

3D MODELING WORKSHOP

OVERVIEW

During this workshop you will learn how to use Tinkercad to create & customize 3D models.

Tinkercad is an easy-to-use tool for creating digital designs that are ready to be 3D printed into physical objects.

And at the end you will have a task to make an object that you can print later on one of our 3D printers

PREPARATIONS

- We will be using browser based software so you don't have to install anything!
- All you need to do is to go to <https://tinkercad.com/> & register for a free account.
- Later on we will also be using Google Docs drawing tool (<https://docs.google.com/drawings>), so if you don't have a Google account this is a good time to go and get one.

MAIN FLOW

1. LEARN THE LAYOUT

Log in to your Tinkercad account, click on “Create new design” button & let's get started!

Take some time to know your way around Tinkercads layout. Basically all the tools you will need are located in the right menu bar.

2. CHECK YOUR GRID

Near the bottom right corner of the workplane you have “*Edit grid*” options & “*Snap grid*” value.

Leave the value as it is, but we need to adjust the grid size to those of the 3D printer bed. It will be easier for you to understand the dimensions you are working in.

3. LEARN THE BASICS.

Drag the red Box to the workplane (close to middle is usually best).

You can drag the box to any place on the workplane. Click & drag to move it in x & y axis, pull the black arrowhead on the top plane to move it in the “z” axis.

Click on the Box and play with the visible controls.

Black dots on the base of the box allow you to scale the box in “y” or “x” axis, and the white dot on the top plane lets you scale it in the “z” axis.

You can also scale the box freely in x&y axis while pulling one of four white dots on the base plane. Use uniform scaling of the objects just by holding shift while pulling any of the control dots.

Notice that you can also rotate the objects in any direction. Holding Shift button while doing so will snap the rotation every 45 degrees.

4. WORKING WITH DIMENSIONS

First of all delete the object you were working on before.

Ok, now get *Cylinder* on the plane. Now from the right menu bar choose the *Ruler* and put it on the workplane.

Notice that when you click on the cylinder now, when the ruler is also on the workplane, you can see the dimensions of the object. You can click on them to enter values.

Change the dimensions to:

- height: 15mm
- diameter: 25mm.

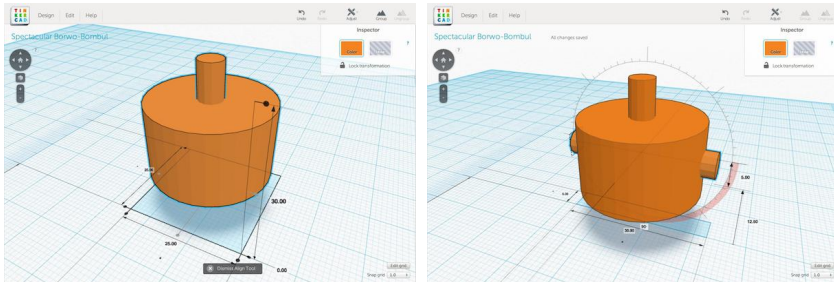
Apart from the object dimensions, you can also change the distance from the workplane & distance from the ruler axis.

5. 3D MODELLING: THE BASICS

Ok, so we have a cylinder with the dimensions set in the previous step. Now lets get one more cylinder to the workplane.

1. Set the cylinder dimensions to
 - height: 30mm
 - diameter: 5mm.

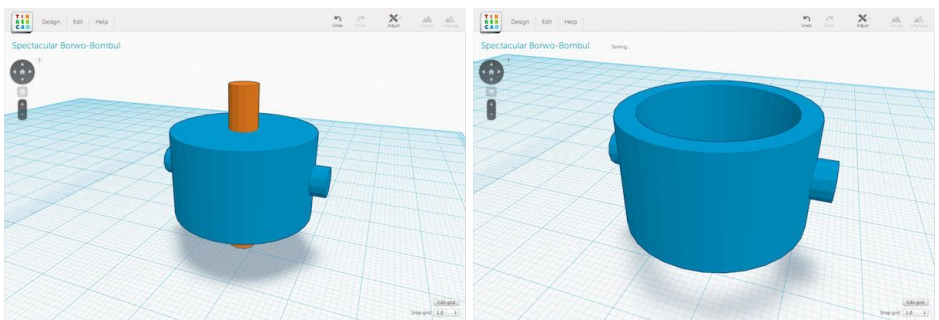
2. Select both objects either by dragging a window over them, or by shift clicking both of them. Go to “Adjust” in the top bar on the right, and choose “Align” option.
3. Center align the cylinders in all three dimensions.
4. Copy & paste the thin cylinder and again select all object and center align them in all dimensions. Rotate one of the thin cylinders 90 degrees.



5. Select the horizontal thin cylinder and the big one and group* them together using either keyboard shortcut or command from the top menu bar.

Group command in Tinkercad “welds” the objects together, you can unweld them simply by ungrouping them.

6. Change the color of the grouped object.
7. Change the diameter of the thin vertical to 20mm. Realign the objects.
8. Click on the thin cylinder and set it to “Hole” in the inspector.
9. Group all objects together and congrats you have your first 3D model ready!



6. USE THE BASIC MODELING TECHNIQUES YOU LEARNED TO CREATE A GAMING DICE

Use the predefined dice model from the right menu bar & the numbers also found there. Feel free to experiment.

ADDITIONAL TASKS

Do you feel good with your skills? If so let's get to the next step if not keep on experimenting or ask us for some help.

UTILIZE YOUR 3D MODELLING SKILLS TO MAKE SOMETHING USEFUL

We dare you to design and model a bottle opener and since the material we will be printing with is not so strong, we will be using a coin in the design, so it will be more sturdy and open the bottle instead of breaking ;)

1.1. USING GOOGLE DOCS DRAWING TOOL TO MAKE CUSTOM SHAPES & TEXT.

Go to <https://docs.google.com/drawings> to start a new drawing.

Here you can create custom shapes with curve tools or use some predefined shapes that are still much more than the ones in Tinkercad or even create custom text!

When you have your shape or text ready, go to “File” -> “Download as” -> “.svg” You can now import this file to Tinkercad using the “Import” command at the top of the right menu bar.

1.2. TIPS FOR DESIGNING THE BOTTLE OPENER.

You can visit <http://www.thingiverse.com/> and search for some bottle openers to have some inspiration of what you can do. If you don't have the patience you can even download the opener you really like and personalize it.

You should know the dimensions of the coin you will be using in your design - you can use the web to find them or use our calliper to measure it.

Your design should not be bigger than x=60mm, y=60mm, z=30mm - printing takes some time and everyone would like their design to be printed :)

ADDITIONAL SOURCES

You want to tinker more in 3D modelling or Tinkercad did not satisfy you?

Here is a list of free 3D modelling software we created for you:

- Autodesk 123D - design: <http://apps.123dapp.com/design/>
- Sketchup - <http://www.sketchup.com/> (plugin needed for stl exports)
- Blender - <http://www.blender.org/>
- Rhino4Mac - <http://www.rhino3d.com/mac> (pre alpha version)
- OpenSCAD - <http://www.openscad.org/>

BUILD-A-BOT WORKSHOP

OVERVIEW

In this workshop you will learn how to assemble and program an arduino based robot that you can control with your laptop, teach to 'see' by using sensors, or use to battle other bots in the sumo ring.

PREPARATIONS

We will be using a piece of software called **Robotnik** that lets you program and control the Arduino robot. In order to run Robotnik on your laptop, you will first need to install Node.js. Please go to <http://nodejs.org/>, click *Install* and then follow the instructions.

Once you have installed Node.js, you can install Robotnik using npm. If you are on a Mac or Linux, just open a command prompt. If you are a Windows user, open 'Node.js command prompt' that was installed along with Node.js. Then you can installed Robotnik by typing:

```
npm install -g robotnik
```

Once the install is complete, connect the Arduino to your laptop using the USB cable:



Then you can start the program by typing:

robotnik

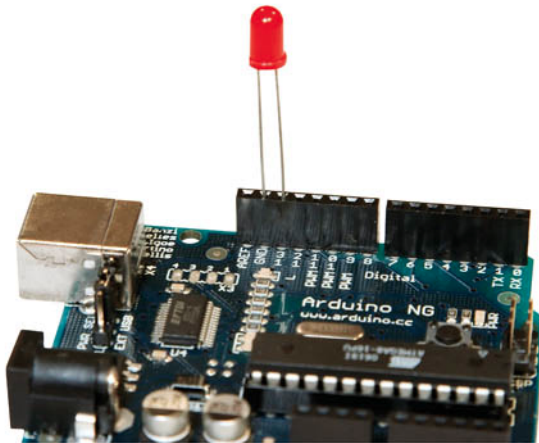
That's it! The program may instruct you to open a web browser to <http://localhost:8057/> if it couldn't do so for you automatically. You are now ready to begin the tutorial. Remember, if you run into any trouble, just ask one of the workshop assistants and we'll help you as much as you require!

