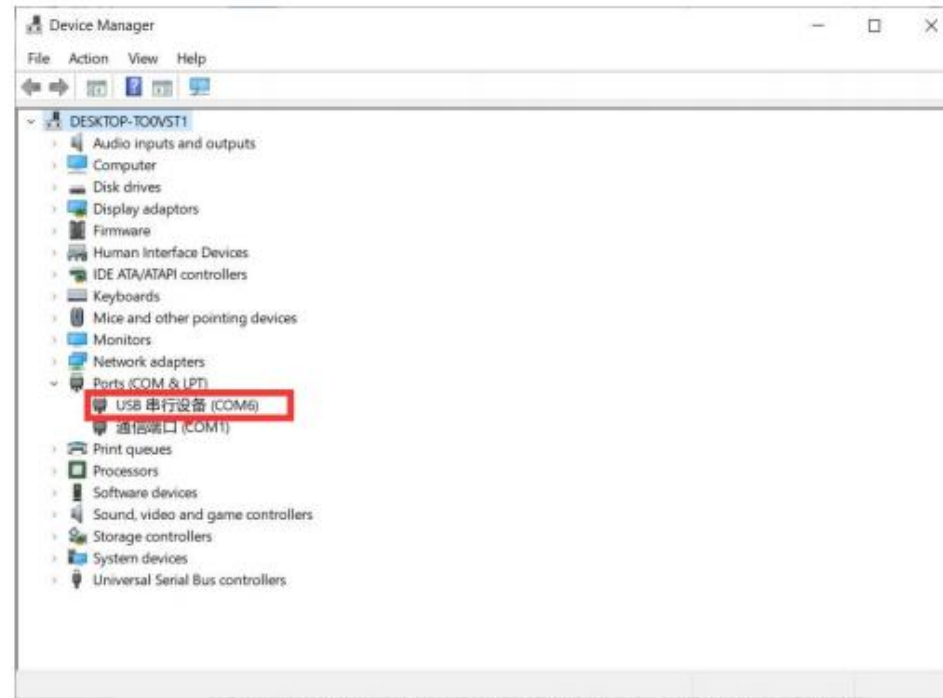
Attach your Arduino board to your computer with the USB cable and check that the 'Board Type' and 'Serial Port' are set correctly.



# LROBROYA



# LROBROYA



**Note: The Board Type and Serial Port here are not necessarily the same as shown in picture. If you are using UNO, then you will have to choose Arduino UNO as the Board Type, other choices can be made in the same manner. And**

# LROBROYA

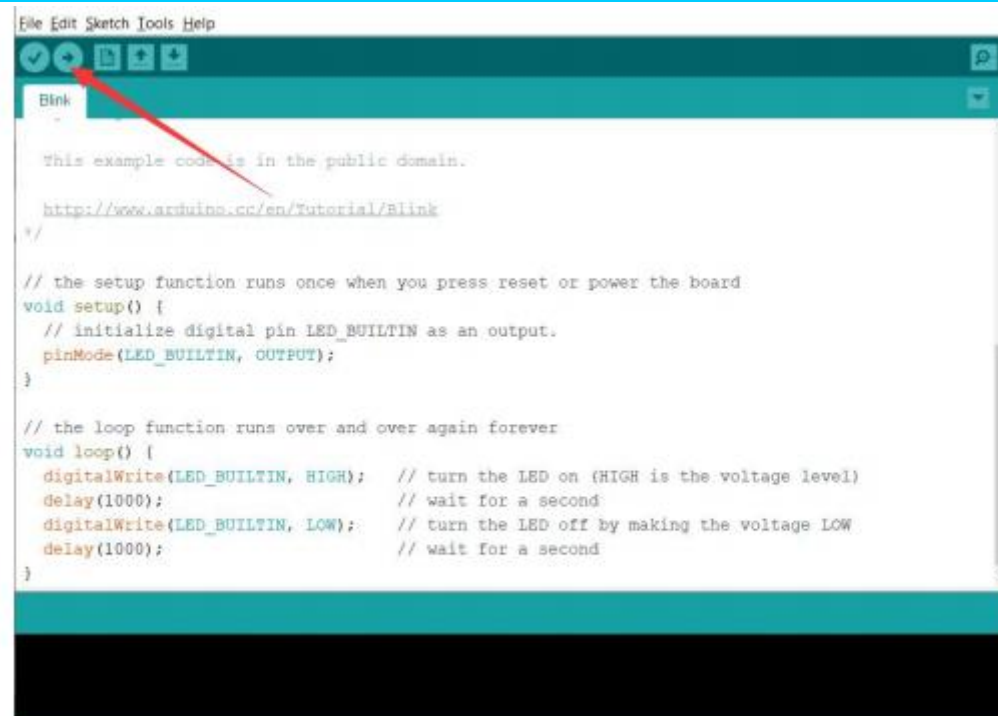
the Serial Port displayed for everyone is different, despite COM 6 chosen here, it could be COM3 or COM4 on your computer. A right COM port is supposed to be COMX (arduino XXX), which is by the certification criteria.

The Arduino IDE will show you the current settings for board at the bottom of the window.



Click on the 'Upload' button. The second button from the left on the toolbar.

# LROBROYA



```
File Edit Sketch Tools Help

Blink

This example code is in the public domain.

http://www.arduino.cc/en/Tutorial/Blink
*/

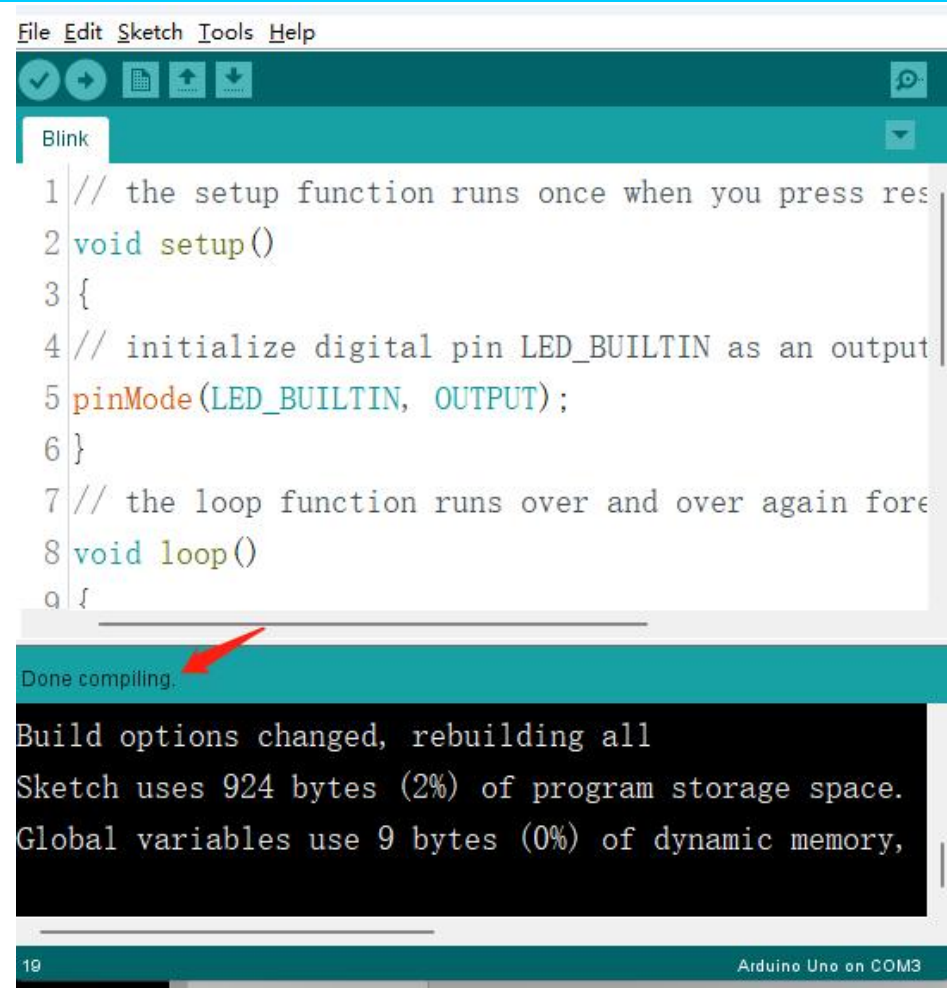
// the setup function runs once when you press reset or power the board
void setup() {
  // initialize digital pin LED_BUILTIN as an output.
  pinMode(LED_BUILTIN, OUTPUT);
}

// the loop function runs over and over again forever
void loop() {
  digitalWrite(LED_BUILTIN, HIGH); // turn the LED on (HIGH is the voltage level)
  delay(1000);                     // wait for a second
  digitalWrite(LED_BUILTIN, LOW);  // turn the LED off by making the voltage LOW
  delay(1000);                     // wait for a second
}
```

When the status bar prompts "Done uploading", it means the code upload is successful



# LROBROYA



The screenshot shows the Arduino IDE interface. The menu bar at the top includes File, Edit, Sketch, Tools, and Help. Below the menu bar is a toolbar with icons for saving, undo, redo, and other functions. The main text area displays the code for the 'Blink' sketch. The code is as follows:

```
1 // the setup function runs once when you press res
2 void setup()
3 {
4 // initialize digital pin LED_BUILTIN as an output
5 pinMode(LED_BUILTIN, OUTPUT);
6 }
7 // the loop function runs over and over again fore
8 void loop()
9 {
```

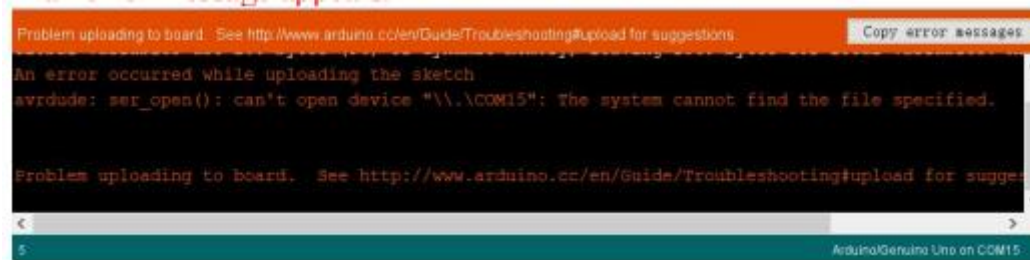
Below the code editor, a status bar indicates 'Done compiling.' with a red arrow pointing to it. Below the status bar, a black box displays the following text:

```
Build options changed, rebuilding all
Sketch uses 924 bytes (2%) of program storage space.
Global variables use 9 bytes (0%) of dynamic memory,
```

At the bottom of the IDE, the status bar shows '19' on the left and 'Arduino Uno on COM3' on the right.

# LROBROYA

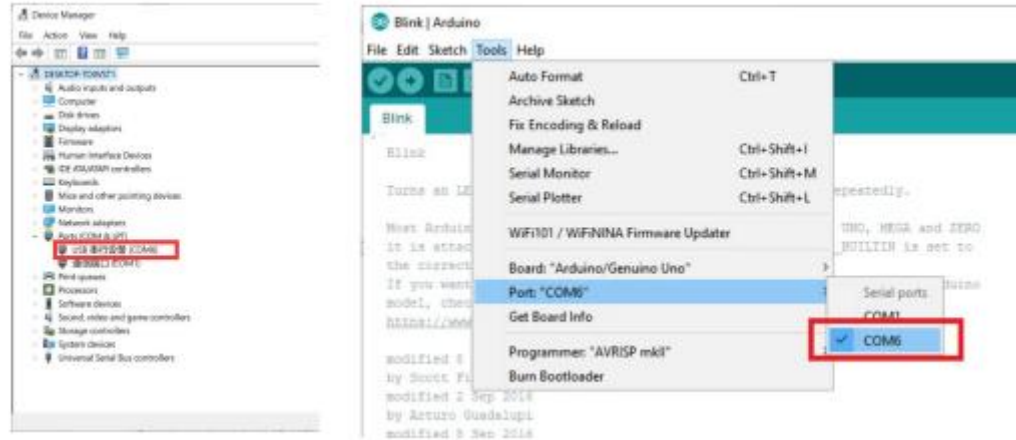
If an error message appears.



There can be several reasons:

1. The arduino uno driver software is not installed successfully, please refer to the course for the installation steps: [How to Install Arduino Driver](#).
2. The communication serial port selection of arduino uno is wrong; you can check the communication port COMx of your arduino uno in the computer in the device manager.

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3. If your Arduino uno is connected to a Bluetooth module, it will occupy the communication serial port. You need to remove the Bluetooth module connection before uploading the code.

4. The USB data cable is not firmly connected. Check if there are any of the above problems. After correcting, follow the previous steps to re-operate.



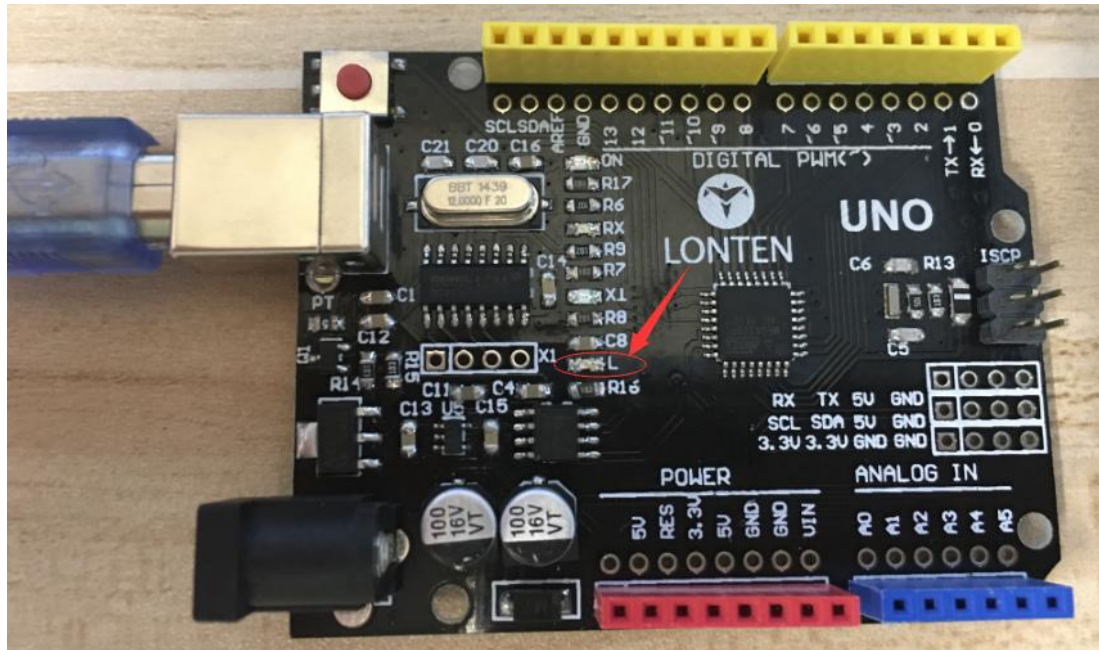
---

## Sample Program

```
void setup() // the setup function runs once when you press reset or power the board
{
    pinMode(LED_BUILTIN, OUTPUT); // initialize digital pin LED_BUILTIN as an output.
}

void loop() // the loop function runs over and over again forever
{
    digitalWrite(LED_BUILTIN, HIGH); // turn the LED on (HIGH is the voltage level)
    delay(1000); // wait for a second
    digitalWrite(LED_BUILTIN, LOW); // turn the LED off by making the voltage LOW
    delay(1000); // wait for a second
}
```

# LROBRUYA

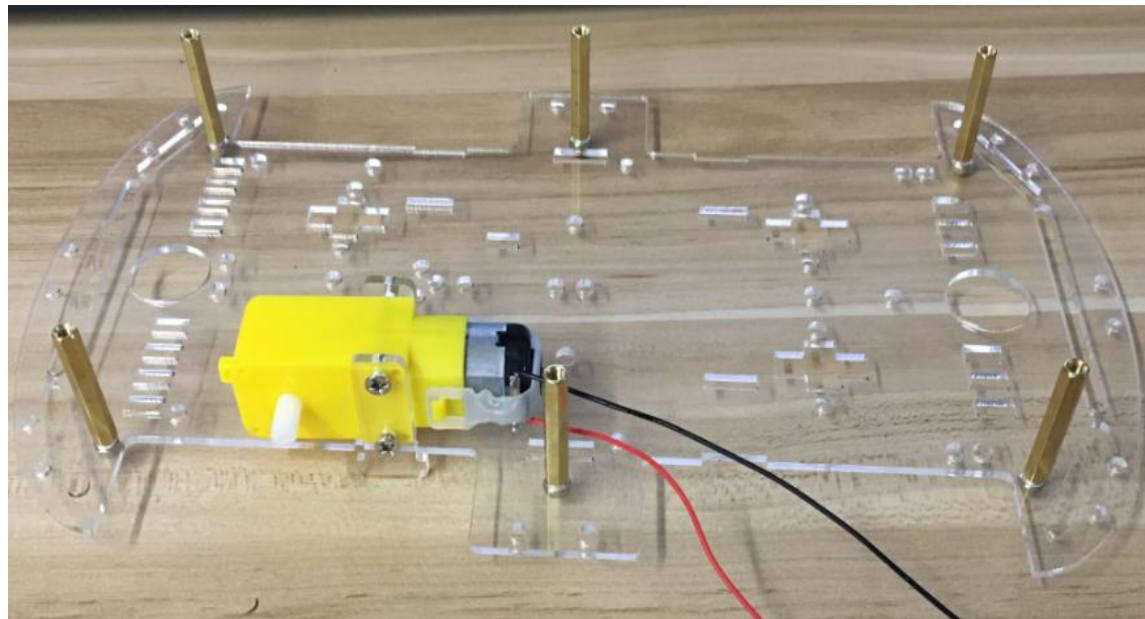


After the code is successfully uploaded, the "L" character LED will flash once per second. So far, you have completed the testing process of your first program.

