

4DOF Mechanical Robot Arm Car

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1. Description

Mechanical arm, alike people's arms, could execute a series of postures. At present, many mechanical arms can't be operated flexibly because of the change of environment and distance.

On tackling this problem, KEYES group has launched a 3 in 1 learning kit-4DOF mechanical robotic arm car. With this kit, you could acquire how to control mechanical arm and smart car. I believe that you can't help opening it to get started.

2. Features

3 in 1 Design: Smart car, mechanical arm, mechanical robot arm car

Multi-purpose Function: obstacle avoidance, follow, remote control and automatic convey.

Easy to Build: Soldering circuit is not required.

High Tenacity: high performance baseplate and metal mechanical arm

High Extension: expand other sensors and modules through motor driver shield.

Multiple Controls: PS2 joypad control, fully automatic and App control(**iOS and Android system**)

Basic Programming: C language code learning.

3. Specification

- Working voltage: 5v
- Input voltage: 7-12V
- Maximum output current: 3A
- Maximum power dissipation: 25W (T=75°C)

- Motor speed: 5V 63 rpm / min
- Motor drive form: TB6612 drive
- Ultrasonic sensing angle: <15 degrees
- Ultrasonic detection distance: 2cm-400cm
- Bluetooth remote control distance: 20-50 meters (measured)
- Bluetooth APP control: support Android and iOS system

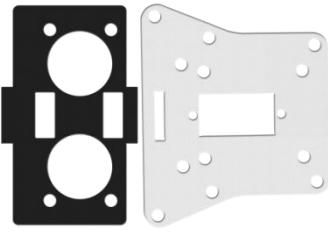
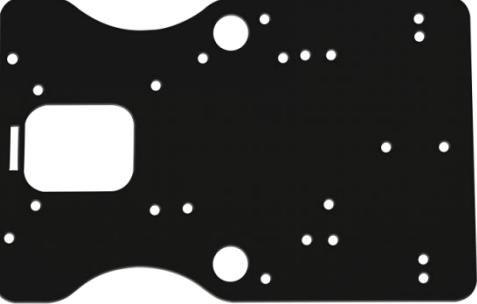
4. Component List

Model	QTY	Picture
KEYESTUDIO V4.0 Development Board (Compatible Arduino UNO)	1	

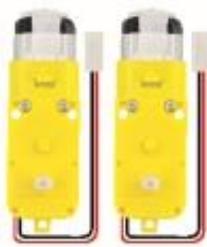


USB Cable AM/BM Blue OD:5.0 L=1m	1	
HC-SR04 Ultrasonic Sensor	1	
KEYESTUDIO TB6612FNG Motor/Servo Drive Shield	1	
KEYESTUDIO Red LED Module	1	
PS2 Wireless 2.4G Game Controller	1	



Baseplate for Ultrasonic Sensor/Servo	1	 A black and grey baseplate with two circular holes and a central rectangular slot.
Car Baseplate $T=3.0$ KS0520	1	 A large black baseplate with multiple circular and rectangular cutouts and several mounting holes.
Bearing Cap	1	 Two white bearing caps, each with a central hole and several smaller holes around the perimeter.
15 pcs Aluminium Alloy Robot Arm Parts	1	 A collection of 15 gold-colored aluminum alloy robot arm parts, including various brackets, gears, and connecting rods.



18650 2-Slot Battery Holder with Lead	1	
KEYESTUDIO Car Wheels	2	
4.5V 200rpm Motor	2	
AXK Plain Bearing	1	
Plain Bearing	2	
Universal Wheel	1	



Fixed Mount 23*15*5MM	2	
M3*30MM Round Head Screws	4	
MG90S 14G Servo	4	
M3*10MM Dual-pass Copper Bush	8	
M3*25MM Dual-pass Copper Bush	2	
M3*30MM Dual-pass Copper Bush	4	
M3*6MM Round Head Nuts	26	



M3*8MM Round Head Screws	21	
M2.5*10MM Round Head Screws	2	
M3*10MM Flat Head Screws	3	
M2*8MM Round Head Screws	4	
M2*12MM Round Head Screws	6	
M2 Nickel Plated Nut	10	
M1.2*4MM Self-tapping Round Head Screws	12	
M3 Nickel Plated Nut	12	



M2.5*20MM Round Head Screws	2	
M2.5 Nickel Plated Self-locking Nuts	2	
M3 Nickel Plated Self-locking Nuts	14	
White Insulator	6	
Black Ties 3*100MM	10	
20cm 2.54 3pin F-F Dupont Wire Eco-friendly	2	
M-F 15CM/40P/2.54/10 Dupont Wire	0.25	



HX-2.54 4P to Dupont Wire 26AWG 200mm	1	A photograph of a four-pin ribbon cable with black and red wires, 200mm long.
3*40MM Red and Black Screwdriver	1	A photograph of a red and black screwdriver set.
2.0*40MM Purple and Black Screwdriver	1	A photograph of a purple and black screwdriver.
M2+M3 Wrench	1	A photograph of a wrench for M2 and M3 screws.
KEYESTUDIO HM-10 Bluetooth-4.0 V3 Module	1	A photograph of the KEYESTUDIO HM-10 Bluetooth module.
Winding Pipe	1	A photograph of a black winding pipe.
6-Slot AA Battery Holder with 15CM Lead	1	A photograph of a 6-slot AA battery holder with a 15CM lead.



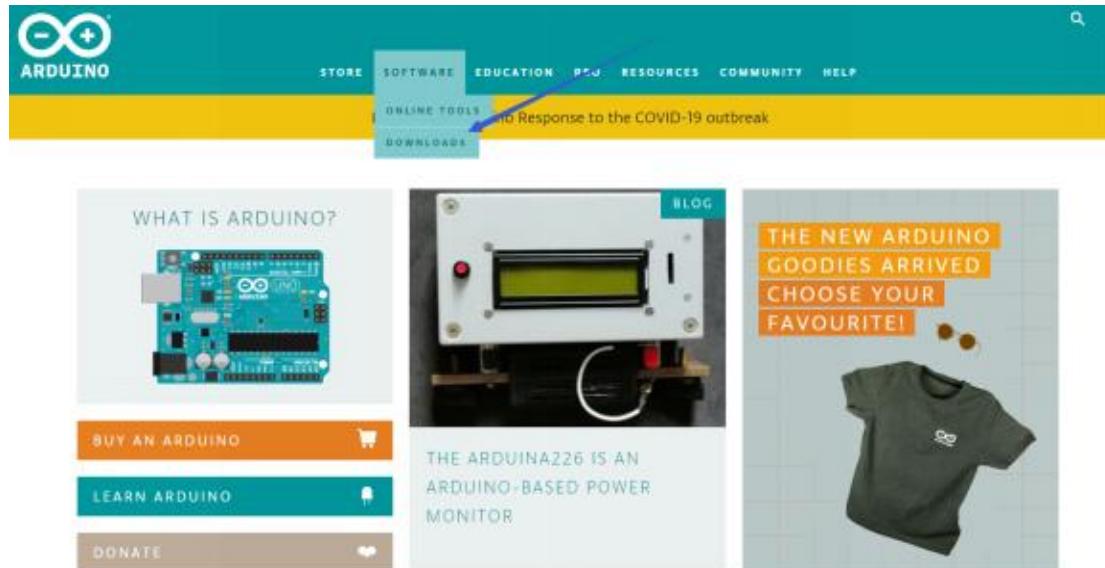
M1.4 Nickel Plated Nuts	6	
M1.4*8MM Round Head Screws	6	