MAIN FLOW

QUEST 1: MAKE A LED BLINK

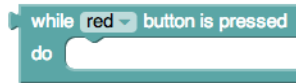
Robotnik is a programming system that works like Lego™ or puzzle pieces. On the left are available blocks and on the right is where you drag them to make your program. We're going to make a program that turns a LED on when you press a virtual button in Robotnik.

First, you'll need to plug a LED (any color) into the Arduino. The short leg goes into GND and the long leg goes into 13.



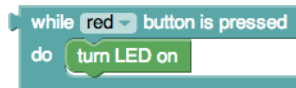
Next, find a block like this:

and drag it on to the right side of the screen. As you can see, the block describes what it will do in English. It's just up to us to finish the sentence now. If you wish, you can



change 'red' to 'blue' to change the sentence to talk about a different button. Let's leave it at 'red' for now.

Next, look for the 'turn LED on' block and drag it inside of the first block next to 'do', so that it looks like this:



Make sure the two pieces are connected - you'll briefly see a yellow outline and hear a clicking noise if you did it right.

Now click the *Run Program* button. If you did everything correctly, a virtual joystick will appear on your screen and clicking on the red button will make the LED blink!

Didn't work? Uh oh. Make sure:

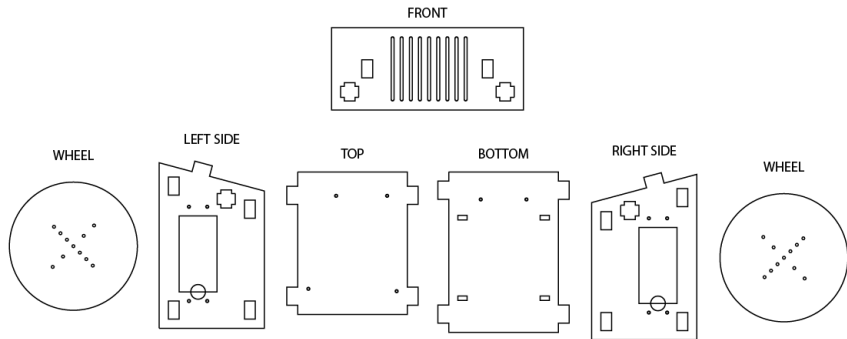
- your USB cable is plugged into your computer and Arduino
- the short leg of the LED is in GND and the long leg is in 13 and it is plugged in
- that Robotnik is still running - look at your terminal window and run `robotnik` again if needed

Don't forget to ask for help if you need it!

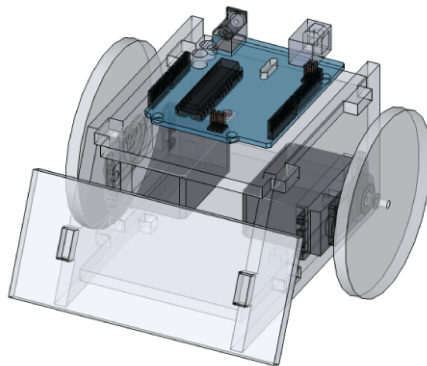
QUEST 2: CONTROLLING A ROBOT

You now know the how to create programs by using Robotnik blocks and how to run programs. We are ready to move on to something more advanced. The first step is to assemble the robot. All of the wooden pieces are labeled and slot together - look at the example robot and ask questions if you need help.

Put all the pieces together, then pop the motors in through the sides and screw them in. Attach the Arduino to the top, plug the shield on to the top of the Arduino and plug the motors and batteries in to the labeled ports of the shield. Attach the wheels to the sides of the motors. Many Arduino shields add additional hardware, but ours is just used to connect everything together in the right way. Under the shield and behind the scenes, the batteries are connected to the motors, and one pin from each motor called



the 'control pin' goes to the appropriate numbered pin on the Arduino.
When you're done, your robot should look something like this:



Good job! Our goal is now to make the robot move forward when we press the joystick forward, backward when we move backward and to turn left and right when we move that way. You can do this by assembling the blocks correctly. Remember that each motor moves independently, and when they move in the same direction, the robot will move in that direction. When they move in opposite directions, the robot will twist in place. When only one motor turns, the robot will pivot around the wheel that isn't moving. Remember to think about the way the motors are facing.

Once you have this down, you can move pilot your robot around the obstacle course, or battle someone in the sumobot ring! The first robot to leave the circle loses the match!

Problems?

- Make all the cables are plugged in correctly
- Is Robotnik is still running? Look at your terminal window and run `robotnik` again if needed
- Are there batteries in the battery case and is it turned on?
- Remember that the motors are facing opposite directions
- Are there any 'extra' sticking out of the Arduino shield? The shield and Arduino should align perfectly and there should be no 'extra' pins.

QUEST 3: TEACHING THE ROBOT TO THINK FOR ITSELF

You've made a robot that you can control with your computer. This is one kind of robot, but to really be useful, a robot can be made autonomous so that it senses the world around it with 'sensor modules' and makes decisions automatically based on the data that it gets from them.

We have provided a 'proximity sensor' that tells the robot how far it is from an object. Attach it to the front of the robot, and plug it into the labeled port on the shield. Now the robot should be able to 'see'. Our goal is to tell the robot to:

1. Move forward
2. If there is something 5cm in front of the robot, turn right slightly
3. Repeat

Again, you can do this by dragging the spaces. Once you have this program working, you should be able to set your robot down in the obstacle course and let it go without bumping into anything.

Did it work? Congratulations on creating a robot that can move and think for itself! Do your part to prevent the robot apocalypse by always staying one step ahead of the machines.

ADVANCED FLOW

You program? Great! I want you to do the same three quests as in the main flow, but I'm going to give you extra information so you can go on side quests. :)

Robotnik is a Google project that actually generates source code when you place the blocks. You can see the source code by clicking on the 'Code' tab. Behind the scenes, we are generating Javascript code and using Rick Waldron's excellent Johnny-Five library

to talk to the Arduino over protocol called Firmata.

You can modify the code in place in the editor and run directly from there instead of using the block interface. This gives you much more flexibility and you can do all sorts of things! The Johnny-Five documentation is linked in the 'Code' tab. Between looking at the code generated by the blocks, and the documentation, you should be able to complete all the quests and add some of your own special twists.

NOT AT MAKERLAND?

Are you home from the conference and want to do this again? No problem! You missed Makerland but want to follow this tutorial anyway? No problem! Everything we use is open source and readily available. First, you'll need an Arduino Uno R3 with the firmata program uploaded to it. This is a requirement to use Johnny-Five. To do that:

- Download Arduino IDE (<http://arduino.cc/en/main/software>)
- Plug in your Arduino or Arduino compatible microcontroller via USB
- Open the Arduino IDE, select: *File > Examples > Firmata > StandardFirmata*
- Click the *Upload* button.

Then you'll need the parts for the robot and schematics for the shield. This is all available at <http://sumobotkit.com> - if you have access to a nice Hackerspace or a laser cutter and 3D printer, you can make everything yourself, otherwise you can find places to order the parts through a service like <http://ponoko.com>

Finally, here is the shopping list of parts from Adafruit:

- Arduino Uno R3: <http://www.adafruit.com/products/50>
- Proximity Sensor: <http://www.adafruit.com/products/164>
- Battery Case: <http://www.adafruit.com/products/830>
- Continuous Rotation Servo Motor (2): <http://www.adafruit.com/products/154>

Any color of LED will do, and you'll also need a 'type B' USB cable to connect the Arduino. You can find them at your local electronics store or at Adafruit if you search.

DANCING DRONES

OVERVIEW

In this workshop you'll learn about the wonderful world of autonomous flying robots, specifically the AR Drone 2.0 provides a high level API to send commands, read data back and stream video from it's HD camera.

We'll start writing basic programs to take off and land, and before you know it you'll be using feedback from a wealth of onboard sensors to perform more impressive maneuvers and behaviours.

PREPARATIONS

- Insert a fully charged battery into the AR Drone: <https://www.youtube.com/watch?v=QdFsd9R3vJ8>
- Download the FreeFlight app for your iOS or Android device.
- Create a folder to work in (something like nodecopter)
- *Optional*: Install Node.js on your computer: <http://nodejs.org/download/>
- *Optional*: Install the ar-drone npm module with `npm install ar-drone` into the folder

MAIN FLOW

Now connect to the drone's WiFi with your smartphone, start the FreeFlight app and make a test flight with it's Piloting feature to learn how the drone behaves.