# LROBROYA

## Lesson 1 Installation Method

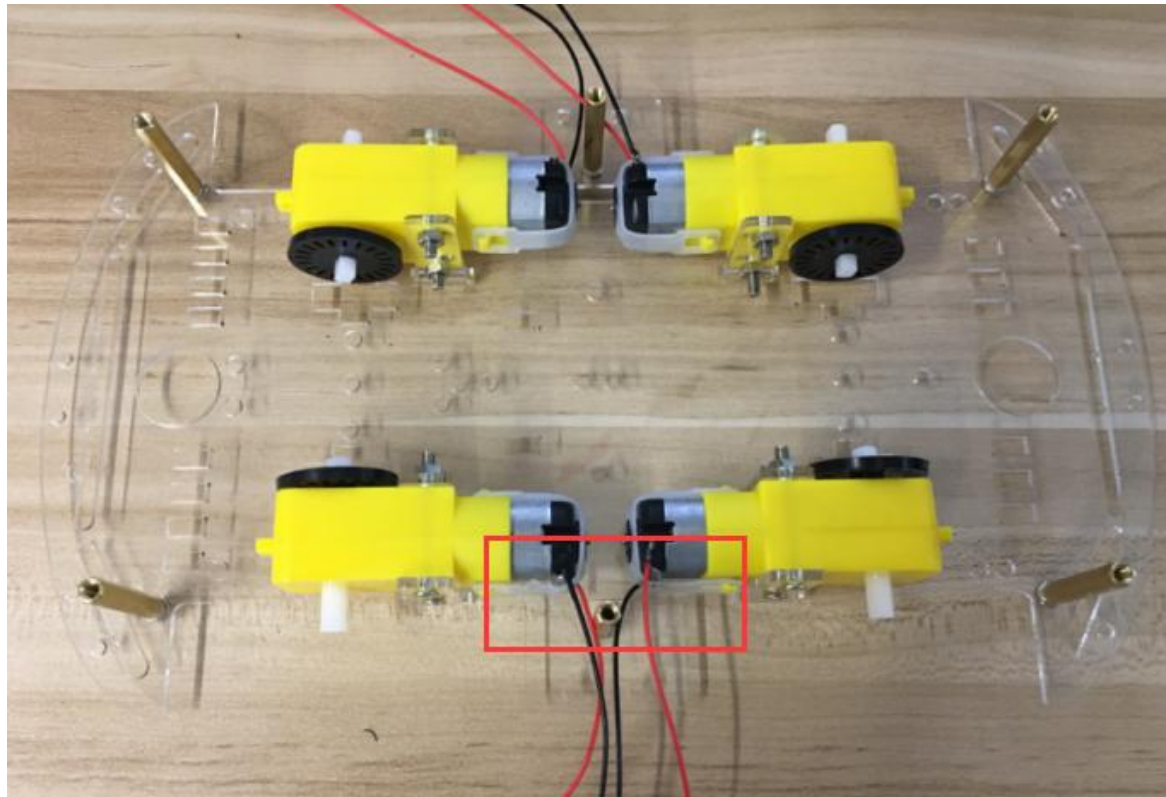
**Step1:** The positive and negative poles of a DC motor can be easily soldered without distinguishing between the positive and negative poles.





# LROBRUYA

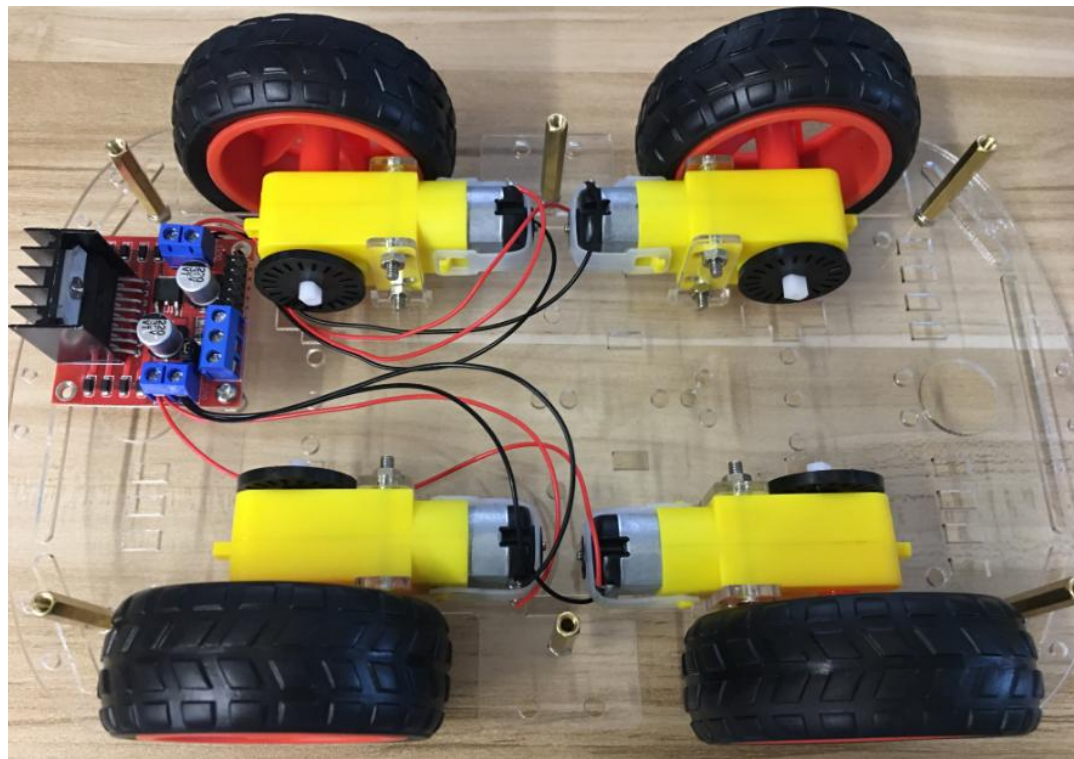
**Step2:** The positive and negative poles of two motors on the same side must be opposite, otherwise it will affect the operation of the car.



# LROBRUYA

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Step3:

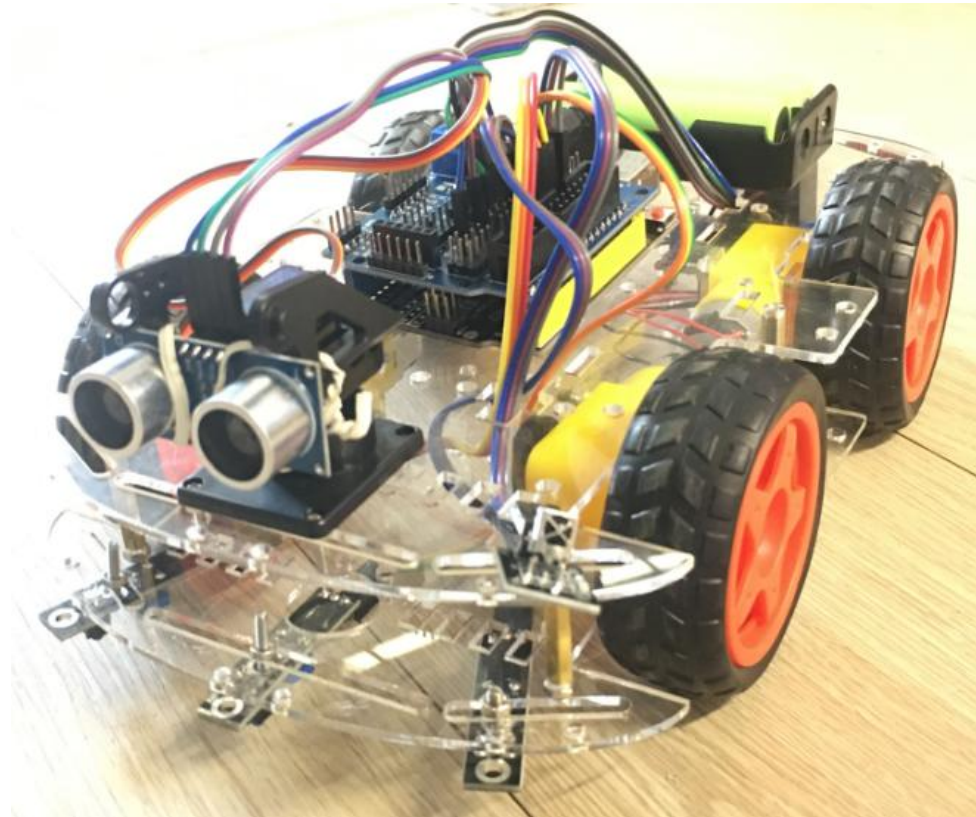




# LROBRUYA

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**Step4:**





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## Lesson 2 Servo

### **About this lesson:**

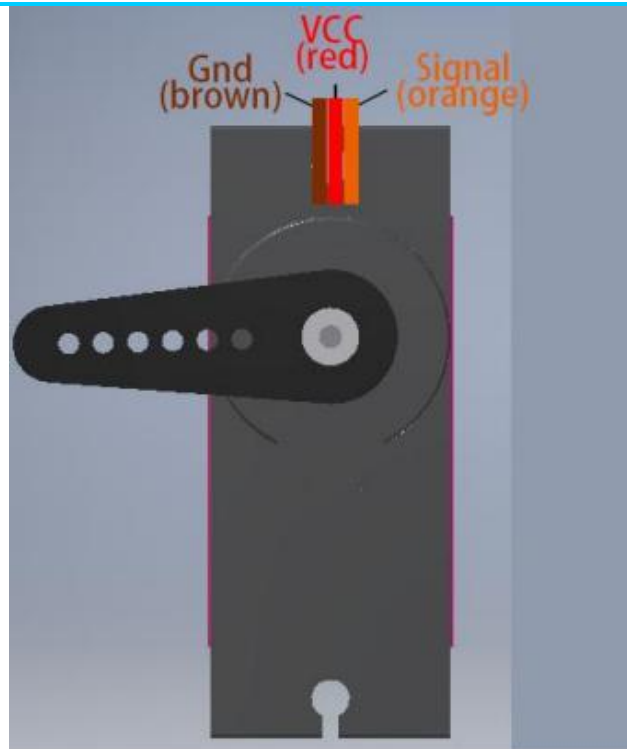
In this lesson, you will learn how to control a servo motor using Arduino UNO development board.

The servo motor has three leads. The color of the leads varies between servo motors, but the red lead is always 5V and GND will either be brown. The red one is the power wire and should be connected to the 5v port and this is usually orange.

This control lead is connected to digital pin A2.

# LROB RUYA

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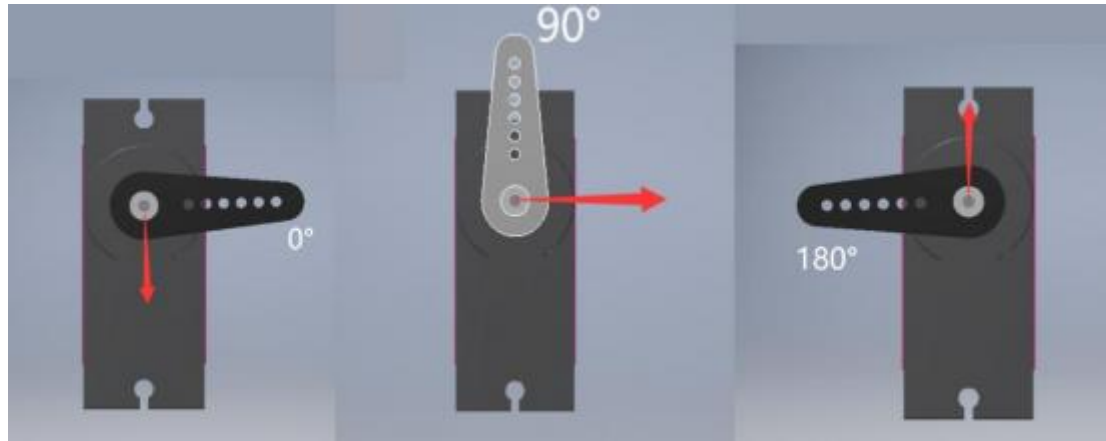
## Introduction

Servo motors are great devices that can turn to a specified position.

# LROBROYA

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Usually, they have a servo arm that can turn 180 degrees. Using the Arduino, we can tell a servo to go to a specified position and it will go there. As simple as that!



Servo motors were first used in the Remote Control (RC) world, usually to control the steering of RC cars or the flaps on a RC plane. With time, they found their uses in robotics, automation, and of course, the Arduino world.

There are two ways to control a servomotor with Arduino. One is to use a common digital sensor port of Arduino to produce square wave with different duty cycle to simulate PWM signal and use that signal to control the positioning of the

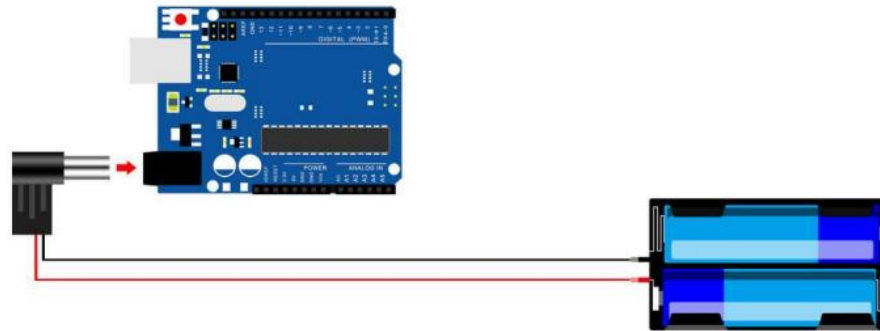


motor. Another way is to directly use the Servo function of the Arduino to control the motor. In this way, the program will be easier but it can only control two-contact motor because for the servo function, only digital pin 9 and 10 can be used. The Arduino drive capacity is limited. So if you need to control more than one motor, you will need external power.

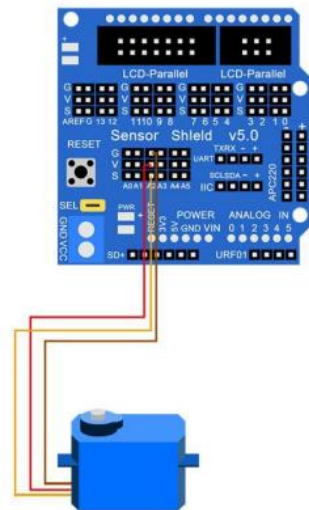
### **Connection diagram**

# LROBRUYA

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Place V5 Expanding Board on UNO





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### **Attention**

After connecting, please open the the program and load up the code - Lesson\_2\_Servo onto your Arduino board. Before you can run this, make sure that you have installed the < Servo> library or re-install it, if necessary. Otherwise, your code won't work.