5. Getting Started with Arduino

(1) Installing Arduino IDE

When we get max control board, we need to download Arduino IDE and driver firstly. You could download Arduino IDE from the official website:

<https://www.arduino.cc/>, click the **SOFTWARE** on the browse bar, click “DOWNLOADS” to enter download page, as shown below:



There are many versions for Arduino software, you only need to download the version suitable for your system. Here, we take WINDOWS system as example to introduce how to download and install Arduino IDE.



The screenshot shows the Arduino 1.8.12 download page. On the left, there's a large teal circle with a white infinity symbol containing a minus sign on the left and a plus sign on the right. To its right, the text "ARDUINO 1.8.12" is displayed in bold capital letters. Below this, a paragraph of text describes the software. At the bottom of the main content area, there are links for "Release Notes", "Source Code", and "Checksums (sha512)". On the right side, there's a teal sidebar with download links. The first two links, "Windows Installer, for Windows 7 and up" and "Windows ZIP file for non admin install", are at the top. Below them is a "Windows app" section with a "Get" button and a note "Requires Win 8.1 or 10". Further down are sections for "Mac OS X 10.10 or newer", "Linux 32 bits", "Linux 64 bits", "Linux ARM 32 bits", and "Linux ARM 64 bits". Red arrows point from the text "There are two option versions as for your reference, one is an installer which can be directly downloaded in computer; another one is zip file which requires you to unzip and install it." to the "Windows Installer" and "Windows ZIP file" links.

ARDUINO 1.8.12

The open-source Arduino Software (IDE) makes it easy to write code and upload it to the board. It runs on Windows, Mac OS X, and Linux. The environment is written in Java and based on Processing and other open-source software.

This software can be used with any Arduino board. Refer to the [Getting Started](#) page for installation instructions.

Windows Installer, for Windows 7 and up
Windows ZIP file for non admin install

Windows app Requires Win 8.1 or 10
Get

Mac OS X 10.10 or newer

Linux 32 bits
Linux 64 bits
Linux ARM 32 bits
Linux ARM 64 bits

[Release Notes](#)
[Source Code](#)
[Checksums \(sha512\)](#)

There are two option versions as for your reference, one is an installer which can be directly downloaded in computer; another one is zip file which requires you to unzip and install it.

The screenshot shows the same download page as the previous one, but with two red arrows pointing to the "Windows" links. One arrow points to the "Windows Installer" link at the top of the sidebar, and another arrow points to the "Windows ZIP file" link just below it. The rest of the page content, including the Arduino logo, the main text, and the other download options, remains the same.

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Linux ARM 32 bits
Linux ARM 64 bits

[Release Notes](#)
[Source Code](#)
[Checksums \(sha512\)](#)



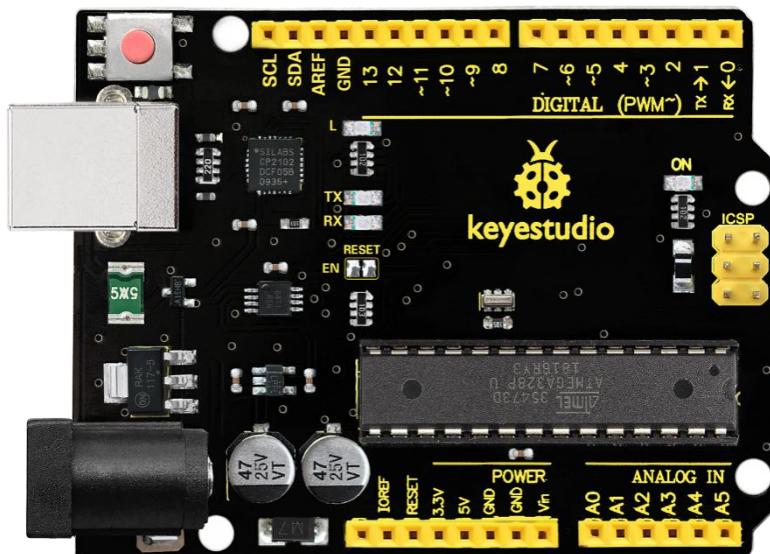
Consider supporting the Arduino Software by contributing to its development. (US tax payers, please note this contribution is not tax deductible). Learn more on how your contribution will be used.



Just click "JUST DOWNLOAD" .

(2) KEYESTUDIO V4.0 Development Board

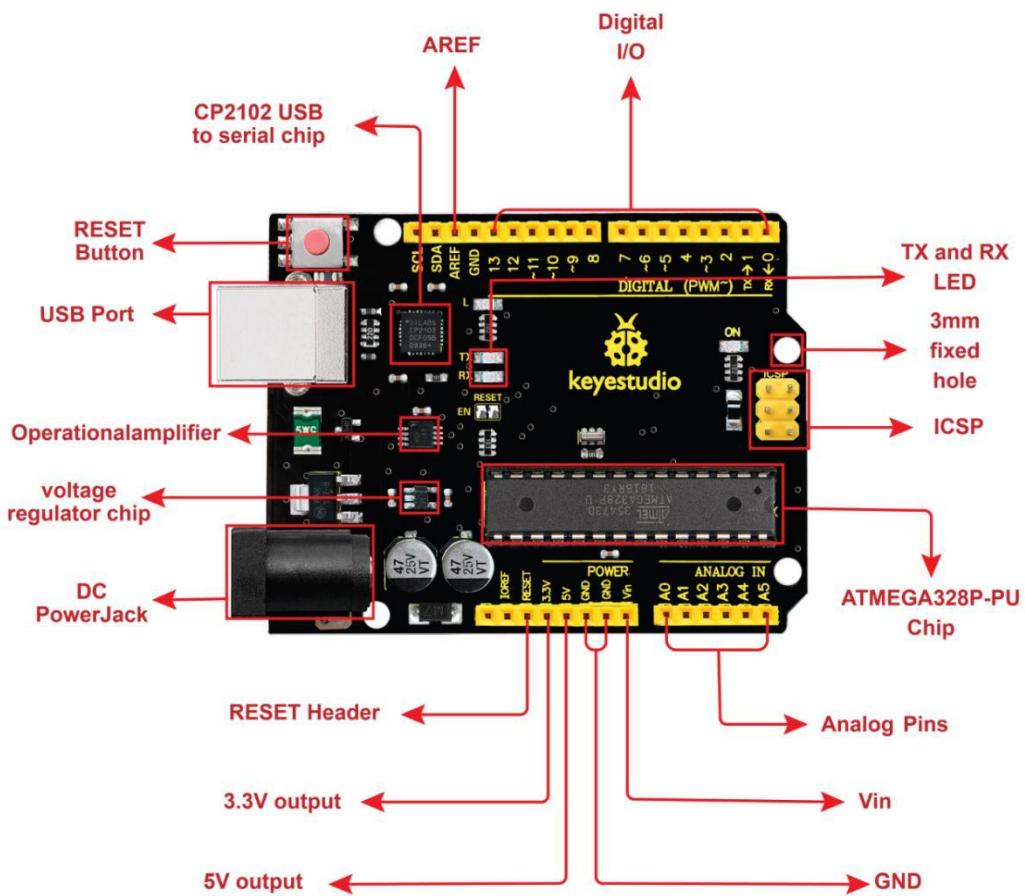
We need to know keyestudio V4.0 development board, as a core of this smart car.