Once you've done that, save this to a file and execute it:

```
var arDrone = require('ar-drone');
var client = arDrone.createClient();

client.takeoff();

client
  .after(5000, function() {
```

```

        this.clockwise(0.5);
    })
    .after(3000, function() {
        this.animate('flipLeft', 15);
    })
    .after(1000, function() {
        this.stop();
        this.land();
    });

```

See how your drone takes of, rotates clockwise and even does a flip! Amazing. Now let's try customising your script with different commands:

Basic directional commands:

- `client.takeoff()`
- `client.land()`
- `client.up(speed)`
- `client.down(speed)`
- `client.clockwise(speed)`
- `client.counterClockwise(speed)`
- `client.front(speed)`
- `client.back(speed)`
- `client.left(speed)`
- `client.right(speed)`
- `client.stop()`

Animation options:

- `phiM30Deg`
- `phi30Deg`
- `thetaM30Deg`
- `theta30Deg`
- ...

More details for the API can be found in the readme: <https://github.com/felixge/node-ar-drone#ar-drone>

Combine these together and get your drone dancing around the room!

Now that you've got the hang of the basics, there are three different challenges to attempt, you can try them in any order.

MAKE YOUR OWN DRONE CONTROLLER

sending commands from a controller (xbox, keyboard, arduino, browser)

SECOND FLOW

reading nav data from the drone and visualising it (in a browser, or terminal)

EYE IN THE SKY

streaming video/png data back and displaying it (most likely in a browser)

ADDITIONAL TASKS

Additional tasks to be filled here. For those who want more or are more advanced if you don't have second flow.

FAQ

- Crashes
- Won't take off
- The App
- How much can an AR Drone lift? - Not much, about 100g before it becomes unstable.

ADDITIONAL RESOURCES

- Nodecopter website - <http://nodecopter.com/hack>
- Nodecopter modules on NPM - <https://npmjs.org/browse/keyword/nodecopter>
- Nodecopter projects on GitHub - <https://github.com/search?q=nodecopter>

HACK YOUR HOUSE

OVERVIEW

In this workshop you will learn how to build your own smart RFID-controlled deadbolt lock. We will be using an Arduino Uno, a servo, and a few sensors to modify a deadbolt lock so that you can control it via software and unlock it with an RFID tag. You will be able to mount our Arduino to your existing deadbolt without physically modifying or damaging it!

PREPARATIONS

Download the Arduino IDE from <http://arduino.cc/en/Main/Software> and install it on your system.

MAIN FLOW

STEP 1: HELLO ROBOT!

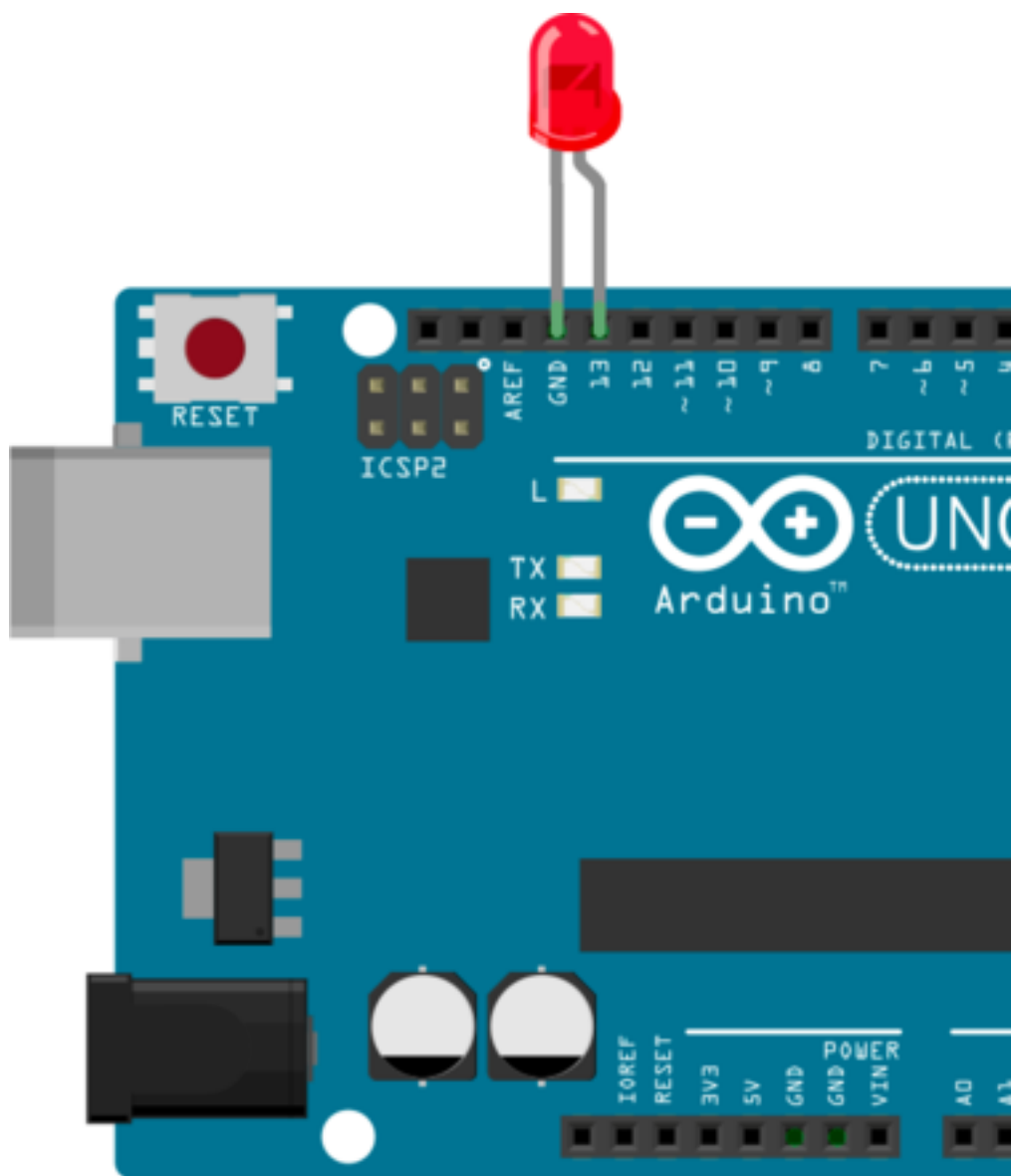
We are going to start off by making sure that you are able to upload code to your Arduino using the Blink tutorial (<http://arduino.cc/en/tutorial/blink>). One of the best things about Arduino is the amazing open source community that exists around it. We will be making use of a number of open source examples as we build our smart lock!

Plug your LED power into pin 13 of your Arduino and ground into the GND pin next to it. The shorter pin is Ground (-) for LEDs.

Plug your Arduino into your computer via USB.

Open the Arduino IDE, select: File > Examples > 01.Basics > Blink and click the “Upload” button to install the Blink program on your board.

If you successfully uploaded your program, the LED that you plugged into your Arduino should be blinking on and off every second!



STEP 2: CONNECT AND TEST A SERVO

Now that we are sure that you can program your Arduino, we will move on to the fun stuff and connect our servo to our board.

A servo is a type of motor that typically has a 180 degree movement radius. Later in the workshop, we will be using our servo to control the movement of a deadbolt lock.

For now, we just want to connect our servo to our Arduino and make sure we are able to control it via a simple program.

A servo motor has three wires - power (red), ground (black), and control (frequently yellow or white). Connect the power wire to the 5V pinout on the Arduino and the ground wire to the GND pinout next to it. We can then connect the control wire to Digital Pin 12 on our Arduino as in the following diagram:

Now that our servo is connected to the Arduino, we will need to write the software to control it. Let's create a new file and start it off with the following code:

```
#include <Servo.h>
Servo myservo;
```