### **Result**

After uploading the code, the servo motor rotates from 0 degrees to 180 degrees, 1 degree at a time. Then rotate from 180 degrees to 0 degrees, one degree at a time.



---

## Lesson 3 Ultrasonic Sensor Module

### About this lesson:

Ultrasonic sensor is great for all kind of projects that need distance measurements, avoiding obstacles as examples.

It works like a bat's eye. Determine the distance of obstacles in front after receiving and receiving high-frequency sound waves.

As the following picture shown, it is our ultrasonic module. It has two something like eyes.

One is transmitting end, the other is receiving end.



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## **Introduction:**

Ultrasonic sensor module HC-SR04 provides 2cm-400cm non-contact measurement function, the ranging accuracy can reach to 3mm. The modules includes ultrasonic transmitters, receiver and control circuit.

The basic principle of work:

- (1) Using IO trigger for at least 10us high level signal
- (2) The Module automatically sends eight 40 kHz and detect whether there is a pulse signal back.
- (3) IF the signal back, through high level , time of high output IO duration is the time from sending ultrasonic to turning.

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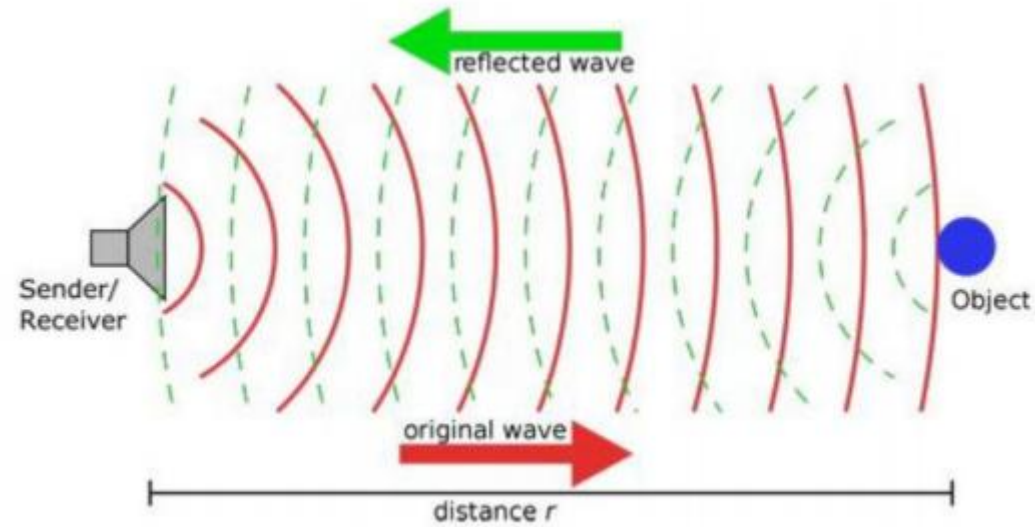
---

Test distance = (high level time  $\times$  velocity of sound (340m/s) / 2

The Timing diagram is shown below. You only need to supply a short 10us pulse to the trigger input to start the ranging, and then the module will send out an 8 cycle burst of ultrasound at 40 kHz and raise its echo. The Echo is a distance object that is pulse width and the range in proportion .You can calculate the range through the time interval between sending trigger signal and receiving echo signal. Formula:  $\text{us} / 58 = \text{centimeters}$  or  $\text{us} / 148 = \text{inch}$ ; or: the range = high level time \* velocity (340M/S) / 2; we suggest to use over 60ms measurement cycle, in order to prevent trigger signal to the echo signal.

# LROBRUYA

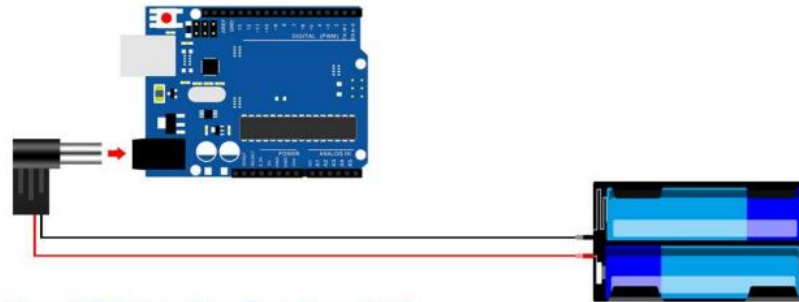
---



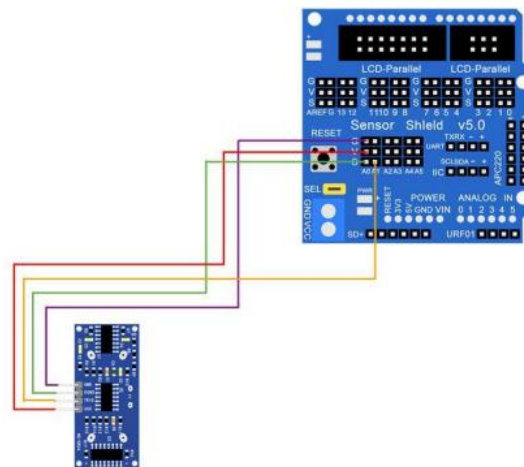
**Wiring diagram**

# LROBBUYA

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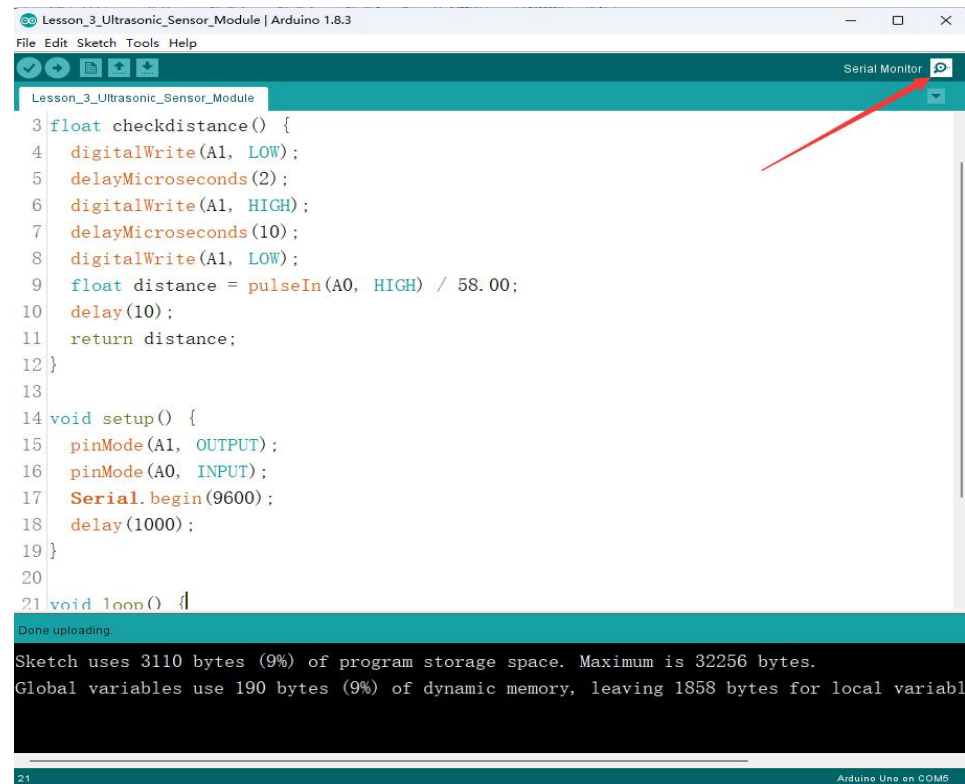
Place V5 Expanding Board on UNO



# LROBROYA

## Result

After uploading the code, click the button in the upper right corner to open the serial monitor to view the measured distance.



```
Lesson_3_Ultrasonic_Sensor_Module | Arduino 1.8.3
File Edit Sketch Tools Help
Serial Monitor
Lesson_3_Ultrasonic_Sensor_Module
3 float checkdistance() {
4   digitalWrite(A1, LOW);
5   delayMicroseconds(2);
6   digitalWrite(A1, HIGH);
7   delayMicroseconds(10);
8   digitalWrite(A1, LOW);
9   float distance = pulseIn(A0, HIGH) / 58.00;
10  delay(10);
11  return distance;
12 }
13
14 void setup() {
15   pinMode(A1, OUTPUT);
16   pinMode(A0, INPUT);
17   Serial.begin(9600);
18   delay(1000);
19 }
20
21 void loop() {
```

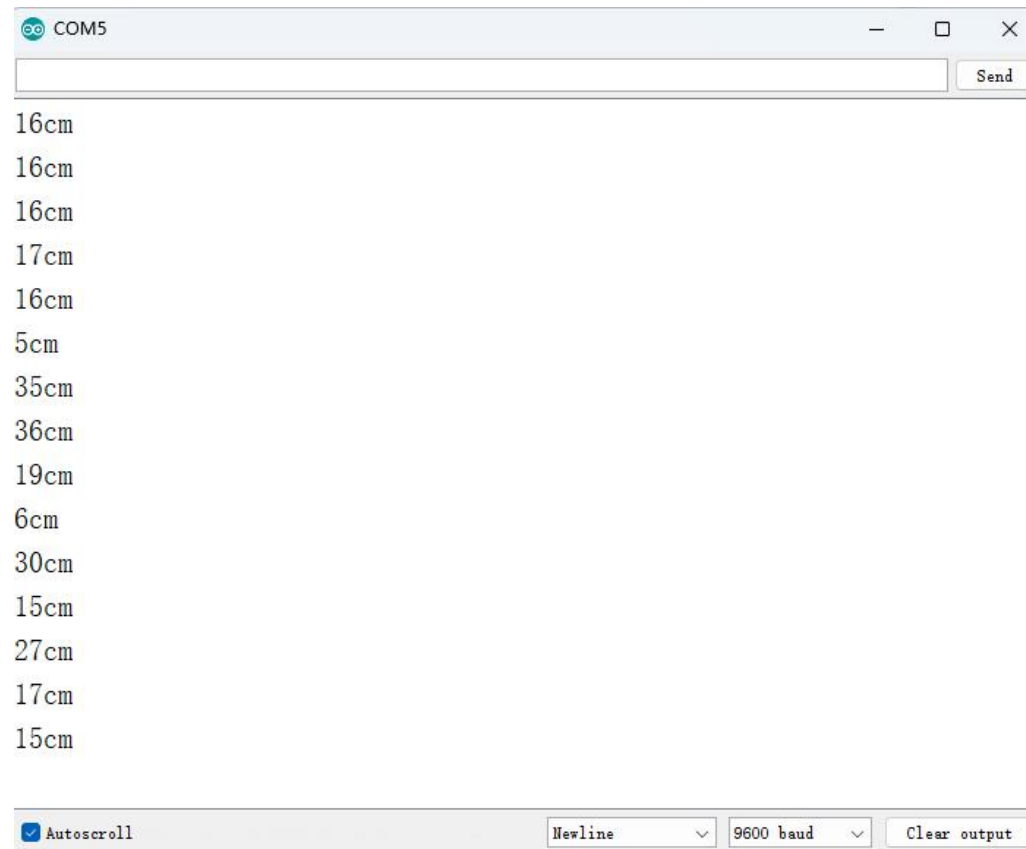
Done uploading.

Sketch uses 3110 bytes (9%) of program storage space. Maximum is 32256 bytes.  
Global variables use 190 bytes (9%) of dynamic memory, leaving 1858 bytes for local variables.

21 Arduino Uno on COM5

# LROBROYA

Then you can see the data as blow:





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## Lesson 4 L298N Motor Driver

### **About this lesson:**

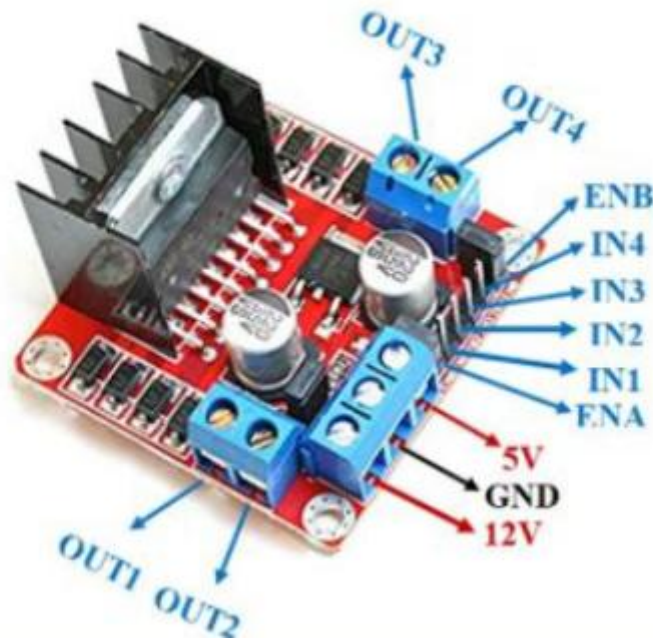
In this lesson, you will learn how to use a L298N Motor Driver module.

### **Component Introduction**

This L298N Motor Driver Module is a high power motor driver module for driving DC and Stepper Motors. This module consists of an L298 motor driver IC and a 78M05 5V regulator. L298N Module can control up to 4 DC motors, or 2 DC motors with directional and speed control.

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Using L298N made by ST Company as the control chip, the module has characteristics of strong driving ability, low calorific value and strong anti-interference ability.

This module can use built-in 78M05 for electric work via a driving power supply part. But to avoid the damage of the





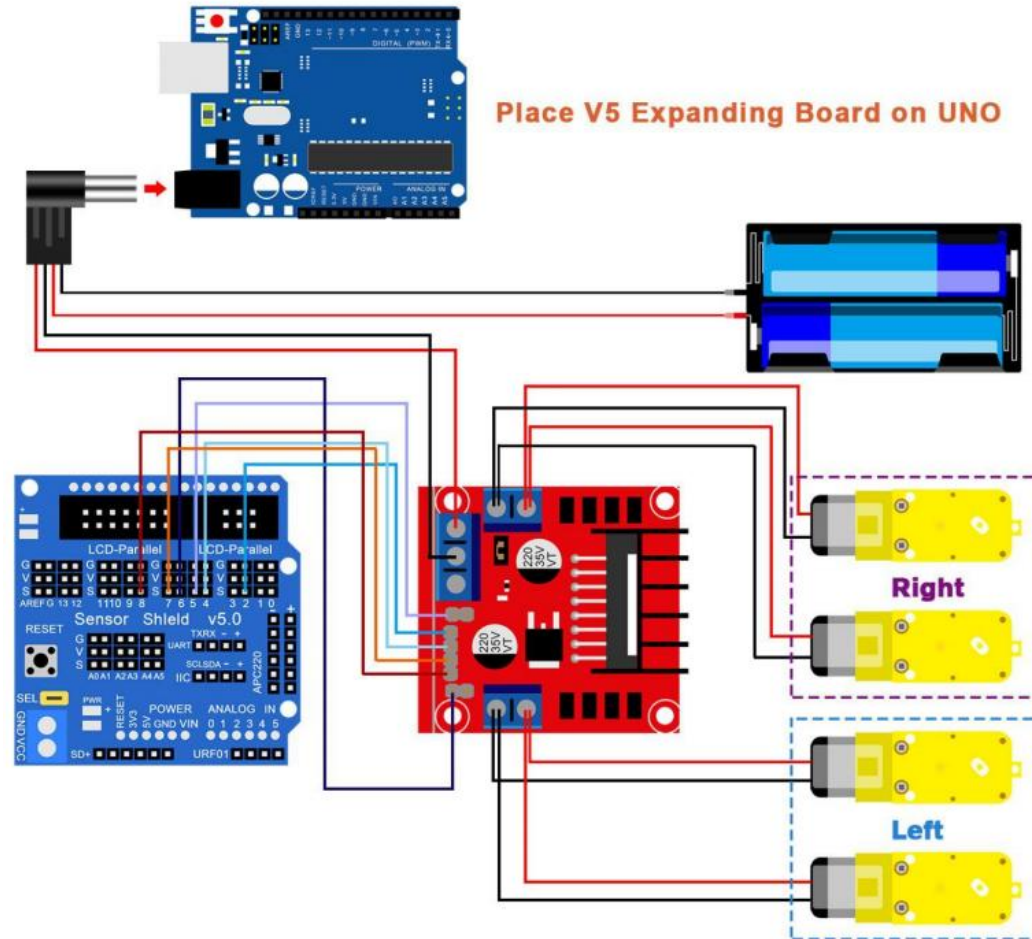
---

voltage stabilizing chip, please use an external 5V logic supply when using more than 12V driving voltage.