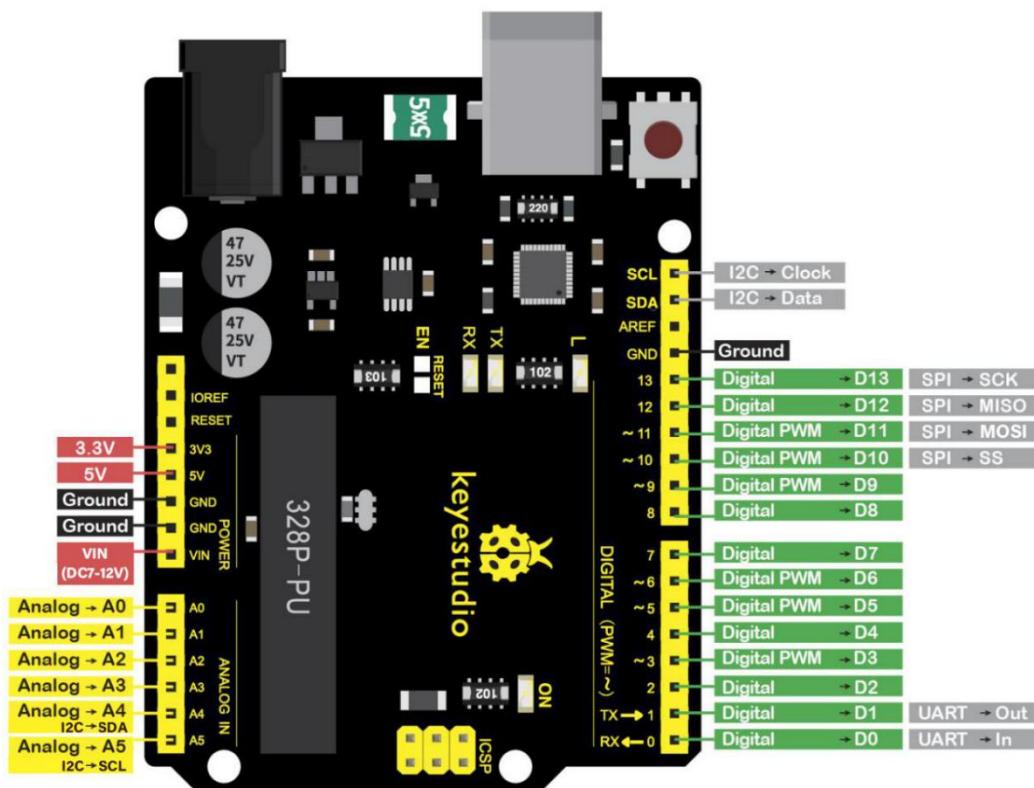
KEYESTUDIO V4.0 development board is an Arduino uno -compatible board, which is based on ATmega328P MCU, and with a cp2102 Chip as a UAR



T-to-USB converter.



It has 14 digital input/output pins (of which 6 can be used as PWM outputs), 6 analog inputs, a 16 MHz quartz crystal, a USB connection, a power jack, 2 ICSP headers and a reset button.



It contains everything needed to support the microcontroller; simply connect it to a computer with a USB cable or power it via an external DC power jack (DC 7-12V) or via female headers Vin/ GND(DC 7-12V) to get started.

Microcontroller	ATmega328P-PU
Operating Voltage	5V
Input Voltage (recommended)	DC7-12V
Digital I/O Pins	14 (D0-D13) (of which 6 provide PWM output)
PWM Digital I/O Pins	6 (D3, D5, D6, D9, D10, D11)
Analog Input Pins	6 (A0-A5)



DC Current per I/O Pin	20 mA
DC Current for 3.3V Pin	50 mA
Flash Memory	32 KB (ATmega328P-PU) of which 0.5 KB used by bootloader
SRAM	2 KB (ATmega328P-PU)
EEPROM	1 KB (ATmega328P-PU)
Clock Speed	16 MHz
LED_BUILTIN	D13

(3) Installing the Driver of V4.0 Board

Let's install the driver of V4.0 board. The USB-TTL chip on PLUS board adopts CP2102 serial chip. The driver program of this chip is included in Arduino 1.8 version and above, which is convenient.

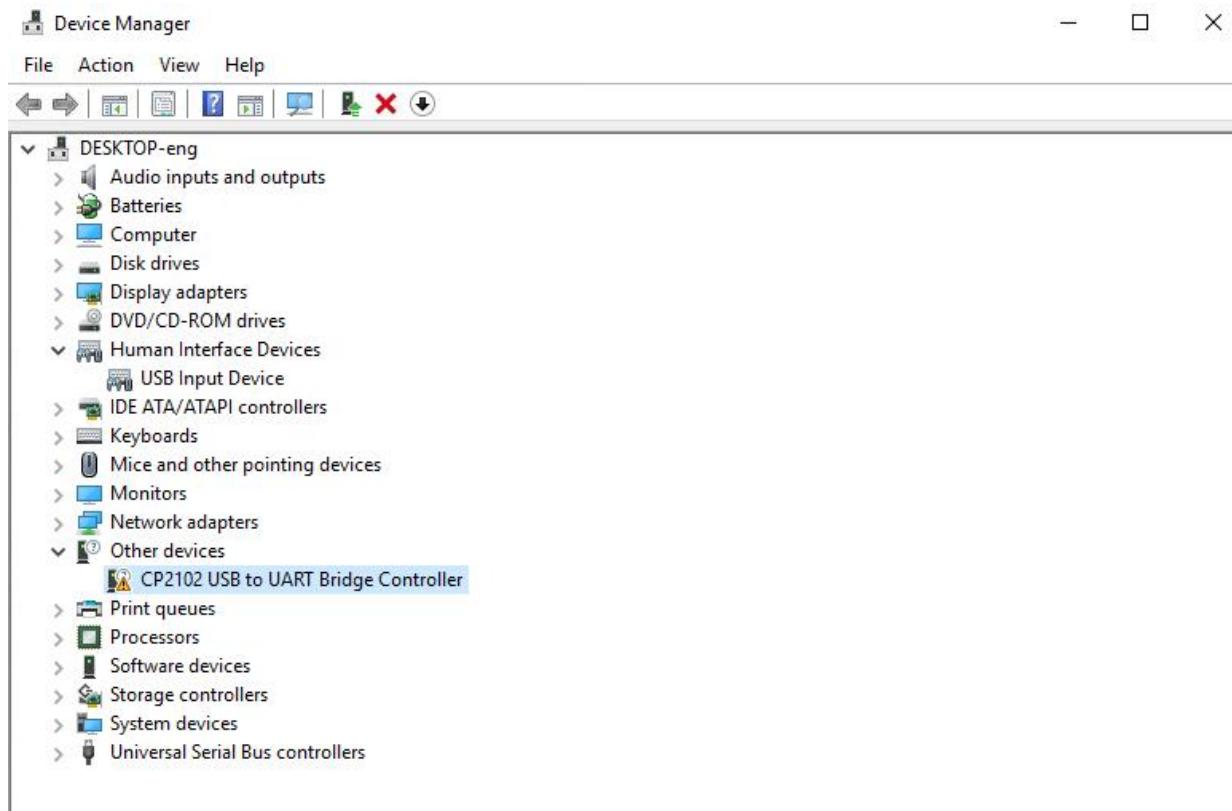
if the version is not above 1.8, you need to download driver of CP2102 in the link:

[https://www.silabs.com/products/development-tools/software/usb-to-uart-bridge-vcp-drivers\)](https://www.silabs.com/products/development-tools/software/usb-to-uart-bridge-vcp-drivers)

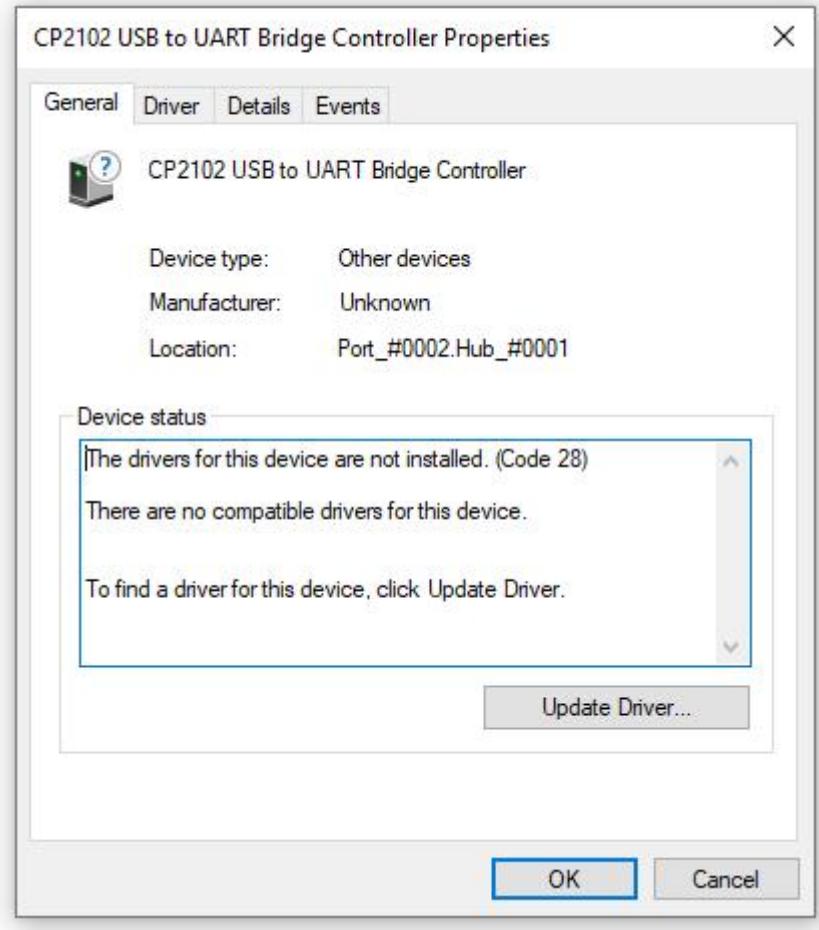


When you attach USB port to computer, the driver of CP2102 can be installed.

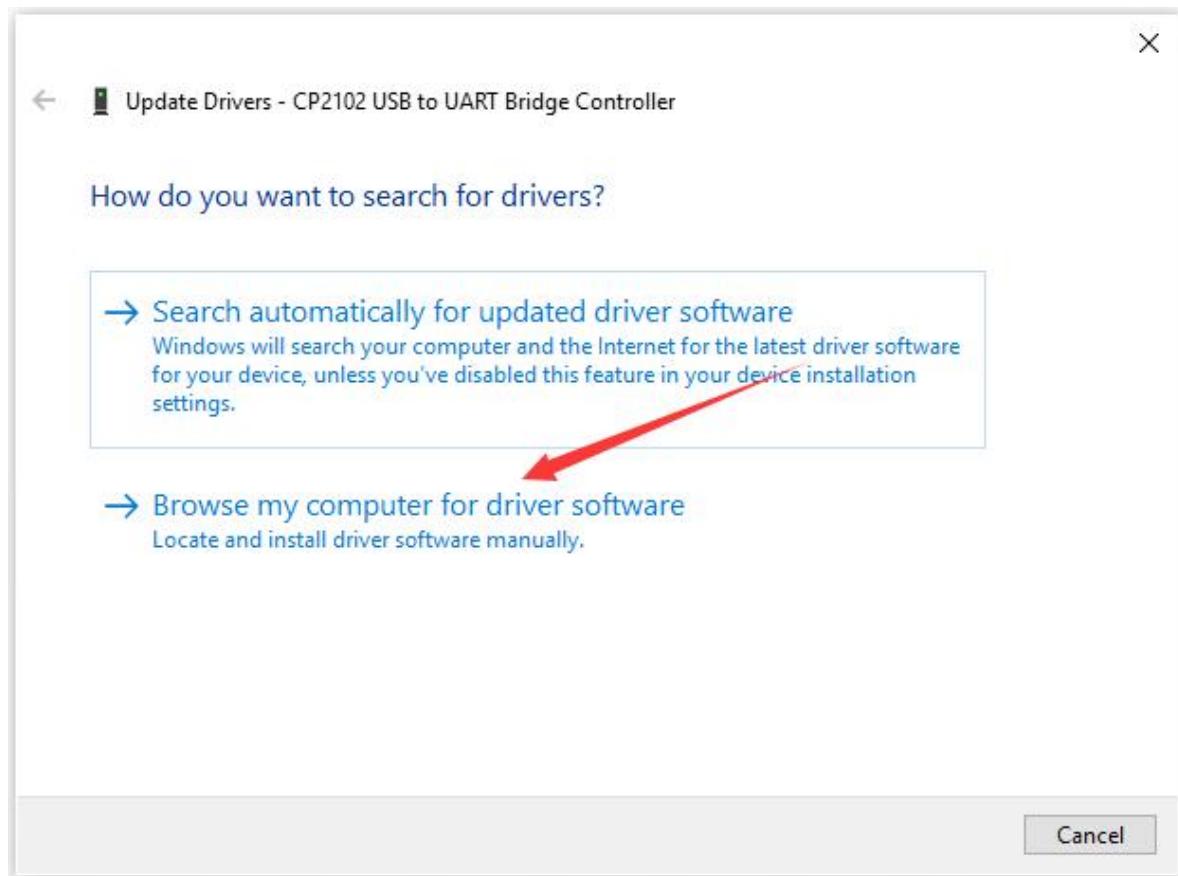
If you install unsuccessfully, or intend to install manually, please open the device manager of computer. Right click Computer----- Properties----- Device Manager.