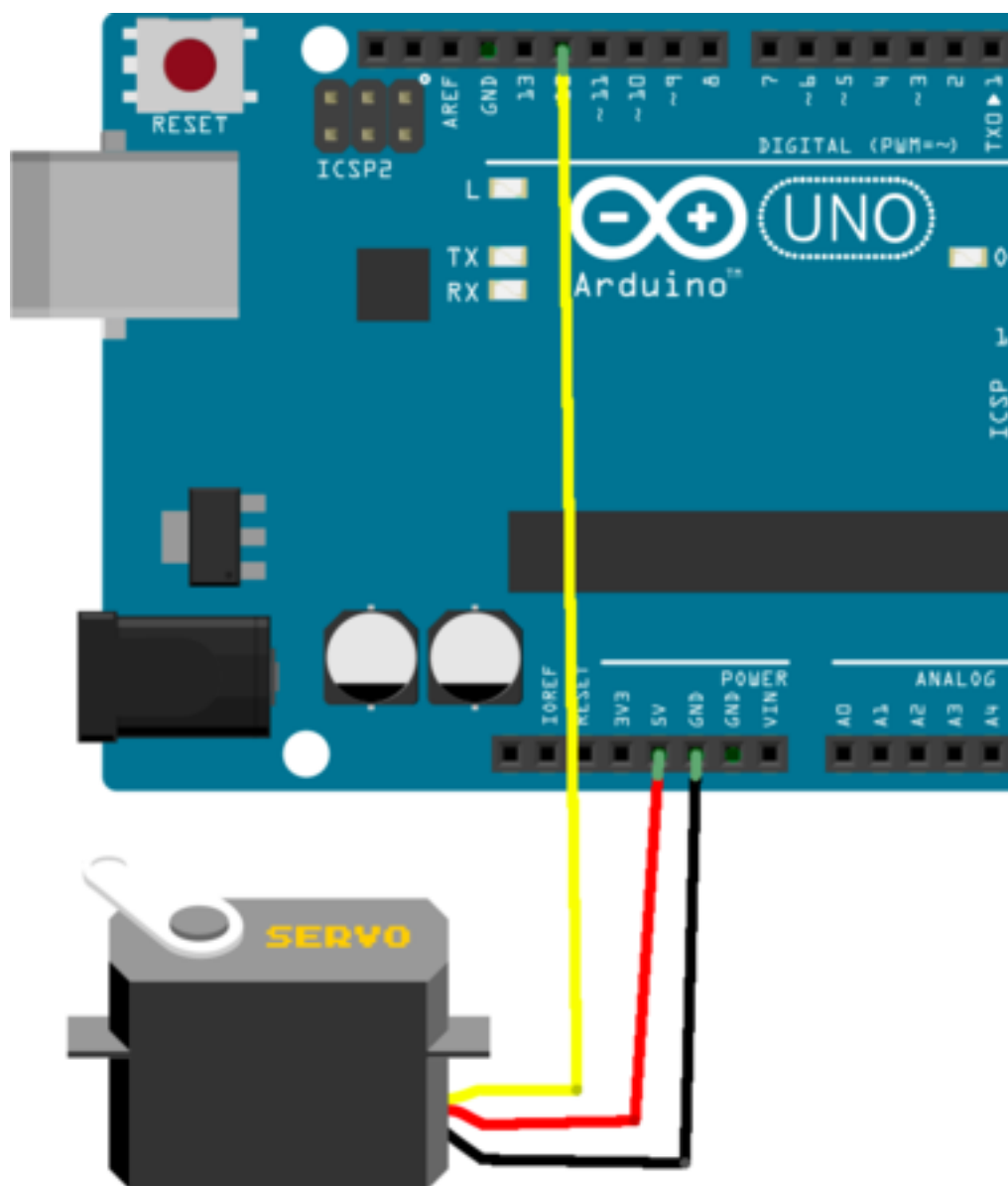
This snippet includes the Servo library and defines a new Servo object that we will use later to control our servo motor.

Next, we can create two methods: `loop()` and `setup()` - these methods are common to every Arduino program. The `setup()` method runs when the Arduino turns on, and the `loop()` method constantly runs on a loop (as the name would suggest).

In our `setup()` method, we will attach our `myservo` object to pin 10 where we plugged in the servo earlier. The method should look like this when we are done:

```
void setup()
{
  myservo.attach(12);
}
```

Now that the Arduino knows where to find our Servo, we can experiment a bit. In order to move the servo to a new position, you use the `myservo.write(pos);` method. `pos` is an integer from 0 to 180. Try using `myservo.write(pos);` in both the `setup()` and `loop()` methods - see what happens when you set `pos` to different values. Note that you can use the `delay()` method to pause execution between different commands. For



fritz

example:

```
myservo.write(180);  
delay(1000);  
myservo.write(0);
```

This snippet would move the servo to position 180, pause for 1 second, and then move the servo to position 0.

After each modification, Upload your code to the Arduino again. You can view the progress of your upload in the log console on the bottom of your Arduino IDE.

Once you are comfortable with controlling your Servo, we can move on. Additional examples are available here: <http://arduino.cc/en/Tutorial/Sweep>

STEP 3: CONNECT AND TEST RFID READER

Now that we have programmed our Arduino to control a Servo, we can add our first sensor - the RFID reader. We will be testing using an example sketch from <http://playground.arduino.cc/Learning/PRFID>

The Parallax RFID Reader that we are using is actually fairly simple to program. It has four pins: GND, VCC (power), ENABLE, and SOUT. The ENABLE pin takes a digital voltage - either high or low. When the voltage is low, the RFID reader is on and actively reading inputs. When it is high, it is deactivated. The SOUT pin is a Serial interface that outputs the RFID tag code as a series of 10 digits.

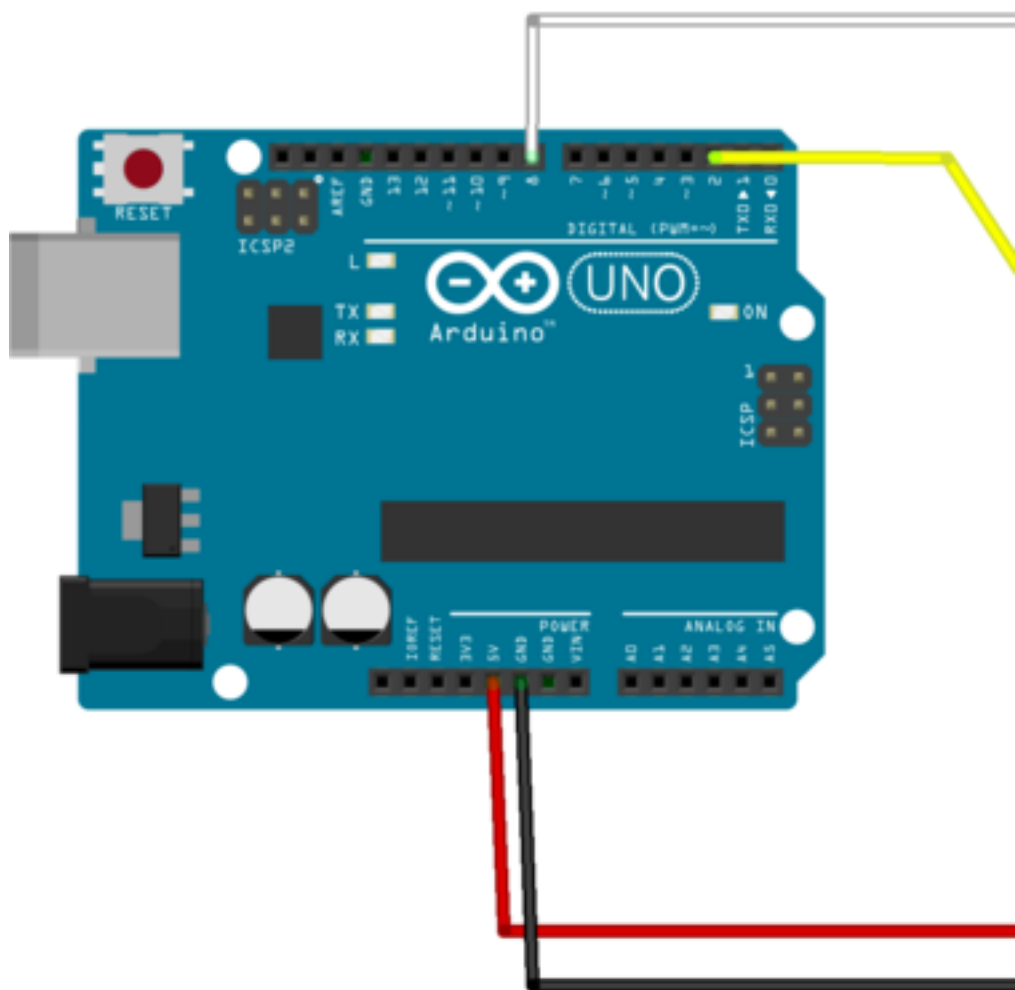
You will need to wire the GND to your Arduino's GND, VCC to Arduino's +5V, ENABLE to Digital Pin 2 on the Arduino, and SOUT to Digital Pin 8 on the Arduino. I like to plug my RFID reader into a breadboard before wiring it to my Arduino, as it makes it easier to prototype.

Once it is wired up, we will be writing a program that uses the Arduino's SoftwareSerial library to read values from the RFID reader and print them out in our Serial Monitor (a simple tool that the Arduino IDE provides to receive data from the Arduino via a Serial port and display it to you, the developer).