Using large capacity filter capacitor, this module can follow current to protect diodes, and improve reliability.

### **Wiring diagram**

# LROBRUYA





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### **Attention**

When connecting, the jumper caps of ENA and ENB must be removed.

After wiring, please open the program in the code folder- Lesson\_4\_L298N\_Motor\_Driver and click UPLOAD to upload the program.

### **Result**

After connection and power-on, two motors rotate clockwise for 2 second at a speed of 200 (PWM value is 200) and then stop for 2 second; two motors rotate anticlockwise for 2 second at a speed of 200 (PWM value is 200) and then stop for 2second; circulating like this.



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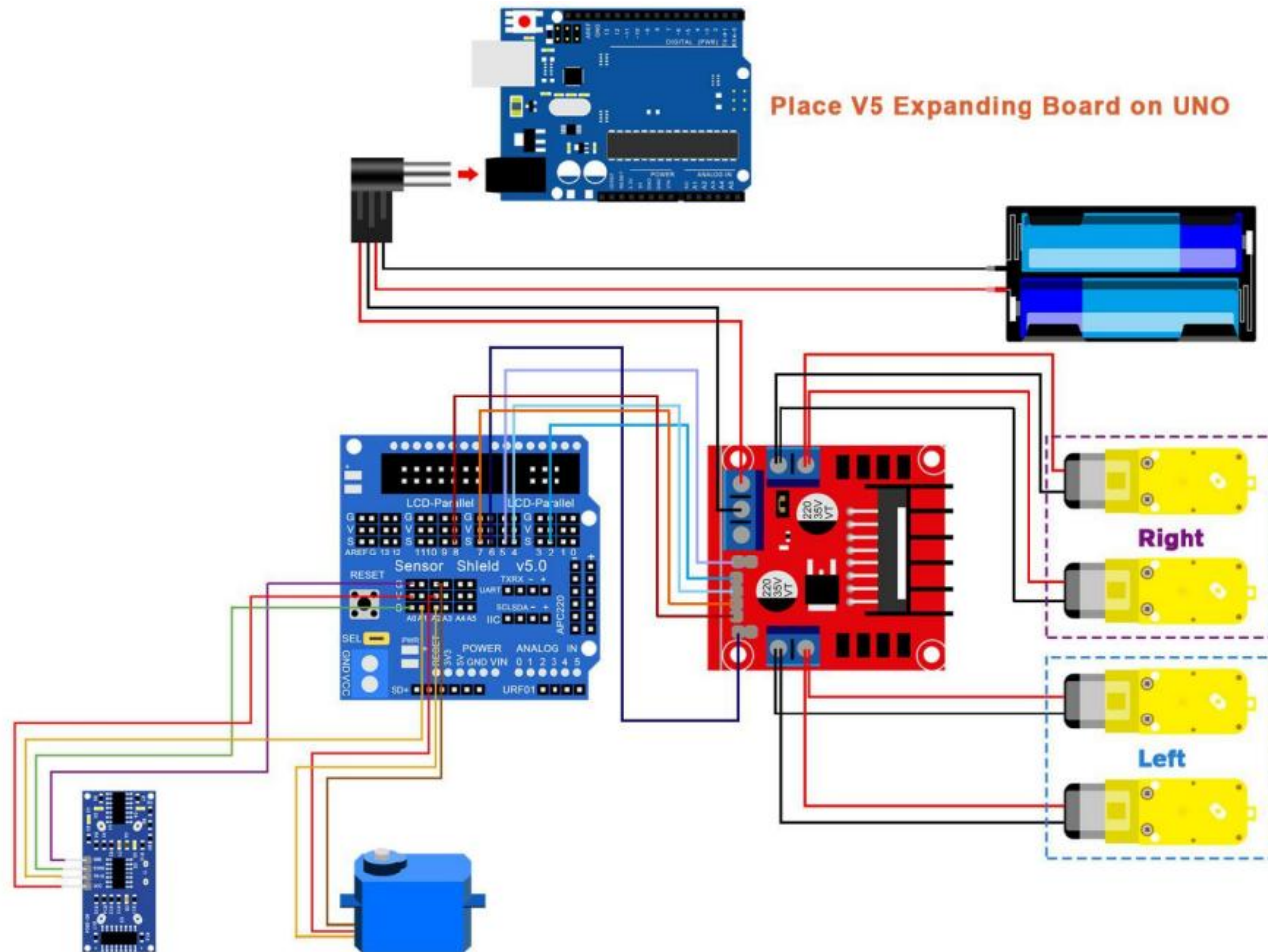
## Lesson 5 Ultrasound Obstacle Avoidance Car

### **About this lesson:**

This lesson ,regarding Arduino as main control, detect front obstacle by ultrasonic sensor and platform motor, and send the feedback to Arduino. Arduino will analyses the feedback signal and then control the driver motor to adjust the car diversion. Finally the car is able to avoid obstacle automatically and keep going.

### **Wiring diagram**

# LROBRUYA





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## Attention

After connecting, please open the the program and load up the code - Lesson\_5\_Ultrasound\_Obstacle\_Avoidance\_Car onto your Arduino board. Before you can run this, make sure that you have installed the < Servo> library or re-install it, if necessary. Otherwise, your code won't work.

## Result

1. Ultrasonic detecting distance: one port emits high level more than 10 us. Once it outputting level, open potentiometer to time. When the port becomes low level, read out current value. Use the time of detecting distance to calculate distance.
2. Use ultrasonic to detect the distance between obstacle and car, so that control the motion of the car according to the data.
3. When there is no obstacle in front of the robot car, the tank keeps walking straight. When the distance of the obstacle in front of the robot car is less than 30cm, the robot car stops, then detects whether there is an obstacle in the left front and right front, and then turns in the opposite direction.



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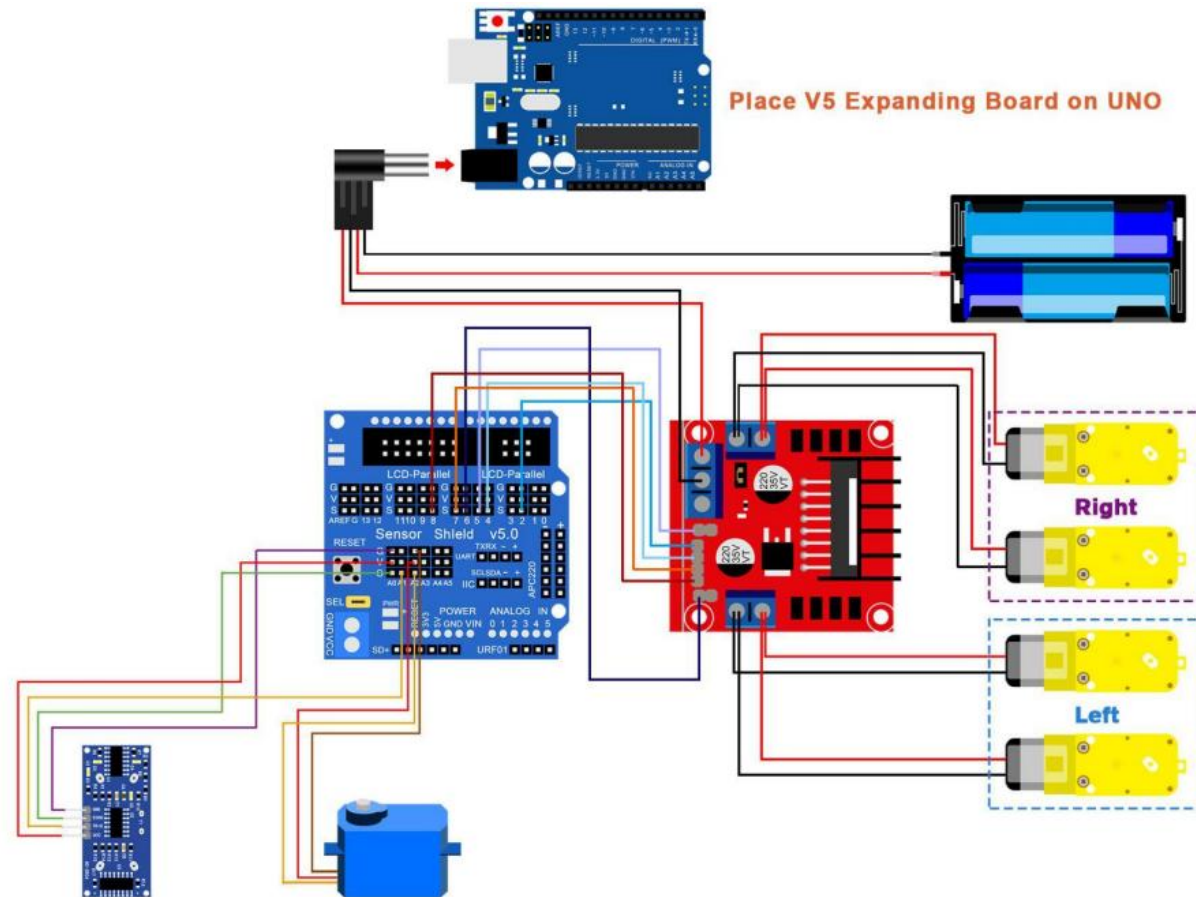
## Lesson 6 Follow Car

### **About this lesson:**

In this lesson, we learn the use of ultrasonic sensors and then use ultrasonic sensors to detect distances to achieve robots to follow his master.

### **Wiring diagram**

# LROBRUYA







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## **Attention**

After connecting, please open the the program and load up the code - Lesson\_6\_Follow\_Car onto your Arduino board.

Before you can run this, make sure that you have installed the < Servo> library or re-install it, if necessary. Otherwise, your code won't work.

## **Result**

After downloading the program and observing the distance information printed by the serial port window, unplug the USB data cable and turn on the power switch of the robot. you can move your hand close to the front of the ultrasonic sensor.

When the robot is less than 10 cm away from your hand, he will stop. Move your hand straight forward. When the robot is more than 20cm away from your hand, the robot will approach your hand.

# LROB RUYA

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## Lesson 7 IR Receiver Module

### About this lesson:

Using an IR Remote is a great way to have wireless control of your project. Infrared remotes are simple and easy to use. In this tutorial we will be connecting the IR receiver to the UNO, and then use a Library that was designed for this particular sensor.



### Introduction

IR is widely used in remote control. With this IR receiver, Arduino project is able to receive command from any IR remoter controller if you have the right decoder. Well, it will be also easy to make your own IR controller using IR transmitter.

There are 3 connections to the IR Receiver.

The connections are: Signal, Voltage and Ground.

# LROBROYA

The “-” is the Ground, “S” is signal, and middle pin is Voltage 5V.

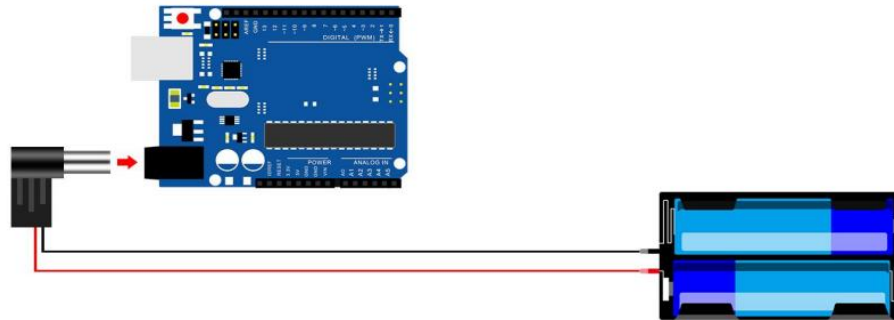
**Remote control code:**



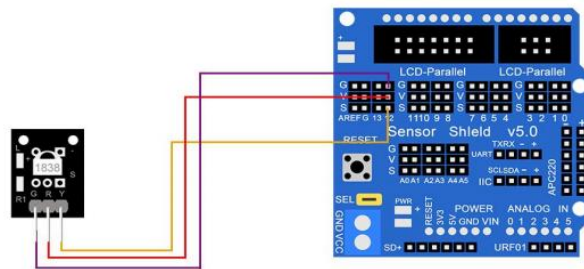
① FFA25D	② FF629D	③ FFE21D
④ FF22DD	⑤ FF02FD	⑥ FFC23D
⑦ FFE01F	⑧ FFA857	⑨ FF906F
* FF6897	0 FF9867	# FFB04F
⬅ FF10EF	⬆ FF18E7	➡ FF5AA5
	OK FF38C7	
	⬇ FF4AB5	

# LROBROYA

## Wiring diagram



Place V5 Expanding Board on UNO





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## Attention

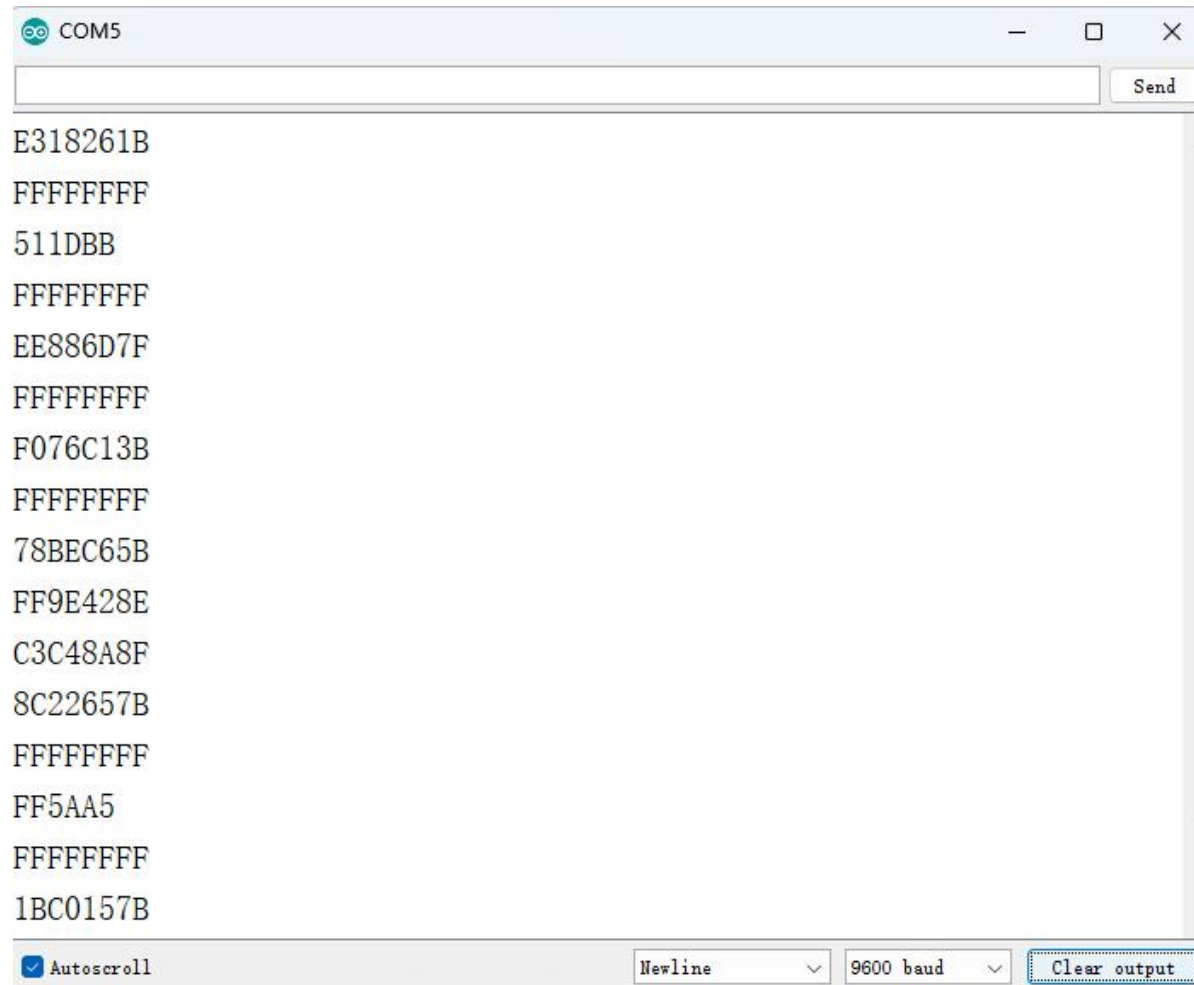
After wiring, please open the program in the code folder- Lesson\_7\_IR\_Receiver\_Module and click UPLOAD to upload the program.