There is a yellow exclamation mark on the page, which implies installing unsuccessfully. Then we double click the hardware and update the driver.



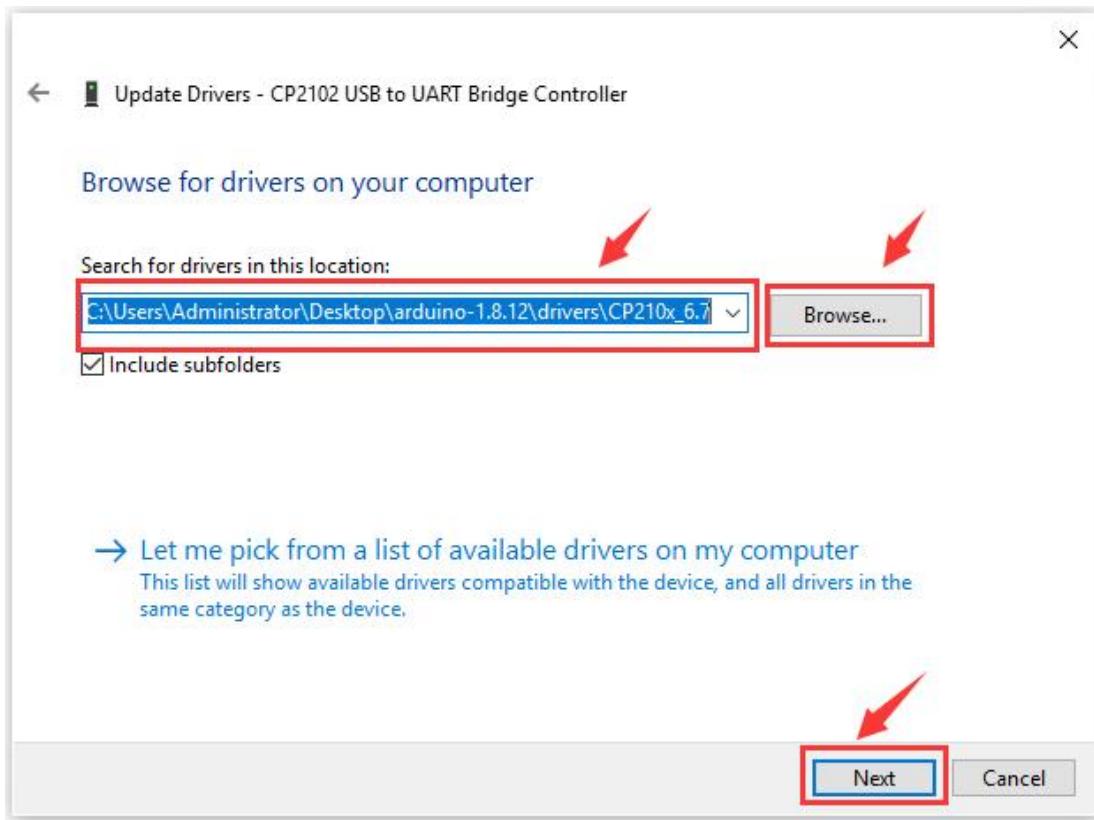
Click “OK” to enter the following page, click “browse my computer for updated driver software” .