Create a new Sketch (Arduino program) that has a `setup()` and `loop()` method. Then include the SoftwareSerial library at the top of the sketch:

```
#include <SoftwareSerial.h>
```

Next we will set up some variables that will be used in our `loop()` method a little later:



```

int val = 0;
char code[10];
int bytesread = 0;

#define rxPin 8
#define txPin 9
SoftwareSerial RFID = SoftwareSerial(rxPin,txPin);

```

An important thing to take note of here are that we are defining our `SoftwareSerial` pins as digital pins 8 and 9, which explains why our RFID Reader's SOUT is connected to pin 8. We also define the `val`, `code`, and `bytesread` variables. `val` will store the single digit value read by our RFID reader. `code` is an array that we will push the digits read by `val` onto to build the full tag code. And `bytesread` is a counter to determine how many digits we have read from the RFID reader for an expected tag code, which is 10 digits. Now we can move on to our `setup()` method. Most of our logic for the RFID reader is going to be in the `loop()` method, so all our `setup()` method needs to do is initiate our Serial monitor and enable our RFID reader by setting digital pin 2 to LOW and opening the 2400-baud `SoftwareSerial` connection. Add the code from below:

```

Serial.begin(2400);    // Hardware serial for Monitor 2400bps
pinMode(2,OUTPUT);    // Set digital pin 2 as OUTPUT to connect it to the RFID /ENAB
digitalWrite(2, LOW);  // Activate the RFID reader
RFID.begin(2400);

```

Now we can move on to the meat of our application, the `loop()` - I will explain each block of code line by line, as it is fairly complex the first time you encounter it.

First we need to check the output of the RFID reader:

```

if((val = RFID.read()) == 10)
{
}

```

The RFID reader outputs 10 at the beginning of a tag code, and 13 at the end. This lets us know when to stop reading bytes for the current tag code, and move on to the next one.

Within this `if` statement, we will be running a while loop that reads in 10 digits from the RFID reader:

```

bytesread = 0;
while(bytesread<10)
{
}

```

The expected length for our tag code is 10 digits, so we only loop until we have read in 10 bytes.

Then we can add the rest of our code within the while loop:

```

val = RFID.read();
if((val == 10)||(val == 13))
{ // if header or stop bytes before the 10 digit reading
  break; // stop reading
}
code[bytesread] = val; // add the digit
bytesread++; // ready to read next digit

```

For every iteration of the loop, we read in a single byte outputted by our RFID reader. If that byte is 10 or 13 (our start or stop codes), we break out of our loop. If it is any other value, we add it to the code array and increment bytesread. Last but not least, we need to print our tag code out to the Serial Monitor. After our while loop's end bracket (but still within our large if statement), we will add the following code:

```

if(bytesread == 10)
{ // if 10 digit read is complete
  Serial.print("TAG code is: "); // possibly a good TAG
  Serial.println(code); // print the TAG code
}
bytesread = 0;
delay(500); // wait for half a second

```

If we have read in 10 bytes successfully, we print it out in the Serial Monitor and then reset our bytesread counter and wait for half a second to prevent us from looping faster than the RFID reader actually reads values. And that's it, now you can Upload your code and open the Serial Monitor via the Tools menu. Once you have the Serial Monitor open, make sure to change the baud rate to 2400. Now when you hold an RFID tag near the RFID reader, you should get a tag code outputted to your Serial Monitor!

STEP 4: TURNING OUR SERVO WITH RFID

Now that we have successfully moved our Servo and read an RFID tag in separate steps, we can try to put it together.

Take the working RFID reader code from Step 3, and attempt to combine it with our working Servo movement code from Step 2.

In order for this to work, we will actually have to connect a separate power supply for our servo to use as the Arduino does not provide enough voltage for both the RFID reader and the servo at the same time.

Take the provided battery, and re-wire the Servo to it. We connect all GND wires to the Arduino's GND, but the RFID reader's VCC goes to the Arduino's +5V output and the Servo's VCC goes to our external battery pack. This becomes much easier if you experiment with moving the Servo when you print out the Tag Code in our Serial Monitor. Note that since the Servo takes time to move, you may need a larger delay in your RFID reader code.

The Servo library documentation is available here if you would like to dive deeper into it: <http://arduino.cc/en/reference/servo>

If you get stuck and would like to compare your code with the solution, you can see it here: <https://gist.github.com/jonmarkgo/9058657>

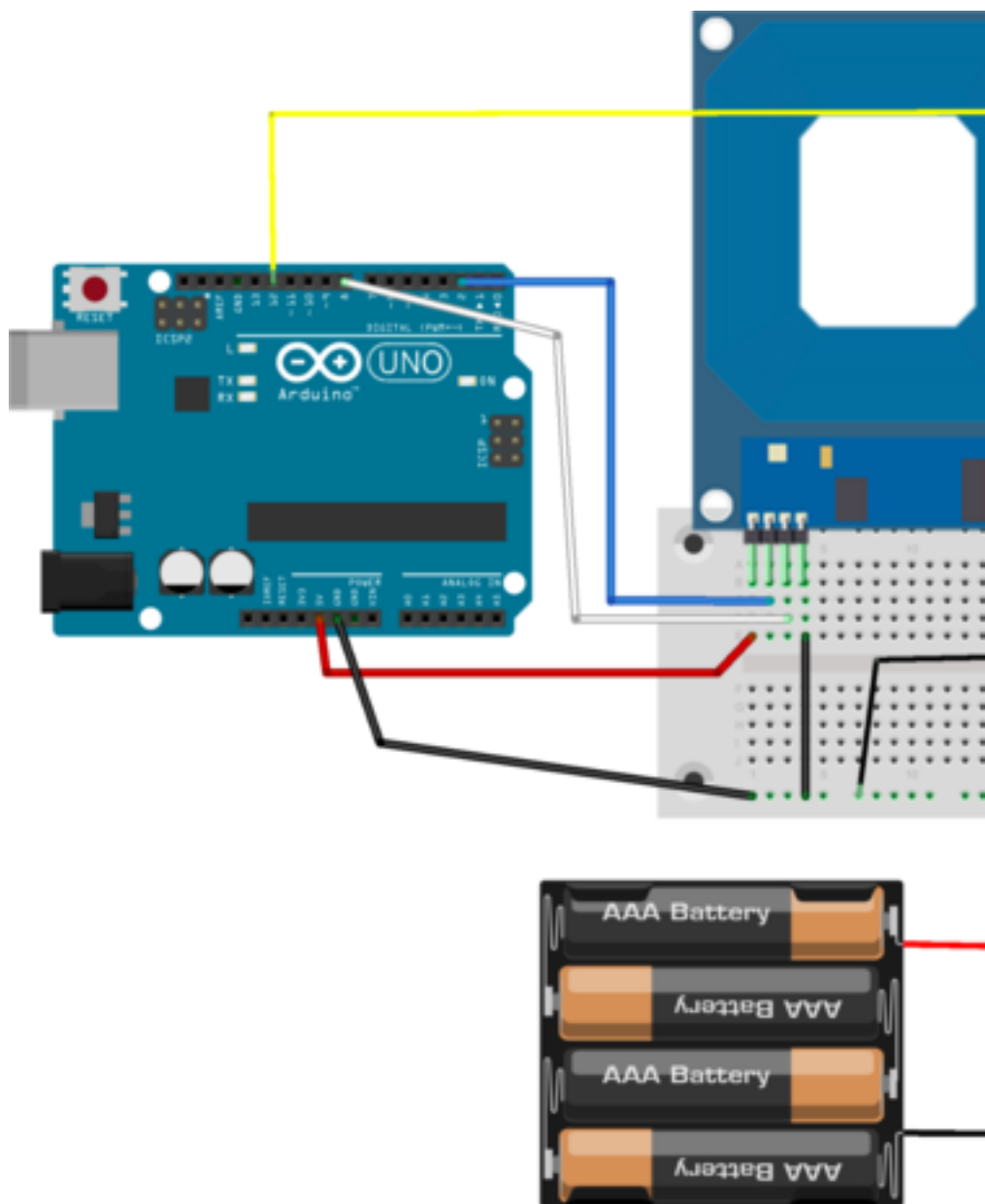
STEP 5: ACCESS CONTROL

Hooray, now you can move a servo whenever someone swipes their RFID tag on our reader! But how do we know if the card being swiped has access to our home? In this step, we will add access control to only allow certain RFID tags to unlock our door.

To find the Tag Code for your RFID tag, open the Arduino IDE Serial Monitor and look for the code that is printed out when you swipe your tag. Copy that code, and put it in a variable in your sketch.

Now, where you currently move the Servo after a tag is detected, add an if statement to check if the tag that was scanned is the verified tag! You may need to use the String library for this comparison: <http://arduino.cc/en/Reference/string>

If you get stuck and would like to compare your code with the solution, you can see it here: <https://gist.github.com/jonmarkgo/9058825>



STEP 6: MOUNTING TO YOUR LOCK

Now that the software side of our project is done, we must mount the servo to our dead-bolt lock. I prefer to use household items when prototyping these types of applications, though if you have access to a 3D printer I would recommend designing and printing your own lock mount.