Before you can run this, make sure that you have installed the < IRremote > library or re-install it, if necessary. Otherwise, your code won't work.

## Result

In this lesson, we need to use a IR remote control which has 17 functional key and its launching distance is 8 meters at most, proper to control various devices indoors. This project is actually to decode remote control signal. After connection and uploading codes, aim at IR receiving module and press the key, finally you can see corresponding codes. If you press the key too long, it will show messy codes easily as shown in bellow figure.

# LROB RUYA



```
COM5  
E318261B  
FFFFFFFF  
511DBB  
FFFFFFFF  
EE886D7F  
FFFFFFFF  
F076C13B  
FFFFFFFF  
78BEC65B  
FF9E428E  
C3C48A8F  
8C22657B  
FFFFFFFF  
FF5AA5  
FFFFFFFF  
1BC0157B
```

☒ Autoscroll    Newline    9600 baud    Clear output



---

## Lesson 8 IR Remote Control Car






### **About this lesson:**

This lesson ,regarding Arduino microcontroller as main control, uses IR module to receive IR remote signal and send the signal to Arduino. Arduino will analyses the signal and then control the driver motor and the motion of the car with IR remote control.

### **How to control the Robot Car**

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Key on IR remote control					
Robot status	Go forward	Go backward	Turn left	Turn right	Stop



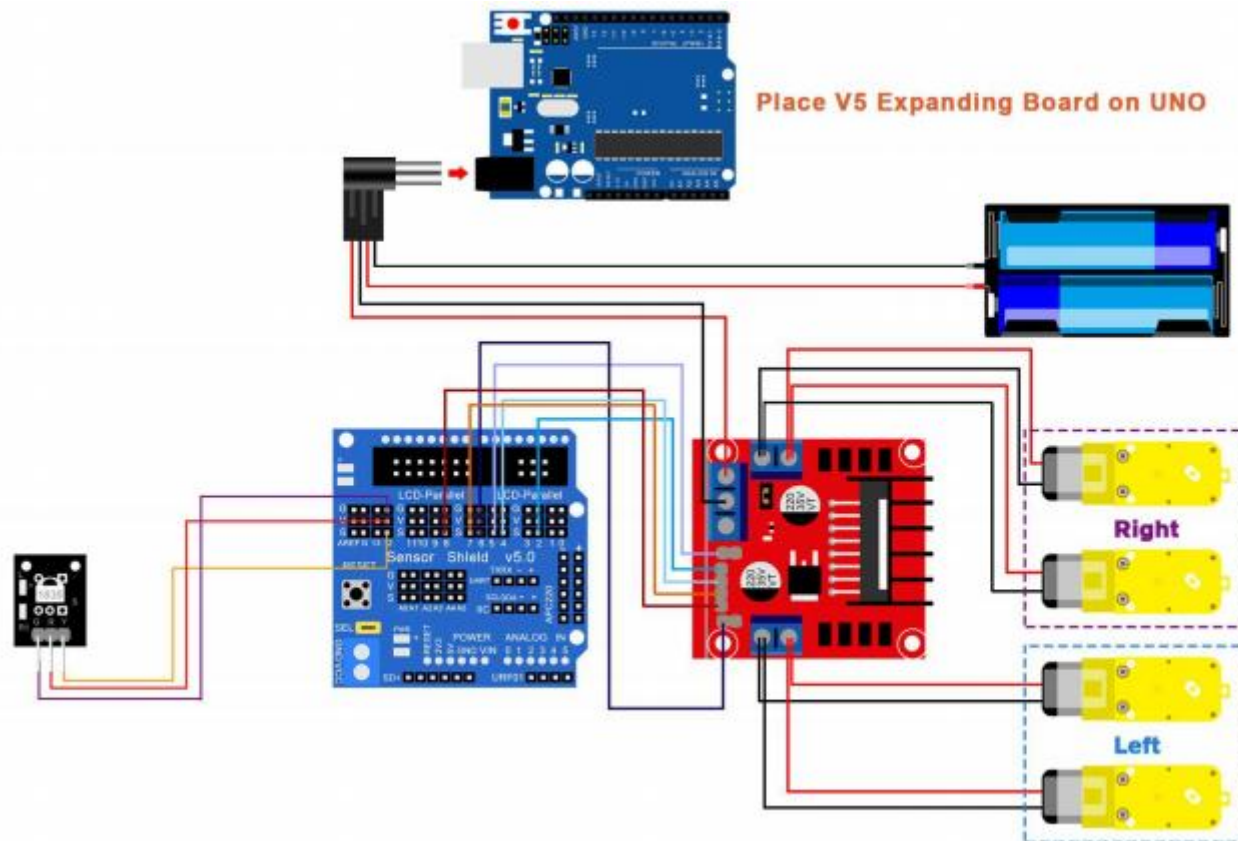
# LROBROYA



① FFA25D	② FF629D	③ FFE21D
④ FF22DD	⑤ FF02FD	⑥ FFC23D
⑦ FFE01F	⑧ FFA857	⑨ FF906F
* FF6897	0 FF9867	# FFB04F
	▲ FF18E7	
◀ FF10EF	OK FF38C7	▶ FF5AA5
	▼ FF4AB5	

# LROBRUYA

## Wiring diagram





### **Attention**

After wiring, please open the program in the code folder- Lesson\_8\_IR\_Remote\_Control\_Car and click UPLOAD to upload the program.

Before you can run this, make sure that you have installed the < IRremote > library or re-install it, if necessary. Otherwise, your code won't work.

### **Result**

Press the corresponding button and the car will run according to the corresponding function.

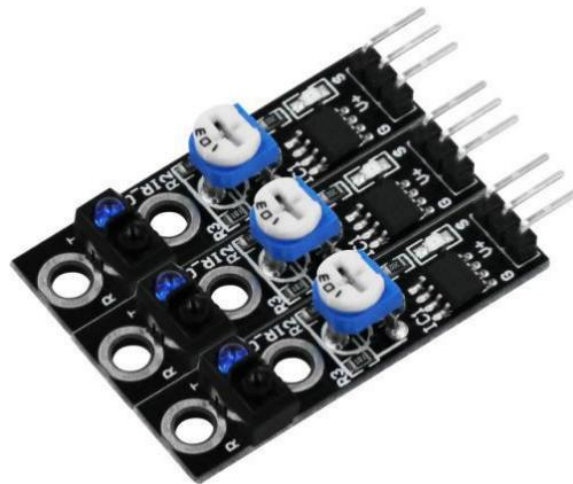
# LROBRUYA

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## Lesson 9 Line-Tracking sensor

### About this lesson:

In this lesson, you will learn how to use a Tracking Sensor. we will use an obstacle avoidance sensor module and an LED attached to pin of the Arduino Uno board to build a simple circuit to make a tracking light.





## **Component Introduction**

This Line Tracking Sensor can detect white lines in black and black lines in white. The single line-tracking signal provides a stable output signal TTL for a more accurate and more stable line. Multi-channel option can be easily achieved by installing required line-tracking robot sensors. The tracking sensor is actually an infrared sensor. The component used here is the TCRT5000 infrared tube. Its working principle is to use the different reflectivity of infrared light to the color, then convert the strength of the reflected signal into a current signal. During the process of detection, black is active at HIGH level, but white is active at LOW level. The detection height is 0-3 cm. By rotating the adjustable potentiometer on the sensor, it can adjust the detection sensitivity of the sensor.

## **Specification:**

Power Supply: +5V Operating Current: <10mA

Operating Temperature Range: 0°C ~ + 50 °C



---

Output Interface: 3-wire interface (1 - signal, 2 - power, 3 - power supply negative) Output Level: TTL level

### **How to use the Line-Tracking sensor**

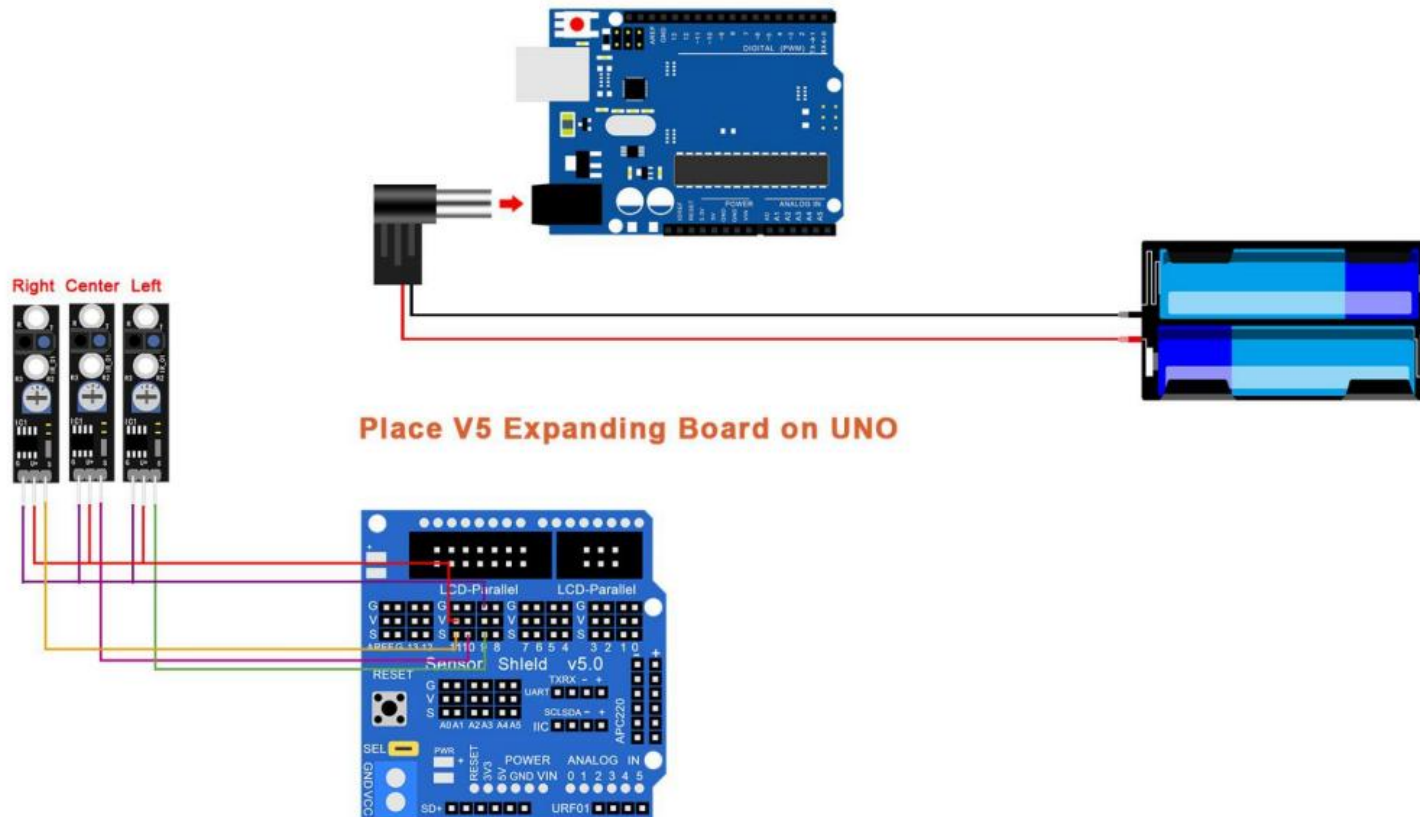
we read the signal level of Line-Tracking sensor to judge whether detect black or not.

When detects black, sensor's signal pin outputs HIGH (display 1).The red indicator light will turn off ; otherwise, output LOW (display 0),the red indicator light will turn on.

Show the result on the serial monitor.

### **Wiring diagram**

# LROBRUYA



# LROBROYA

## Result

After uploading the code, click the button in the upper right corner to open the serial monitor to view the measured distance



The screenshot shows the Arduino IDE interface. The top menu bar includes File, Edit, Sketch, Tools, and Help. Below the menu bar is a toolbar with icons for saving, uploading, and opening the serial monitor. The serial monitor icon, located in the upper right corner of the toolbar, is highlighted with a red square and a red arrow. The main text area displays the code for a sketch named "Lesson\_8\_Infrared\_Obstacle\_Avoidance\_Sensor". The code includes a setup function that initializes the serial port at 9600 baud, sets the left and right IR sensors to 0, and configures pins 9 and 10 as inputs. The loop function reads the digital values from pins 9 and 10, prints them to the serial monitor, and delays for 500ms. The status bar at the bottom indicates "Done uploading." and provides memory usage statistics: "Sketch uses 2392 bytes (7%) of program storage space. Maximum is 32256 bytes. Global variables use 232 bytes (11%) of dynamic memory, leaving 1816 bytes for local variables." The bottom status bar also shows "11" and "Arduino/Genuino Uno en COM8".

```
File Edit Sketch Tools Help

Lesson_8_Infrared_Obstacle_Avoidance_Sensor
void setup() {
  Serial.begin(9600);
  left_IR_Sensor = 0;
  right_IR_Sensor = 0;
  pinMode(9, INPUT);
  pinMode(10, INPUT);
}

void loop() {
  left_IR_Sensor = digitalRead(9);
  right_IR_Sensor = digitalRead(10);
  Serial.print("left_light_value = ");
  Serial.println(left_IR_Sensor);
  Serial.print("right_light_value = ");
  Serial.println(right_IR_Sensor);
  delay(500);
}

Done uploading.
Sketch uses 2392 bytes (7%) of program storage space. Maximum is 32256 bytes.
Global variables use 232 bytes (11%) of dynamic memory, leaving 1816 bytes for local variables.

11 Arduino/Genuino Uno en COM8
```