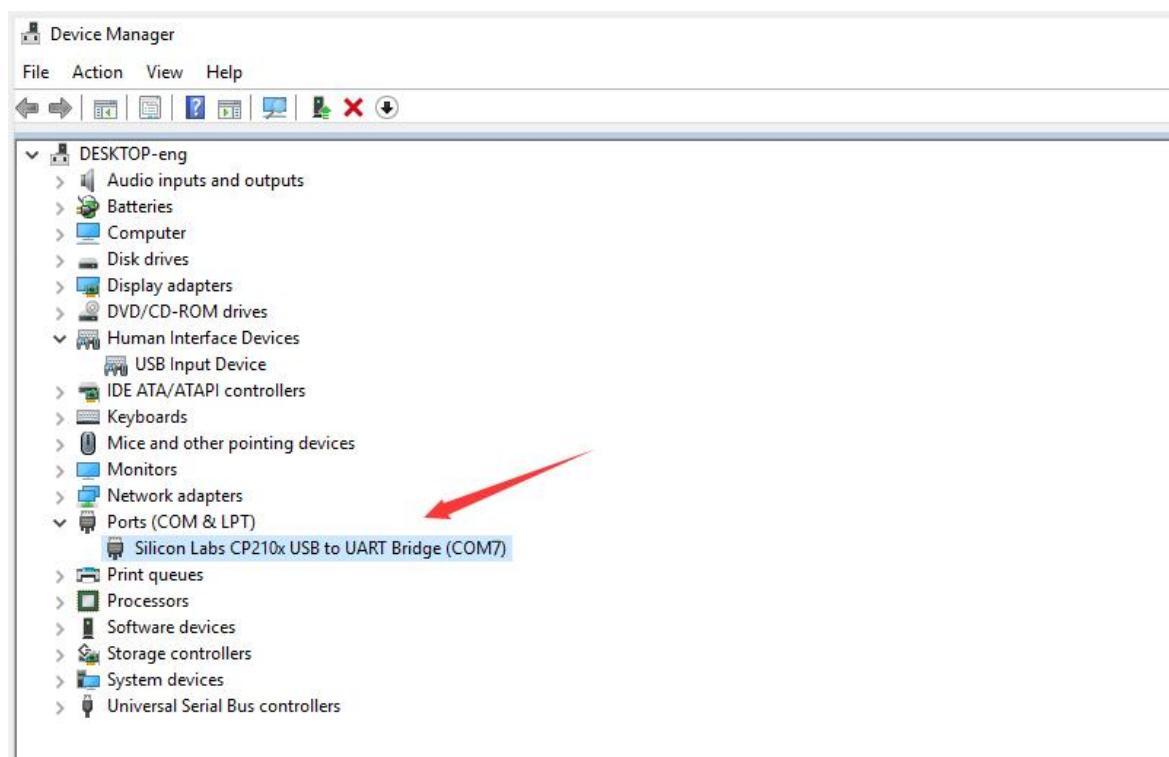
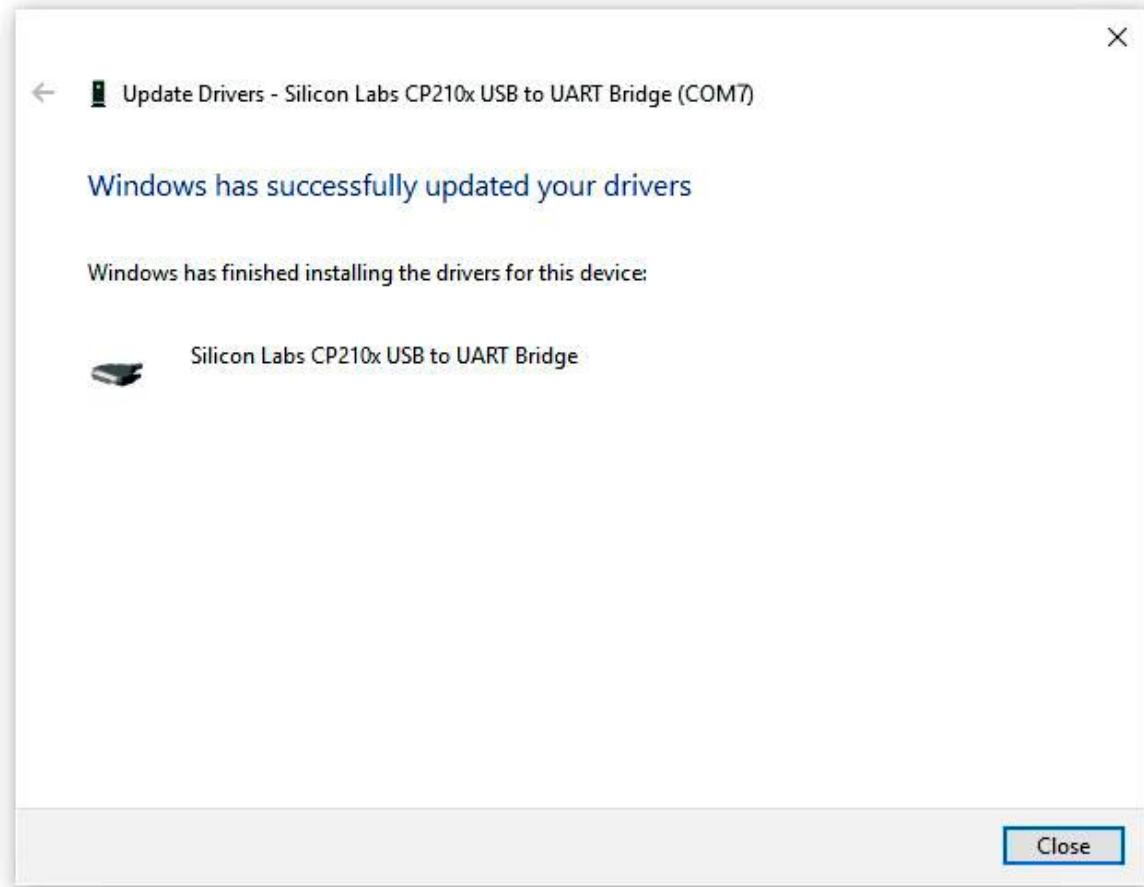
There is a **DRIVERS** folder in **Arduino software installed package**

(**arduino-1.8.12**) , open driver folder and you can see the driver of **CP210X series chips**.

We click "Browse" , then find out the **driver** folder, or you could enter "driver" to search in rectangular box, then click "next" , the driver will be installed successfully.



Open device manager, we will find the yellow exclamation mark disappear. The driver of CP2102 is installed successfully.