For the purpose of prototyping, we will be using cardboard and duct tape to mount our servo to our lock - just like astronauts do!

Attach the two metal rods to your servo with screws and washers.

Now use a piece of cardboard (or other stiff material) to make a tighter bond between the servo and the lock:

Now you can tape the servo to the deadbolt lock. Make sure it is positioned on the correct side so that the direction that the servo turns in is aligned with the direction that the lock turns in:

And last but not least, we will tape our servo's arms to the deadbolt itself:

Now you have your fully mounted (and fully impermanent) servo-controlled deadbolt:

SECOND FLOW (OPTIONAL)

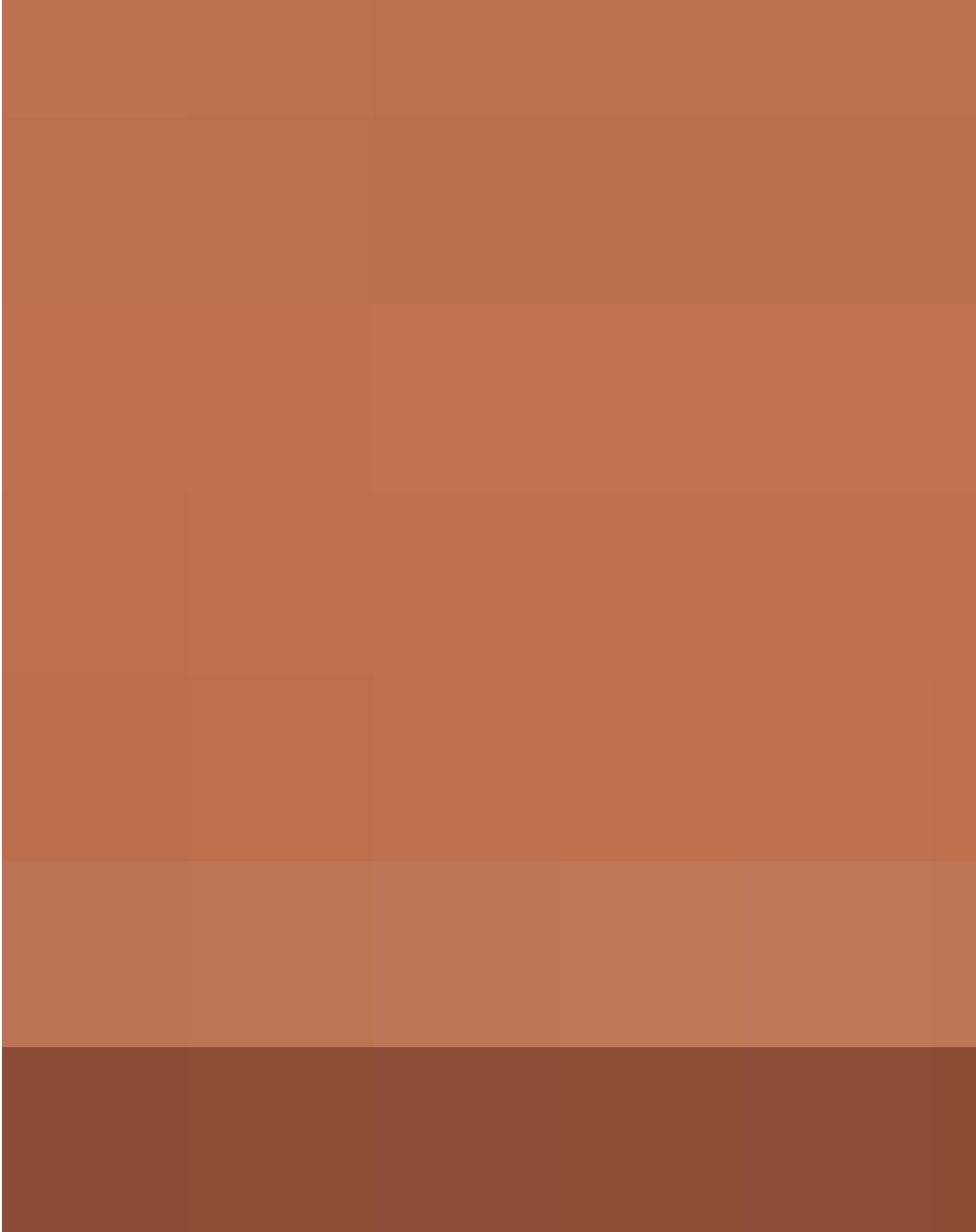
At this point, you have built an RFID-controlled deadbolt using your Arduino, a servo, and an RFID reader. But when it comes to home automation, there is always more to be done!

EXPERIMENT 1: MOTION-CONTROLLED DEADBOLT

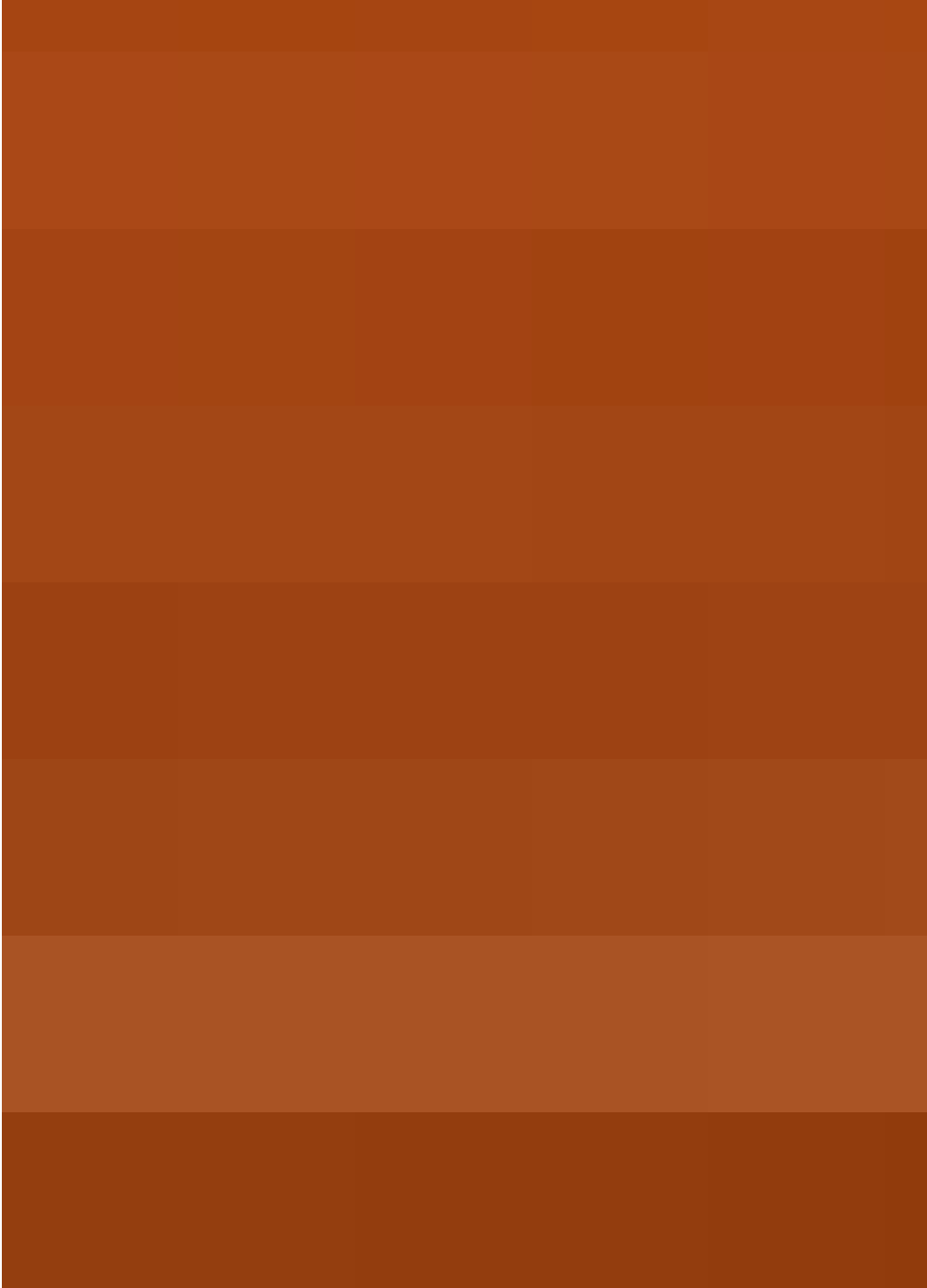
This first experiment is the simplest (and most insecure) - we will unlock or lock our door every time we detect movement in front of it.