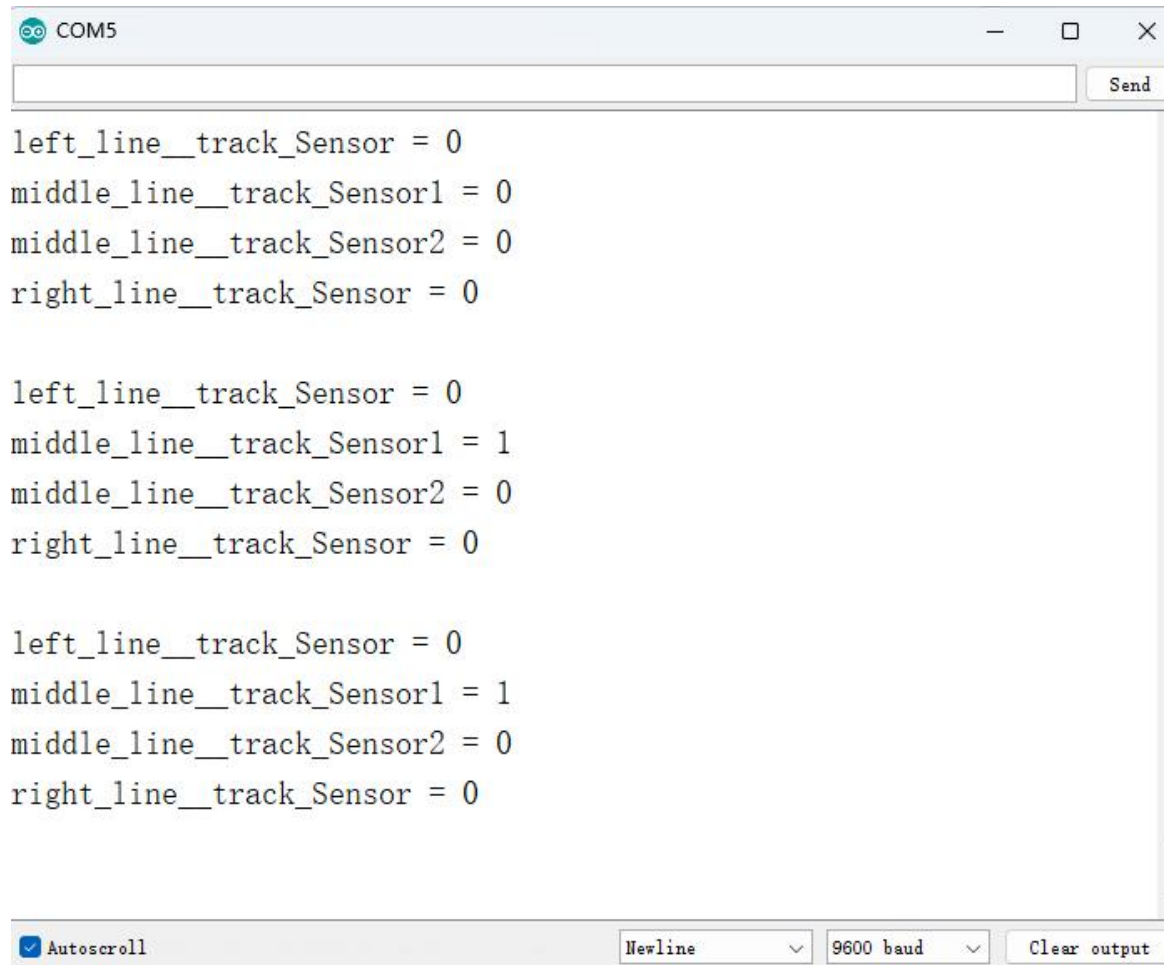


---

Then you can see the data as blow:

When the line patrol sensor detects black, the serial monitor will receive "1", and the digital port will receive a high level, otherwise the serial monitor will receive "0", and the digital port will receive a low level. If the three sensors on the left and right and the middle detect black at the same time, the serial monitor receives three "1"s. If the left sensor detects black and the other two sensors detect non-black, the signals received by the serial monitor are "1" "0" "0".

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The screenshot shows a serial monitor window titled "COM5". It has a text input field at the top with a "Send" button. The main area displays three identical blocks of sensor data, each separated by a blank line. The data for each block is as follows:

```
left_line__track_Sensor = 0
middle_line__track_Sensor1 = 0
middle_line__track_Sensor2 = 0
right_line__track_Sensor = 0

left_line__track_Sensor = 0
middle_line__track_Sensor1 = 1
middle_line__track_Sensor2 = 0
right_line__track_Sensor = 0

left_line__track_Sensor = 0
middle_line__track_Sensor1 = 1
middle_line__track_Sensor2 = 0
right_line__track_Sensor = 0
```

At the bottom of the window, there is a status bar with the following controls:

- ☒ Autoscroll
- Newline (dropdown menu)
- 9600 baud (dropdown menu)
- Clear output (button)



---

## Lesson 10 Line-Tracking Car

### About this lesson:

In this lesson, we will learn a simple and automatic line tracking system of a car.

**Step 1:** Prepare a black track on white ground. (the width of the black track is more than 20mm and less than 30mm).

Please note, the bend angle of the track can't be larger than 90 degree. If the angle is too large, the car will move out of the track.

**Step 2:** Adjust the sensitivity of tracking sensor modules.

Turn on and hold the car to adjust the potentiometer on the tracking sensor with Phillips screwdriver until you get the best sensitivity status: the signal indicate LED light will turn on when sensor is above white ground, and the signal LED will turn off when the sensor is above black track.

Signal Indicate LED ON: White Ground



---

Signal Indicate LED OFF: Black Track

**Step 3:** Turn on the car and put the car over the black track, then the car will move along the black track.

If the car can't move, please check the following:

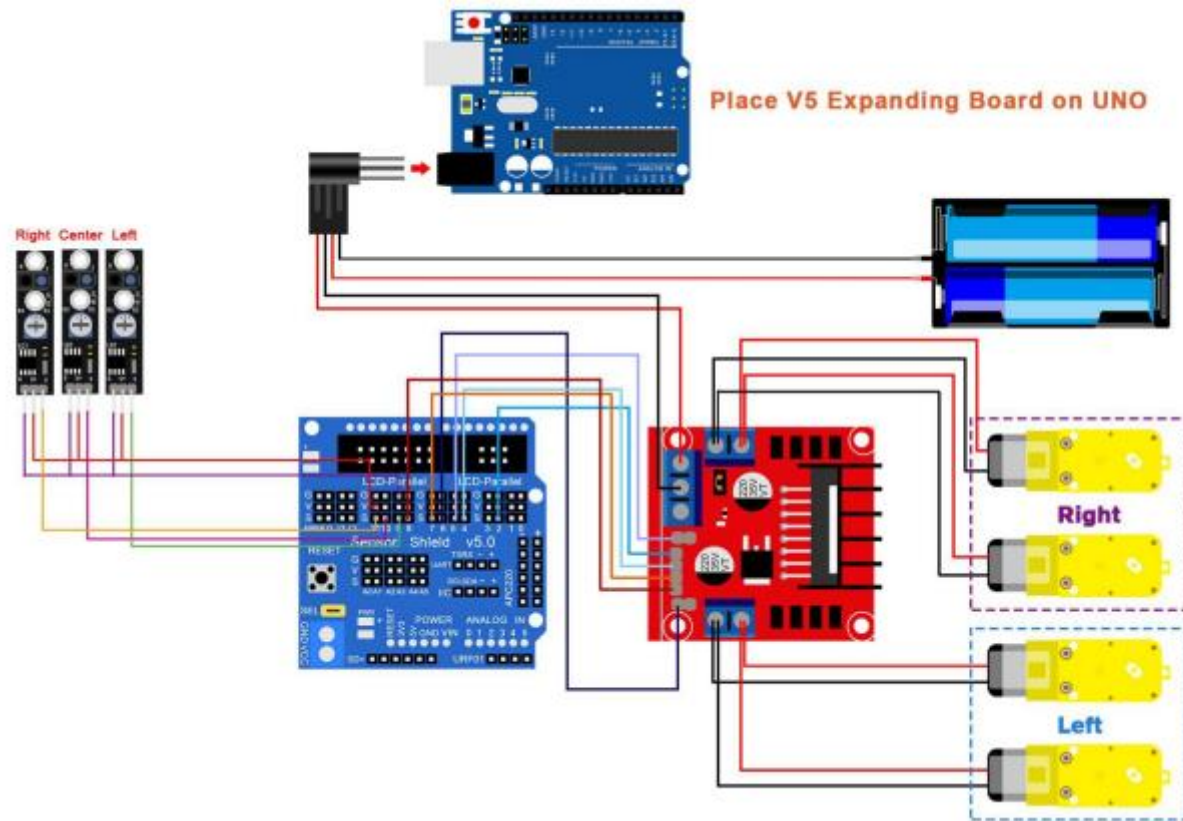
If adjusted well the sensibility of the tracking sensor

### **Car tracking flow chart**

The car entered the tracking mode, namely began constantly scanning and detector connected to the I/O port of the SCM, once detected a signal of a I/O port, enter judgment processing procedures, to determine which one of 3 detectors detect the black line.

### **Wiring diagram**

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### **Attention**

In order to make the car better implement the line following function, the width of the black line should be greater than the parallel width of the three line following sensors.

### **Result**

Turn the POWER switch ON. The robot car will move forward along the black track.

## **Lesson 11 Bluetooth Module**

### **About this lesson:**

In this lesson, we will learn how to use the Bluetooth Module.

### **Introduction:**

The HC05 is a Serial port Bluetooth module which having fully qualified Bluetooth V2.0+EDR (Enhanced Data Rate)



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3Mbps Modulation with complete 2.4GHz radio transceiver and baseband. It uses CSR Blue core 04-External single chip Bluetooth system with CMOS technology and with AFH (Adaptive Frequency Hopping Feature).

We use the serial port communication function of the Bluetooth module, use the app to control the Bluetooth connection of the mobile phone and the HC-06 Bluetooth module, and then the mobile phone app sends data, and the HC-06 Bluetooth module transmits the received data to the arduino uno through the serial port. The default communication baud rate of the HC-05 Bluetooth module is 9600.

### **The HC-06 Bluetooth module to LONTEN UNO R3:**

VCC>>>> +

GND>>>> -

TXD>>>>RX

RXD>>>>TX

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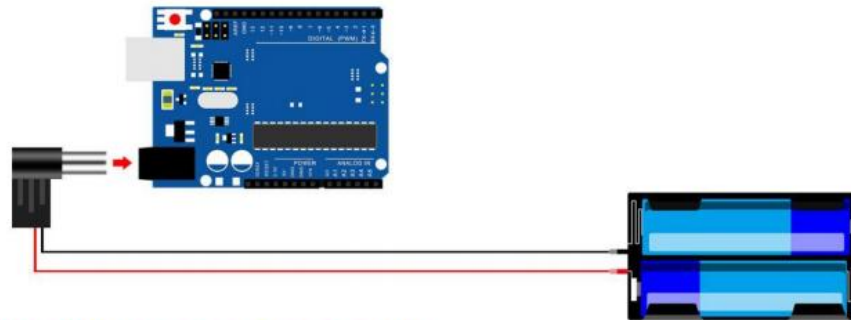


**Wiring diagram**

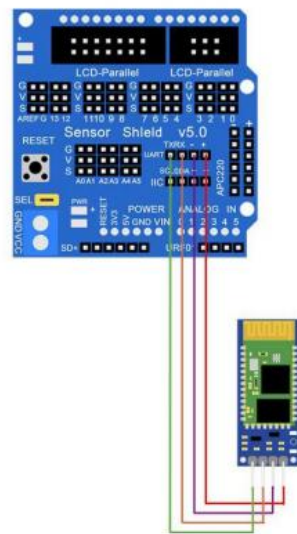


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Place V5 Expanding Board on UNO





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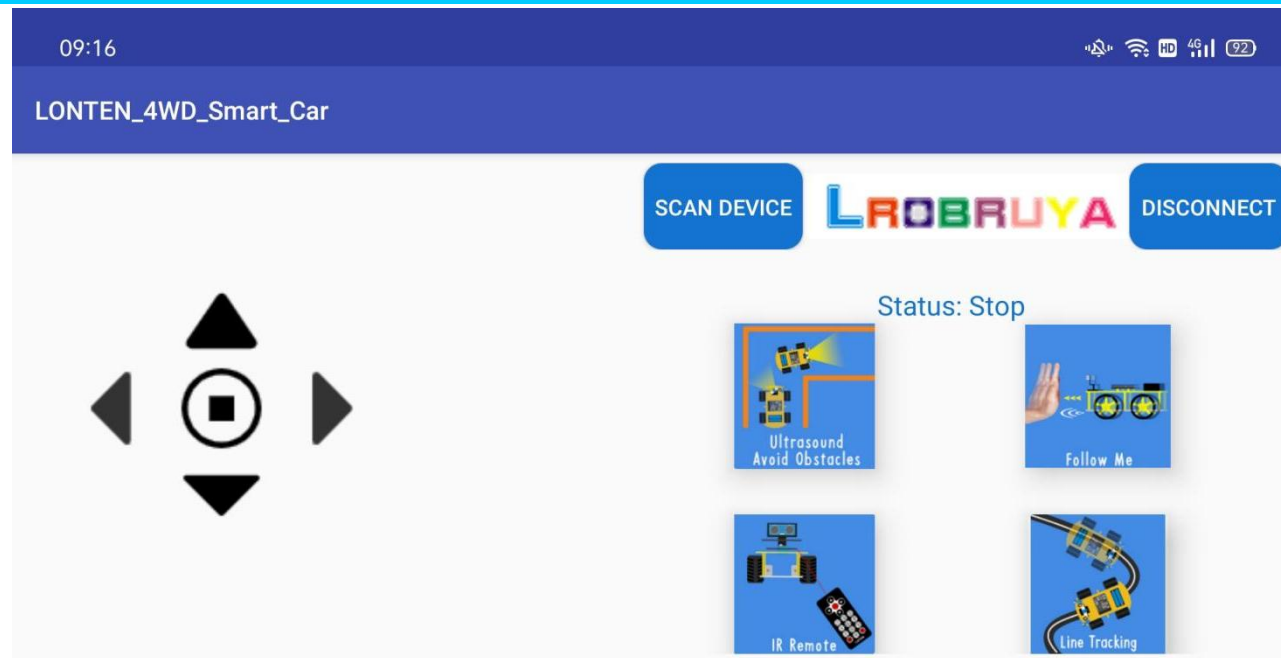
### **Attention**

The bluetooth module should be pulled out before you upload the program every time, or it will be failed to upload the program. When uploading the code, CANNOT connect the Bluetooth module first; otherwise uploading fails! You are supposed to upload the code to control board, then connect the Bluetooth module.

### **Instructions for the use of app**

Firstly, download the “**LONTEN\_4WD\_Smart\_Car.apk**” file from the folder to your mobile phone and install it into an application software.

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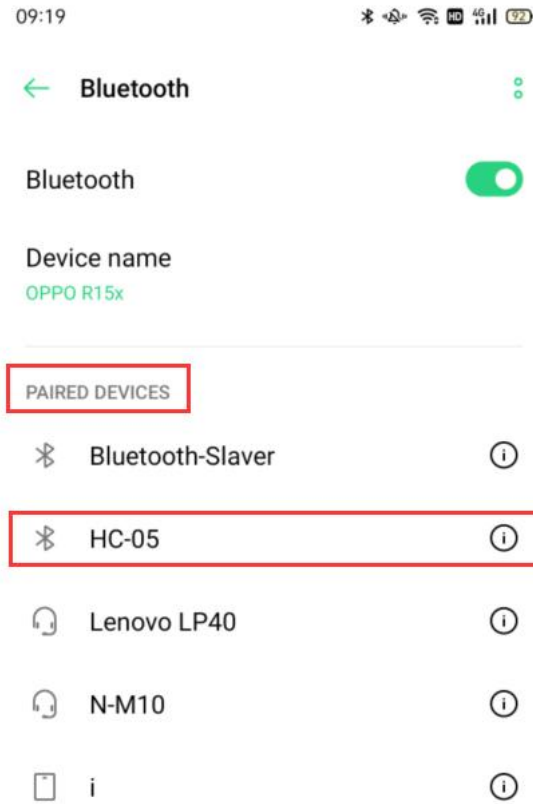
Then make sure the Bluetooth module is connected. Pair your phone with HC-05. for doing this go to **Settings->Bluetooth->Scan device->select HC-05** and pair it. Pass code to pair is '1234'.