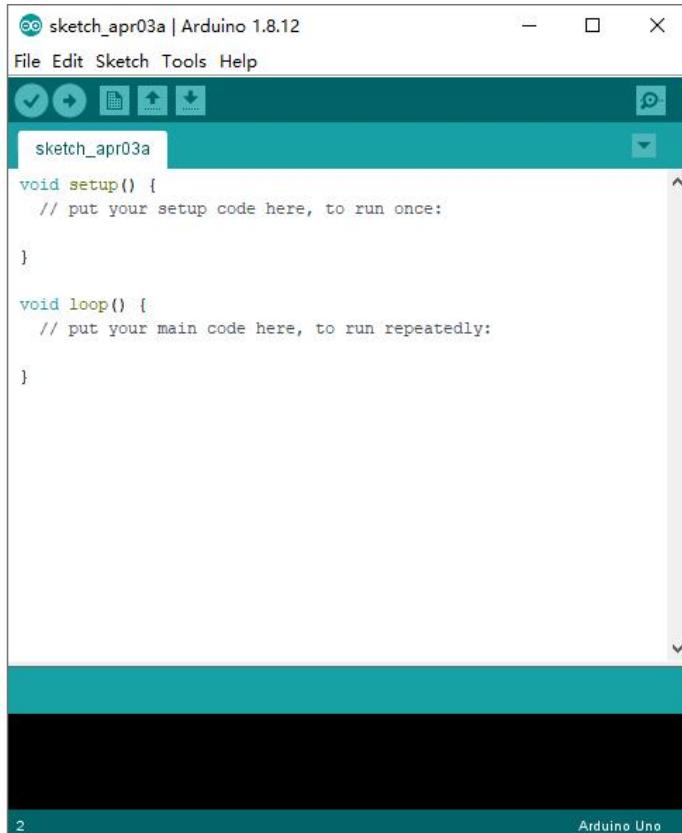




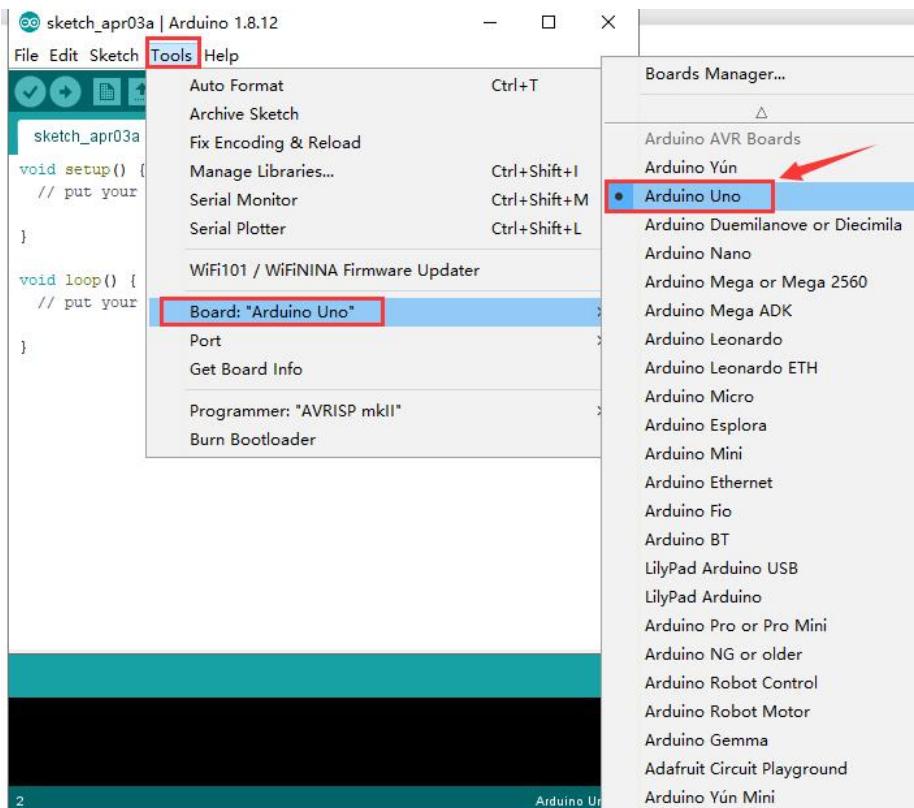
(4) Arduino IDE Setting



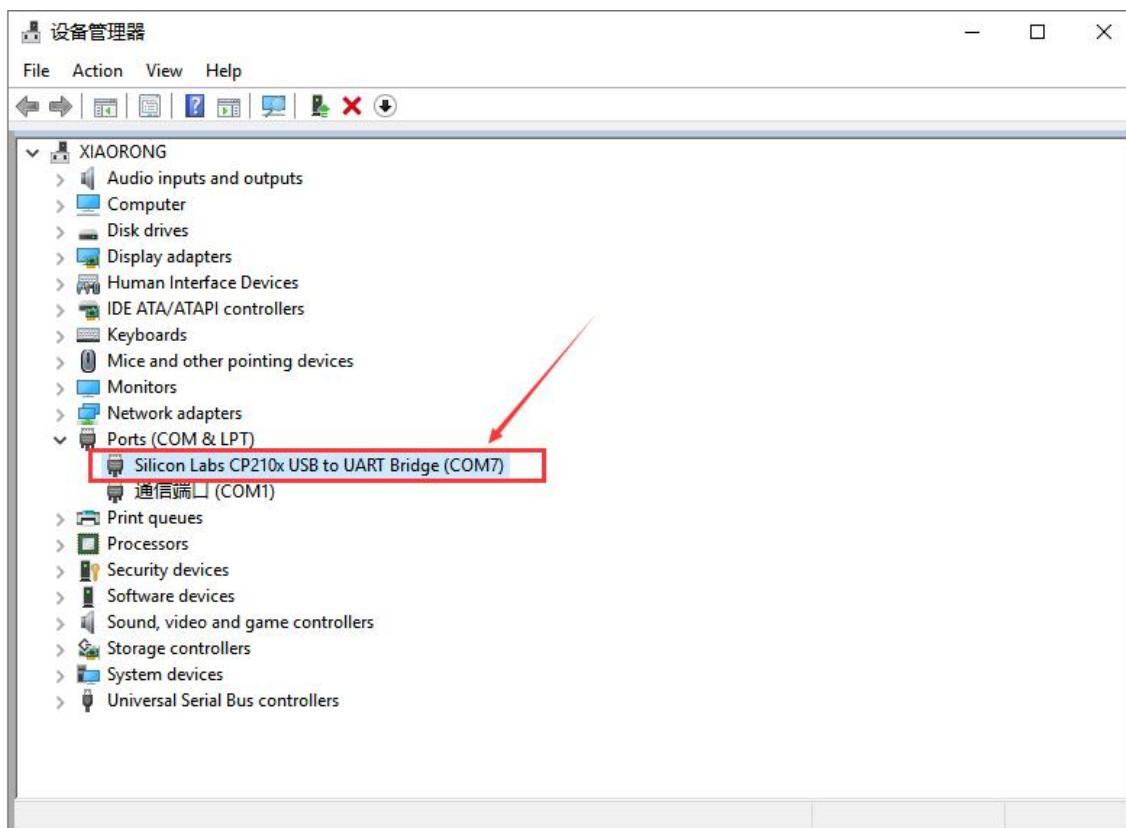
Click Arduino icon, and open Arduino IDE.

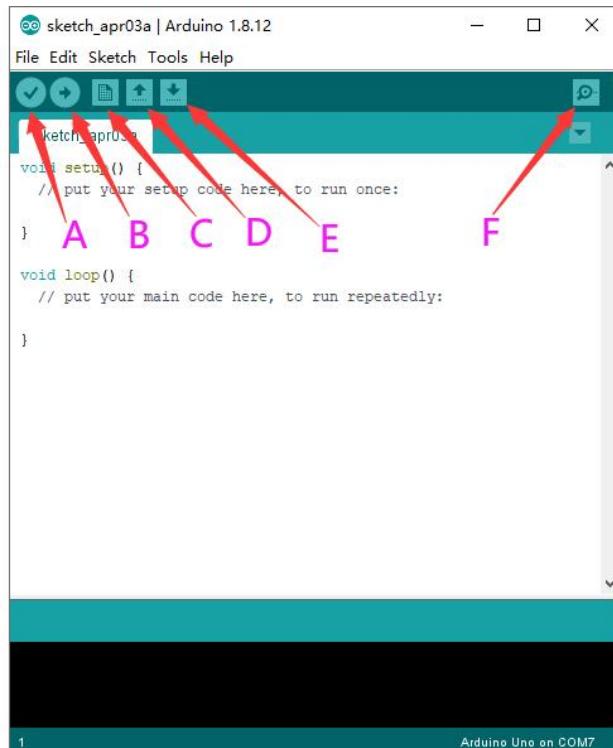
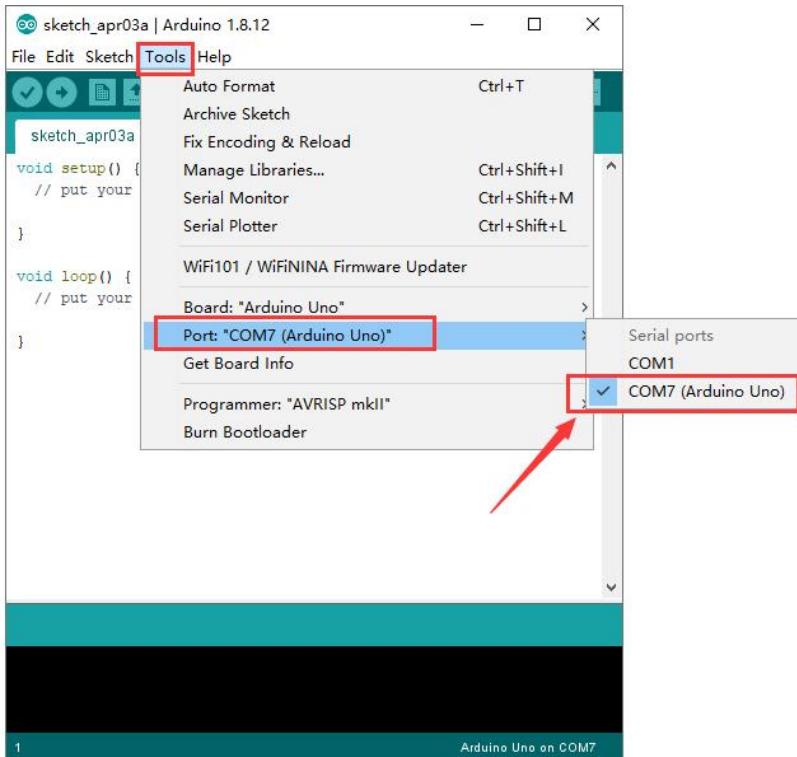