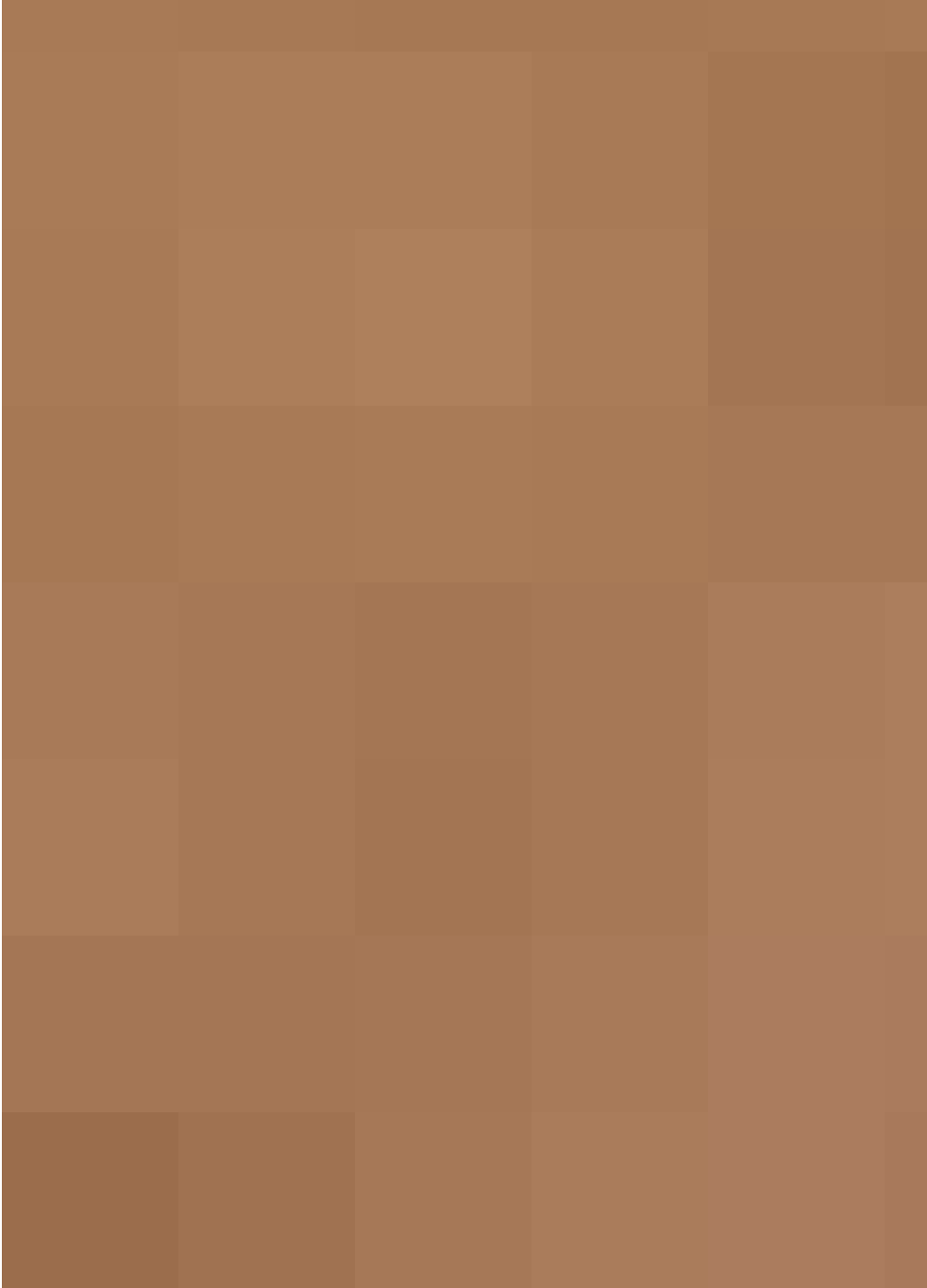
Take the PIR motion sensor and wire it into your Arduino (VCC to +5V, GND to GND, and control to digital pin 2) - NOTE that the middle wire of the PIR sensor is GND, not the black wire. This is strange, but true. The red (+) wire is still VCC (the sensor should have a + and AL marking on it to distinguish this):

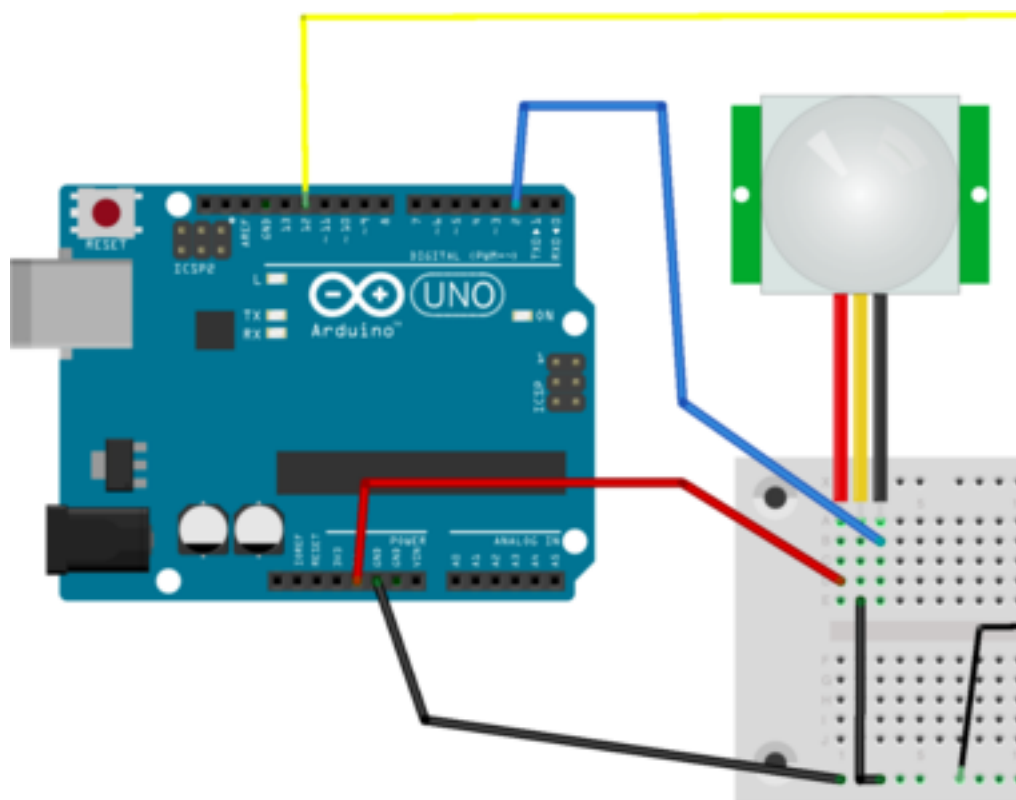
You will need to use an internal pull-up to activate the motion sensor. This is done by setting digital pin 2 as an INPUT pin and then writing a HIGH value to it. Once your Arduino turns on, you need to wait a second or two for the PIR motion sensor to get a reading on a room without movement. Then you can start waving your arms all











around!

When motion is detected, lock or unlock your deadbolt.

You can find additional details on the sensor here: <https://www.sparkfun.com/products/8630>

If you get stuck you can find the solution here: <https://gist.github.com/jonmarkgo/9060847>

EXPERIMENT 2: SMS-ACTIVATED DEADBOLT

For this experiment we only need our Servo connected to our Arduino. Most of the work will be on the Software side.

Once your Arduino is wired up, you need to make sure you have node.js installed and that you have a Twilio account.

You can go to <https://www.twilio.com/> to sign up for a Twilio account. Twilio is an API that makes it easy for us to send and receive text messages or make and receive phone calls. In this case, will be receiving text messages.