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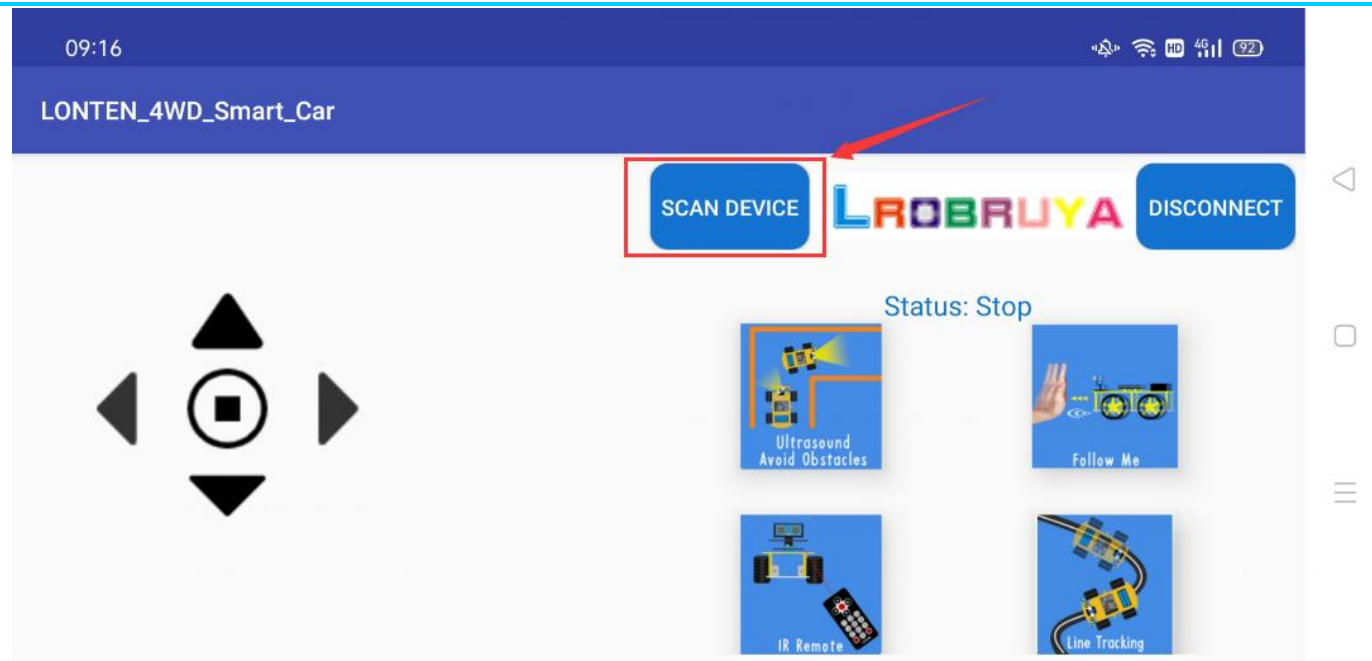
Open Bluetooth Terminal software, go to options and select 'connect a device - secure' option. It it ask for pass code enter 1234.If your phone is connected to the Bluetooth module, you will see a usable device called HC-05 on the PAIRED DEVICES(As shown below).If the HC-05 does not appear on the PAIRED DEVICES, reoperate the above steps.

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After the above steps are complete, we open the **LONTEN\_4WD\_Smart\_Car** app.

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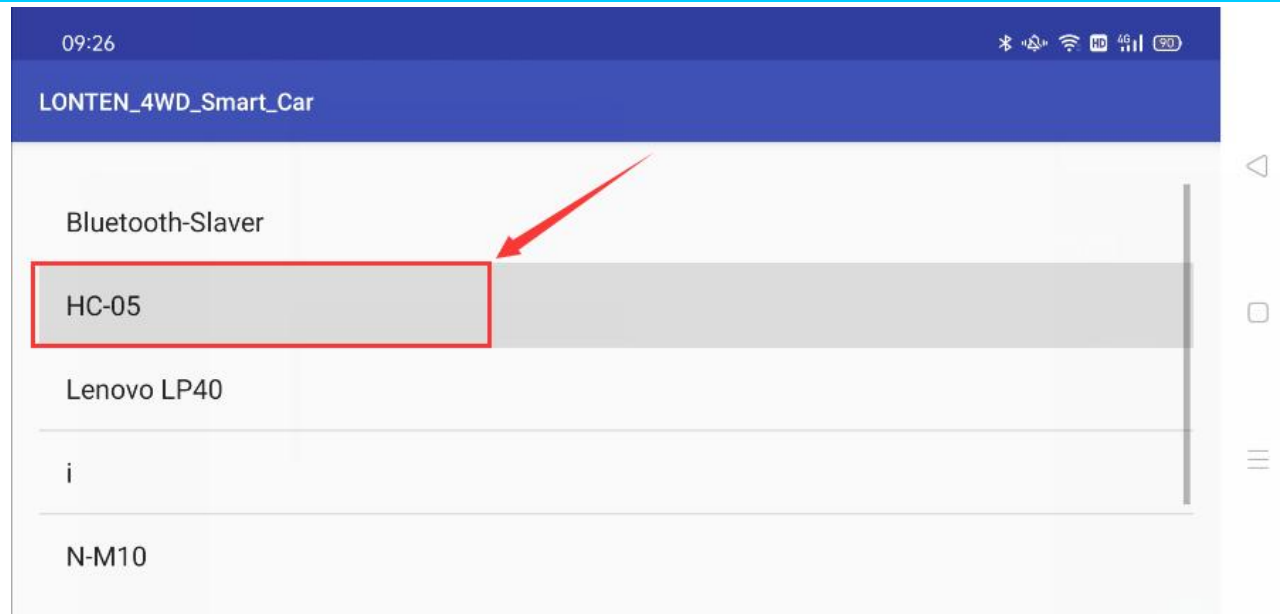
Click the Connect Bluetooth icon button"SCAN DEVICE" . the HC-05 will appear in our scan results.Select HC-05.

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After selecting the hc-05 device, click button will to connect .

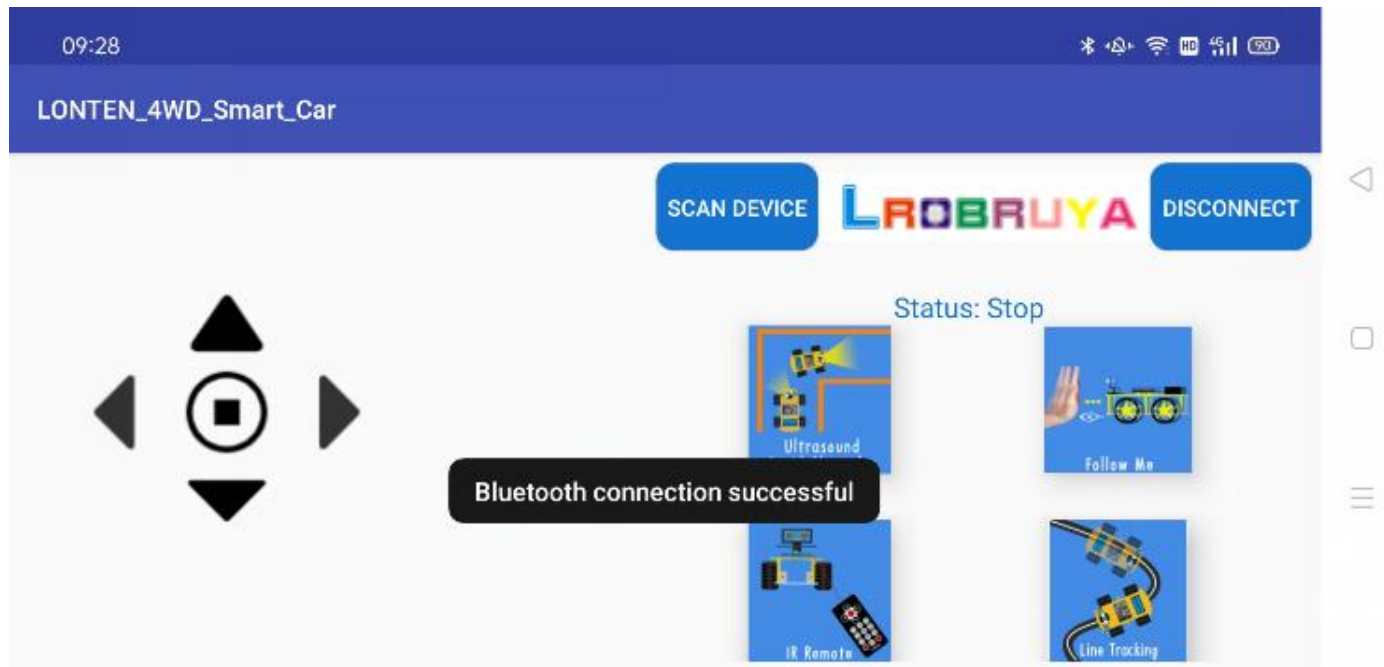
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After click on the button .wait 2 seconds,If the connection is successful, "Bluetooth connection successful" will be displayed.



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(Note: When the Bluetooth module is not successfully connected, the red LED light will continue to flash. When the connection is successful, the red LED light will be remain on.)

If there is a warning in the interface, it means that Bluetooth is not turned on normally or the selected device is wrong.

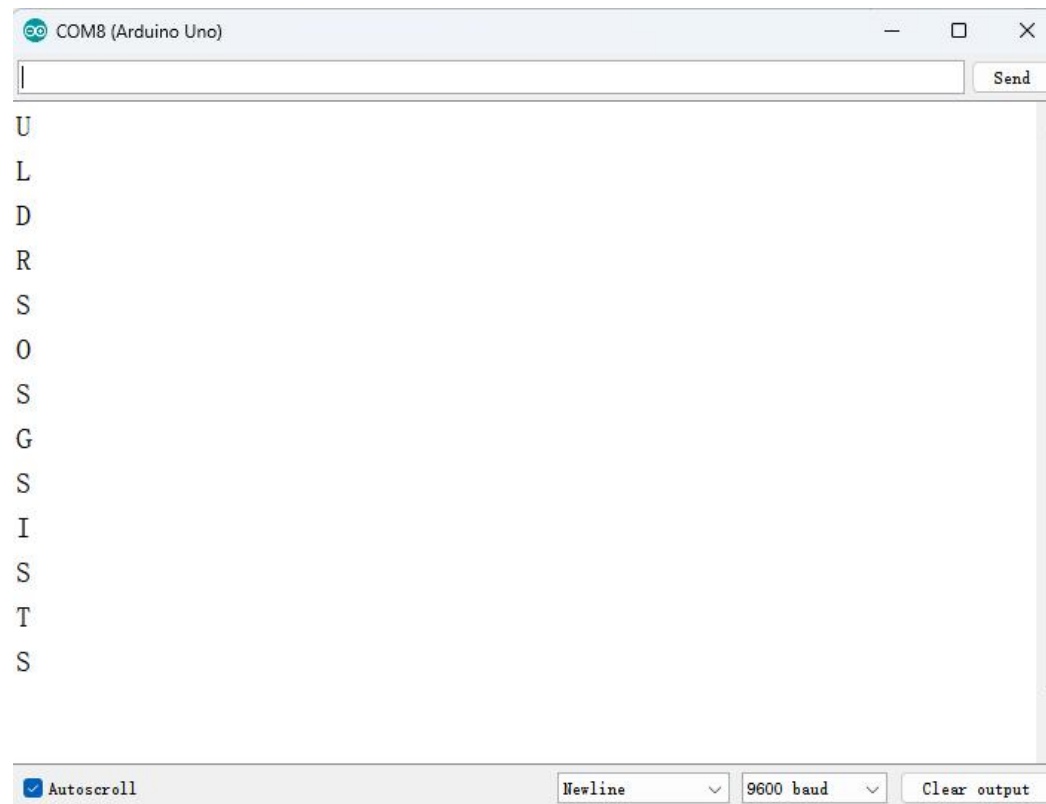
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Follow the steps above to reconnect. After uploading the code, click the button in the upper right corner to open the serial monitor to view the measured distance.



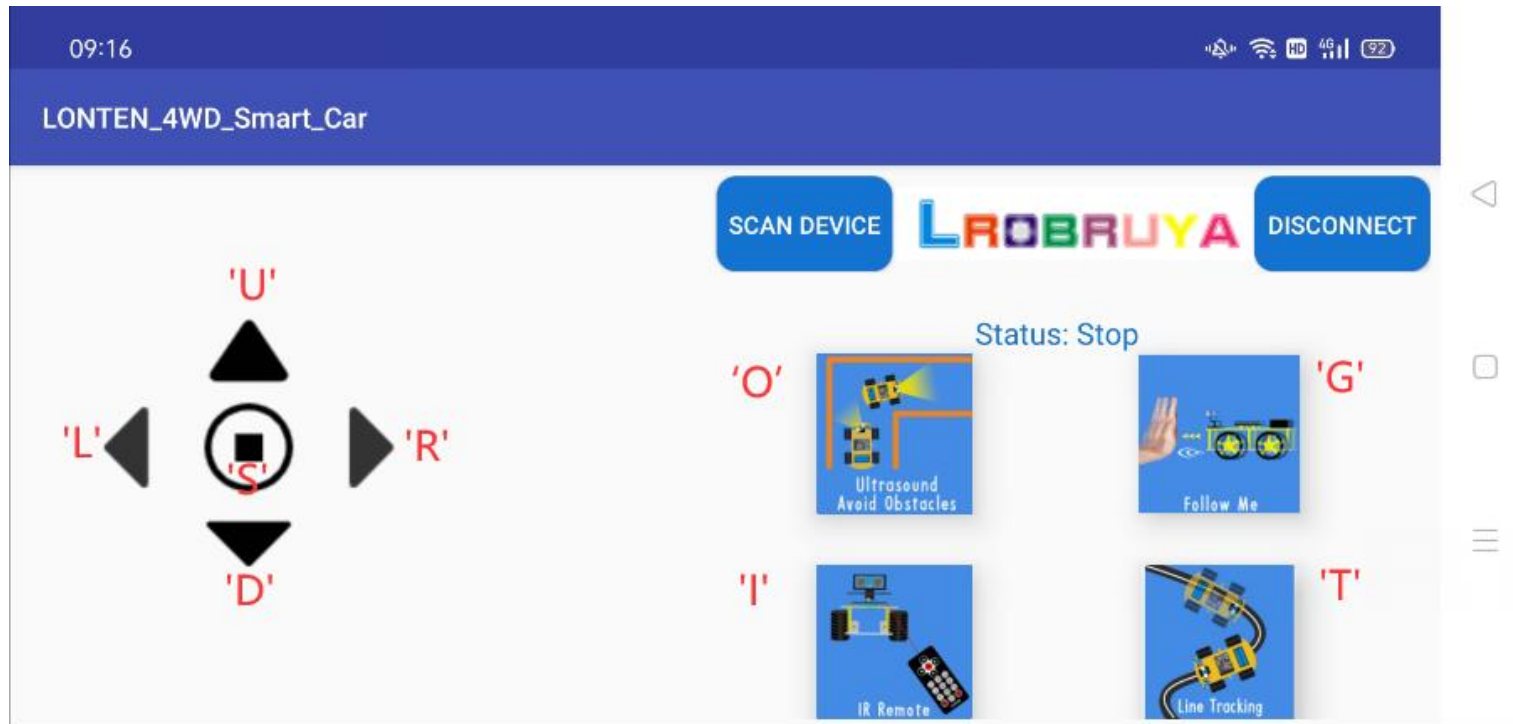
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Then you can see the data as blow:



For example, If the Line Tracking mode button is pressed,

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the mobile phone Bluetooth sends the character "T" to the Robot car Bluetooth module.

Set the baud rate of the communication between the Bluetooth module and the mobile phone's Bluetooth to 9600.

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## Lesson 12 Bluetooth Multifunctional Robot Car

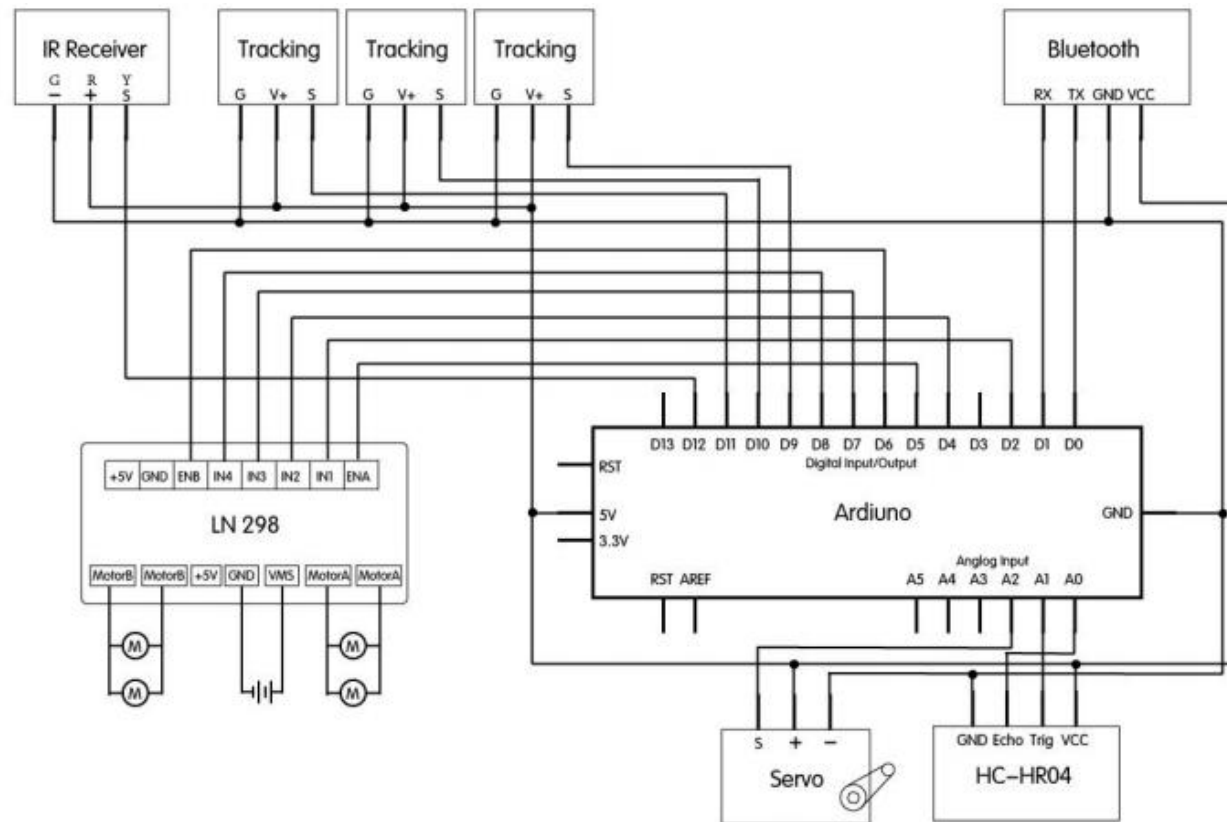
### About this lesson:

In this project, we will put five functions, namely line tracking, obstacle avoidance, following, Bluetooth and IR remote control, together into one to realize the working mode of the car.



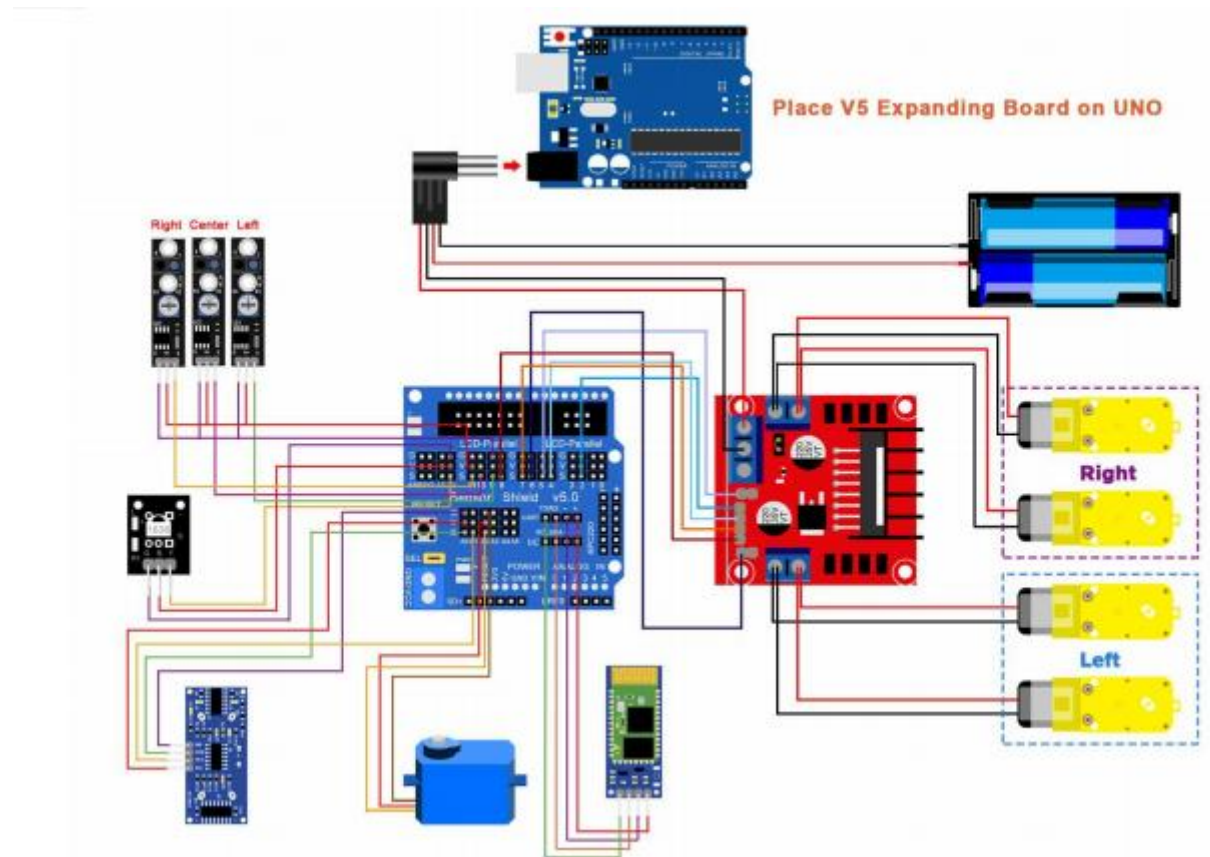
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## Schematic



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## Wiring diagram





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## Attention

The bluetooth module should be pulled out before you upload the program every time, or it will be failed to upload the program. When uploading the code, CANNOT connect the Bluetooth module first; otherwise uploading fails! You are supposed to upload the code to control board, then connect the Bluetooth module.

## How to use the app to control the robot car

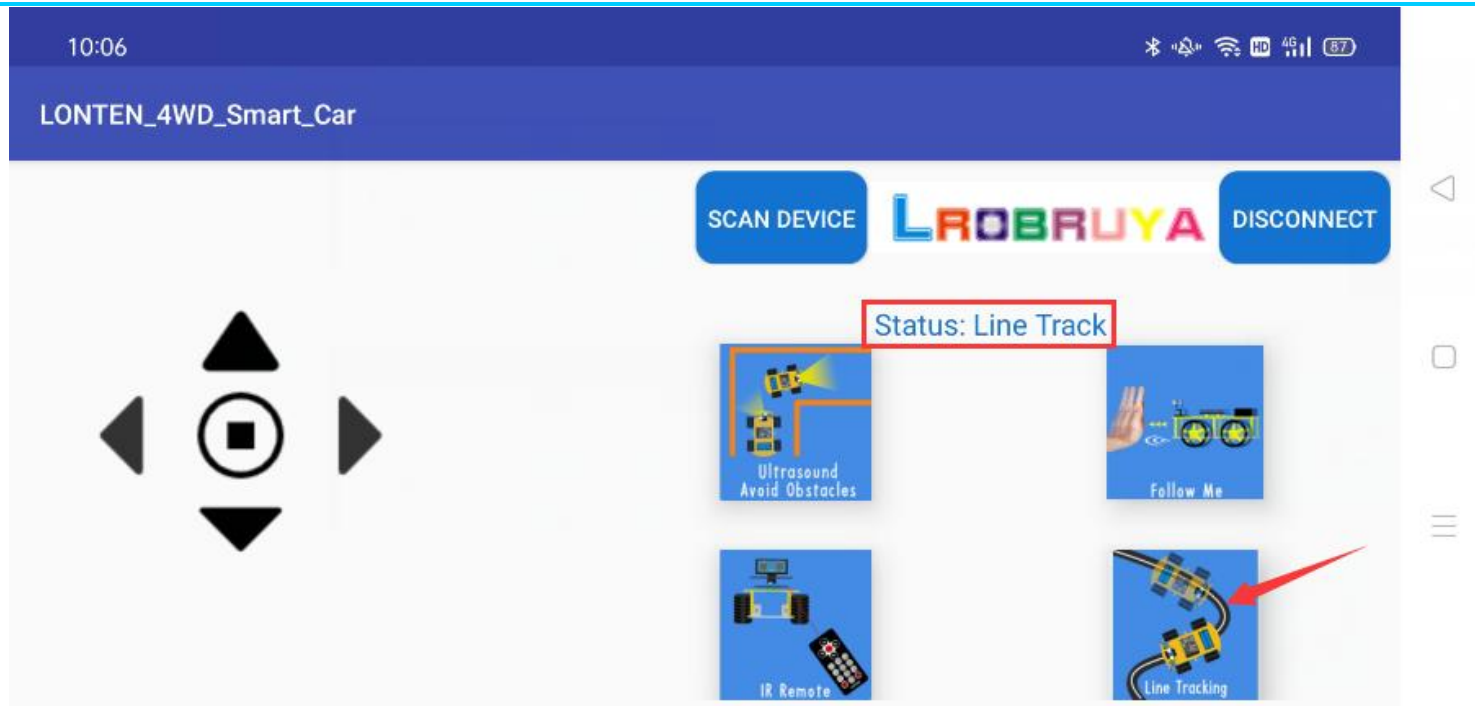
After completing the program upload, plug in the Bluetooth module again, and then open the app software to complete the connection of the Bluetooth device (refer to Lesson 11 Bluetooth Module for specific steps).

The interface after the app software and Bluetooth module are successfully connected is as follows.

For example, if you want to control the car to enter the Line tracking mode, you click the line patrol function button, and then the status bar in the app interface will display: **Status: Line Track**. After the robot car receives the signal, it will enter the line patrol state. At this time, you need to provide a black track for the robot car.



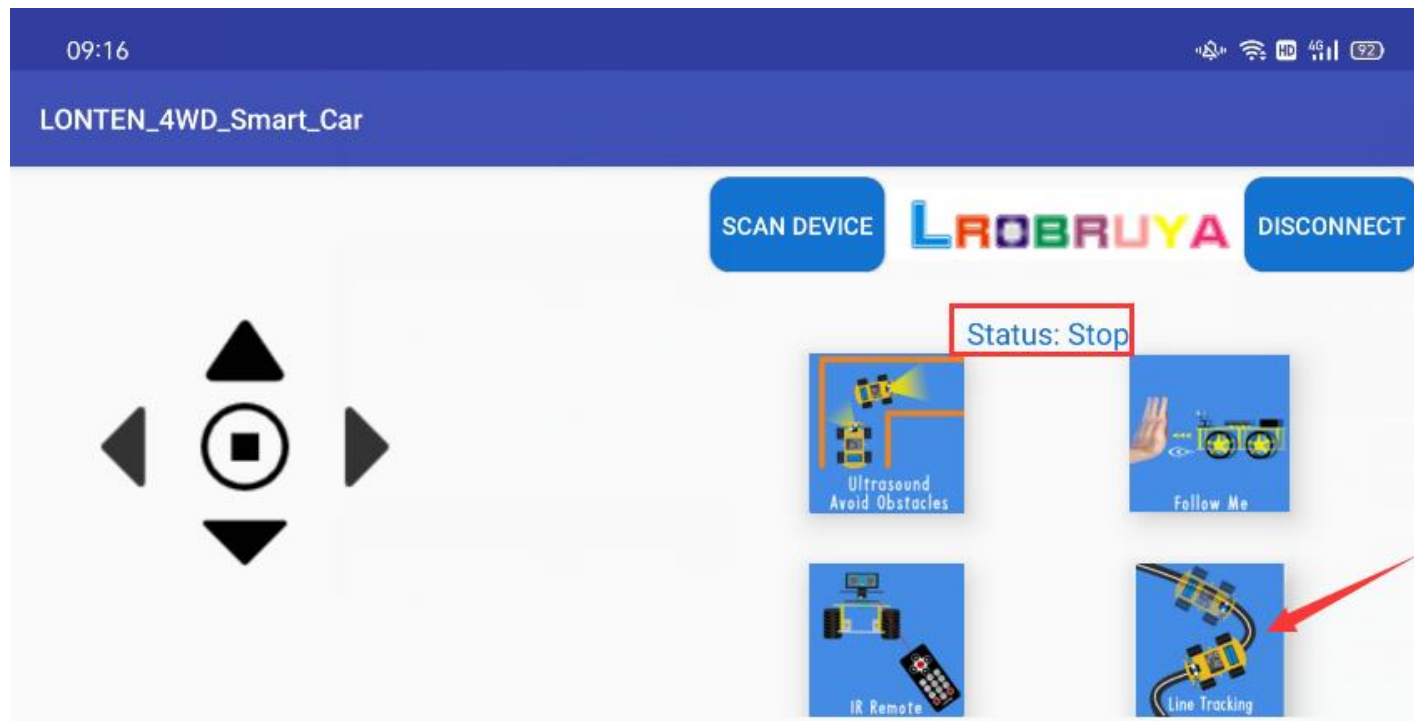
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Note: If you want to switch to other modes, you need to click the button again, and then click the function button you want to switch. It means that you need to be in status: stop to switch to other modes.

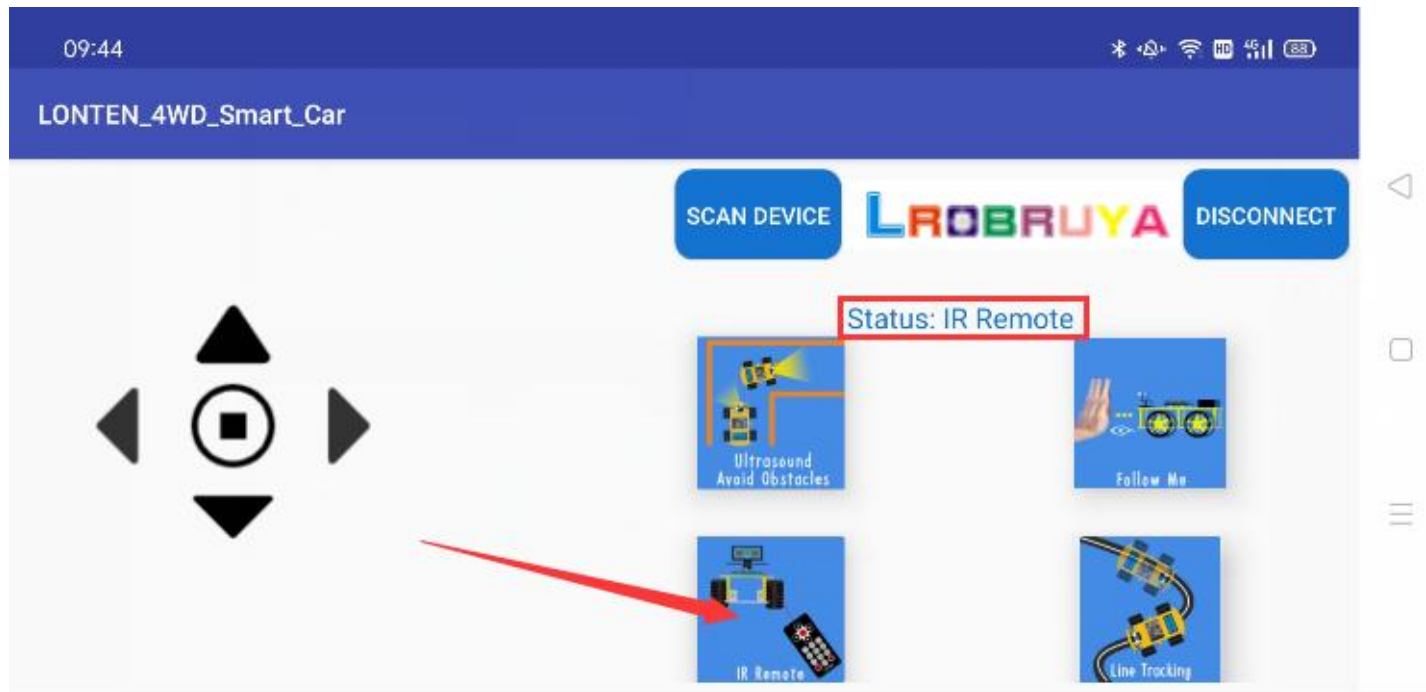
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Step 1:



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Step 2:



The app can control the robot car to complete all functions, and can switch freely. The functions you can choose are Ultrasonic Obstacle Avoidance Mode, Follow Control Mode, IR Remote Control Mode, Line Tracking Mode.