You will then need to install node.js from <http://nodejs.org/> and the ngrok utility from <https://ngrok.com/download>

Once you have your Twilio account and you have successfully installed Node.js and ngrok, we can install the necessary modules with the following command in your Terminal:

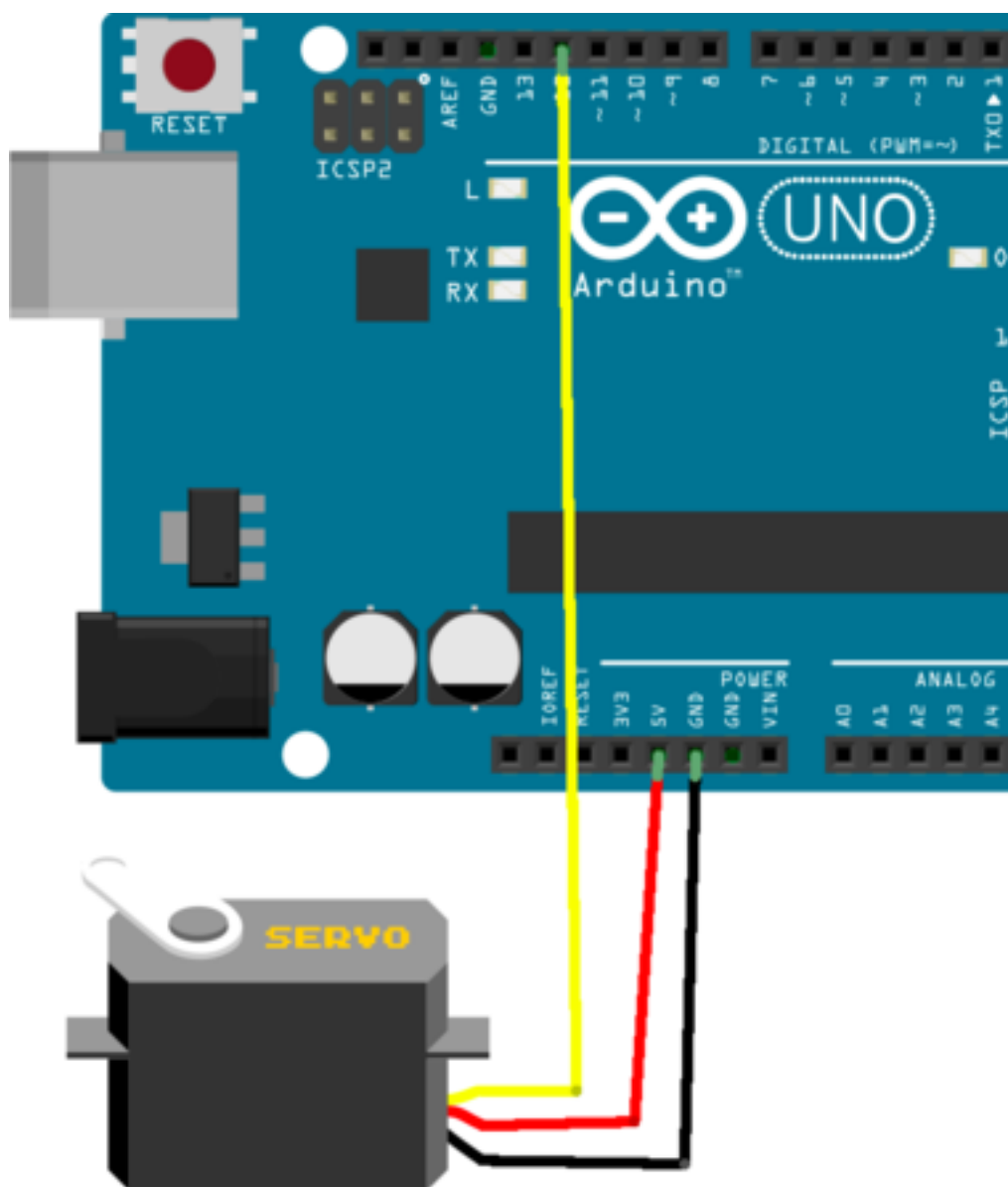
```
npm install serialport twilio express
```

Node-Serialport makes it easy to communicate with your Arduino via a Serial connection from a Node.js program. We will be using it to receive HTTP request for incoming text messages from Twilio, and passing instructions along to the Arduino to lock or unlock your deadbolt.

Express is a simple node.js web framework. And the twilio module makes it easy to communicate with the Twilio API.

First things first, we can set up our new Arduino sketch. The sketch is actually fairly simple. All it needs to do is open a 9600-baud Serial connection, attach to your servo (on pin 12), and read in a character from the Serial connection to determine whether or not it should move the servo motor.

I would encourage you to try this on your own by making use of the Servo code from Step 2 (and your experience so far) as well as the Serial library documentation, available



fritz

here: <http://arduino.cc/en/reference/serial>

I configured my Arduino to lock or unlock my deadbolt whenever it receives the character “V” on its Serial port. You can test this functionality by opening the Serial monitor and typing V to see if the servo moves. When the Arduino locks the deadbolt it responds with the “L” character and when it unlocks it responds with “U”.

If you run into trouble with this portion of the code, you can see the solution here: <https://gist.github.com/jonmarkgo/9061828>

Now that our Arduino is prepared to receive and send instructions on the Serial port, we can dive into something brand new: a node.js program to control our Arduino!

Create a new file in your editor of choice called nodelock.js and start off the file by requiring the modules that we installed earlier using npm:

```
var twilio = require('twilio'),
    serialPort = require("serialport").SerialPort,
    express = require('express');
```

Next we will want to set up our new express server (more documentation available here: <http://expressjs.com/>) and our serialPort connection (more documentation available here: <https://github.com/voodootikigod/node-serialport>):

```
var app = express();
var serialPort = new SerialPort("/dev/tty.usbmodem1411", {
  baudrate: 9600
});
```

Note that we are specifying which USB port to connect to and the baud rate. You may need to change the value of the USB port on your own computer. You can find the name of your active USB port in the Arduino -> Tools -> Port menu.

Next we will set up our HTTP route, called /sms

```
app.use(express.bodyParser());

app.post('/sms', function(req, res){
});
```

We are telling express to accept POST requests at the /sms route, and to parse the POST body using its bodyParser, which will make it easier to access the parameters sent by

Twilio's incoming SMS.

Now that we have our route to accept an incoming SMS, we will want to check if the number the message is from has permission to lock and unlock the door.

```
app.post('/sms', function(req, res){
  if (req.body.From == "+12128675309") {
    console.log("verified number!");
  } else {
    console.log("Wrong number!");
    sendMessage(res, "Invalid number!");
  }
});
```

We are checking the From POST parameter and logging whether or not it is verified.

In the block for a verified number, we can now add the handler to send and respond to data from the Arduino's Serial connection.

```
serialPort.once('data', function(data) {
  if (data.toString().indexOf('U') > -1) { //check if the Arduino returned a U for u
    sendMessage(res, 'Unlocking!');
  }
  else if (data.toString().indexOf('L') > -1) {
    sendMessage(res, 'Locking!');
  }
  else {
    sendMessage(res, 'ERROR');
  }
  console.log('data received: ' + data);
});

serialPort.write("V", function(err, results) {
  if (err) {
    console.log('err ' + err);
  }
  console.log('results ' + results);
});
```

This looks fairly meaty, but what is really going on is fairly straightforward. We set up an event handler to receive Serial data from the Arduino. This event handler checks if the Arduino has sent “U” or “L” - we then take this value and return an SMS response to the user using the `sendMessage` function (which we will write shortly).

After setting up our event handler, we write “V” to the Arduino’s serial connection to tell it that a verified SMS has been received, and it should now lock/unlock the door.

Towards the top of the file we can now create our `sendMessage` function, which takes two arguments - `res` and `message`:

```
function sendMessage(res, message) {  
  var resp = new twilio.TwimlResponse();  
  resp.message(message);  
  res.type('text/xml');  
  res.send(resp.toString());  
}
```

`sendMessage` is called to generate a TwiML response for the user. TwiML is the subset of XML that Twilio uses to pass around instructions. In this case, we are telling Twilio to respond to the SMS message we have received with another SMS message. So the user might send in “unlock” and we might send back “Unlocking!” via Twilio SMS.

Now that our SMS handler is configured, we can finish up our application by opening our `SerialPort` and starting up our Express web server:

```
serialPort.open( function () {  
  app.listen(3000);  
  console.log('Listening on port 3000');  
});
```

And that’s all of our code. Now, if you Upload the sketch we wrote to your Arduino and run your `nodelock.js` script by typing `node nodelock.js` into your Terminal we will be good to go.

If you have run into errors and would like to compare with the solution, you can check it out here: <https://gist.github.com/jonmarkgo/9061701>

To finish things off, we will need to configure Twilio.

Once you have made a new Twilio account (which also provides you with your very own phone number), we can head over to our Twilio dashboard at <https://www.twilio.com/>

[user/account](#) and click on the Numbers tab. Then click into the number you purchased during account signup.

Here, there are two fields: Voice Request URL and Messaging Request URL. We will be using the Messaging Request URL to tell Twilio where to send data about incoming text messages.

But since Twilio communicates via HTTP requests, we will need a publicly accessible web URL for it to POST to when it receives an SMS to your number. For this, we will be using ngrok - the utility you installed earlier.

Once you have started up your node.js server with `node nodelock.js`, open a new Terminal window and type `./ngrok 3000` from the directory you installed ngrok to. Here you will be given a forwarding URL. Take this forwarding URL, append `/sms` to it, and put it into your Twilio Messaging Request URL in your dashboard. Save your Number's settings, and try sending an SMS to it! Your lock should lock and unlock as long as you set the verified number to be yours.

Great work and happy hacking!