When downloading the sketch to the board, you must select the correct name of Arduino board that matches the board connected to your computer. As shown below;



Then select the correct COM port (you can see the corresponding COM port after the driver is successfully installed)





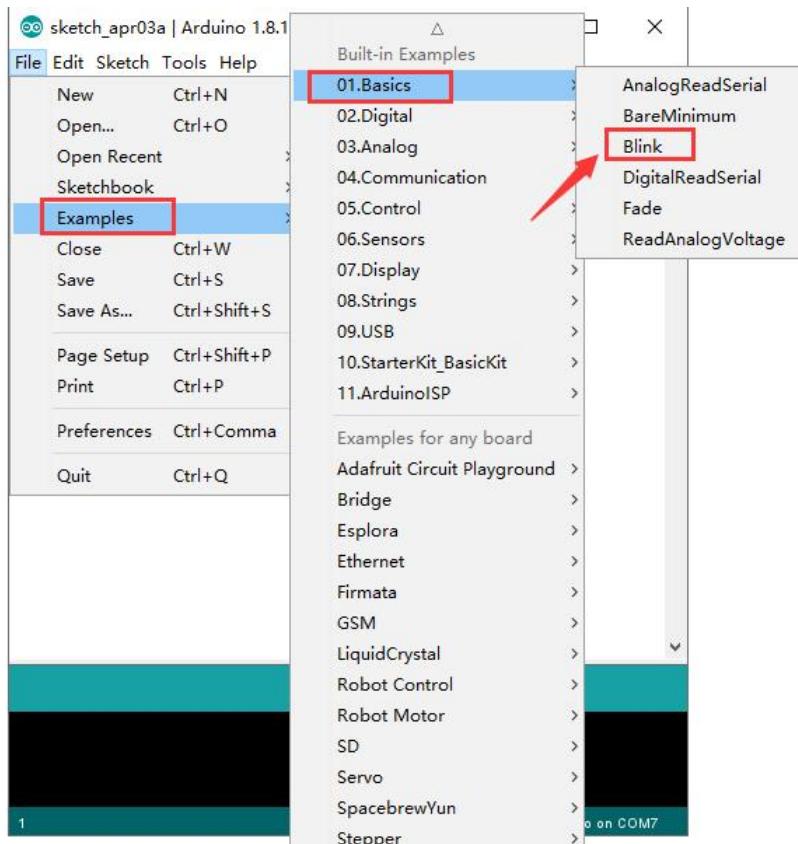
A- Used to verify whether there is any compiling mistakes or not.



- B- Used to upload the sketch to your Arduino board.
- C- Used to create shortcut window of a new sketch.
- D- Used to directly open an example sketch.
- E- Used to save the sketch.
- F- Used to send the serial data received from board to the serial monitor.

(5) Start Your First Program

Open the file to select **Example**, and click **BASIC>BLINK**, as shown below:





```
Sketch: 1
```

```
Blink | Arduino 1.8.12
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
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 t
  delay(1000);                      // wait for a second
  digitalWrite(LED_BUILTIN, LOW);     // turn the LED off by making
  delay(1000);                      // wait for a second
}
```

Arduino Uno on COM7

Set the correct **COM port**, and the corresponding board and COM port are shown on the lower right of IDE.



Blink | Arduino 1.8.12

File Edit Sketch Tools Help

Blink

This example code is in the public domain.

<http://www.arduino.cc/en/Tutorial/Blink>

```
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  digitalWrite(LED_BUILTIN, LOW);     // turn the LED off by making
  delay(1000);                      // wait for a second
}
```

1 Arduino Uno on COM7

Click to start compiling the program, and check errors.



```
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
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  digitalWrite(LED_BUILTIN, LOW);     // turn the LED off by making
  delay(1000);                      // wait for a second
}

```

Done compiling.

Sketch uses 924 bytes (2%) of program storage space. Maximum is 32256 bytes. Global variables use 9 bytes (0%) of dynamic memory, leaving 2039 bytes for local variables.

1 Arduino Uno on COM7

Click to upload the program

```
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
void setup() {
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  delay(1000);                      // wait for a second
}

```

Done uploading.

Sketch uses 924 bytes (2%) of program storage space. Maximum is 32256 bytes. Global variables use 9 bytes (0%) of dynamic memory, leaving 2039 bytes for local variables.

1 Arduino Uno on COM7

After the program is uploaded successfully, the onboard LED blinks.

Congratulation, you finish the first program.

6. Add Libraries

(1) 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 LiquidCrystal library helps talk to LCD displays. There are hundreds of additional libraries available on the Internet for download.

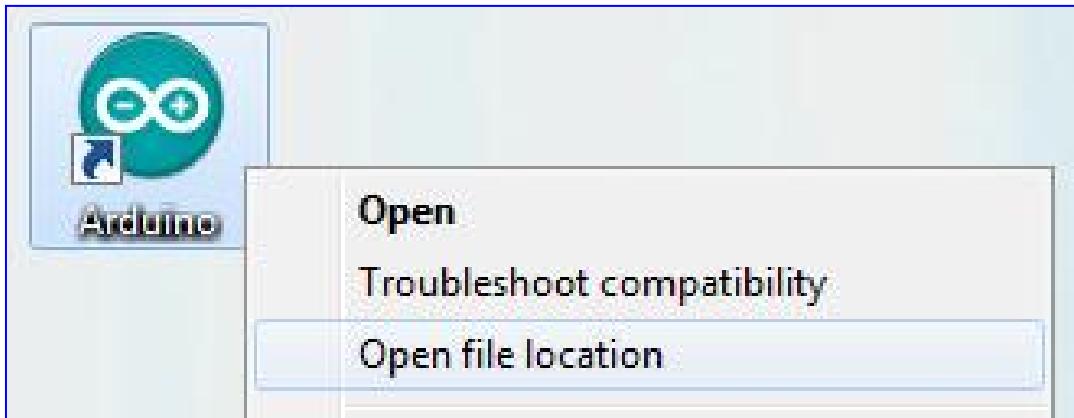
The built-in libraries and some of these additional libraries are listed in the reference.

(2) How to Install a Library ?

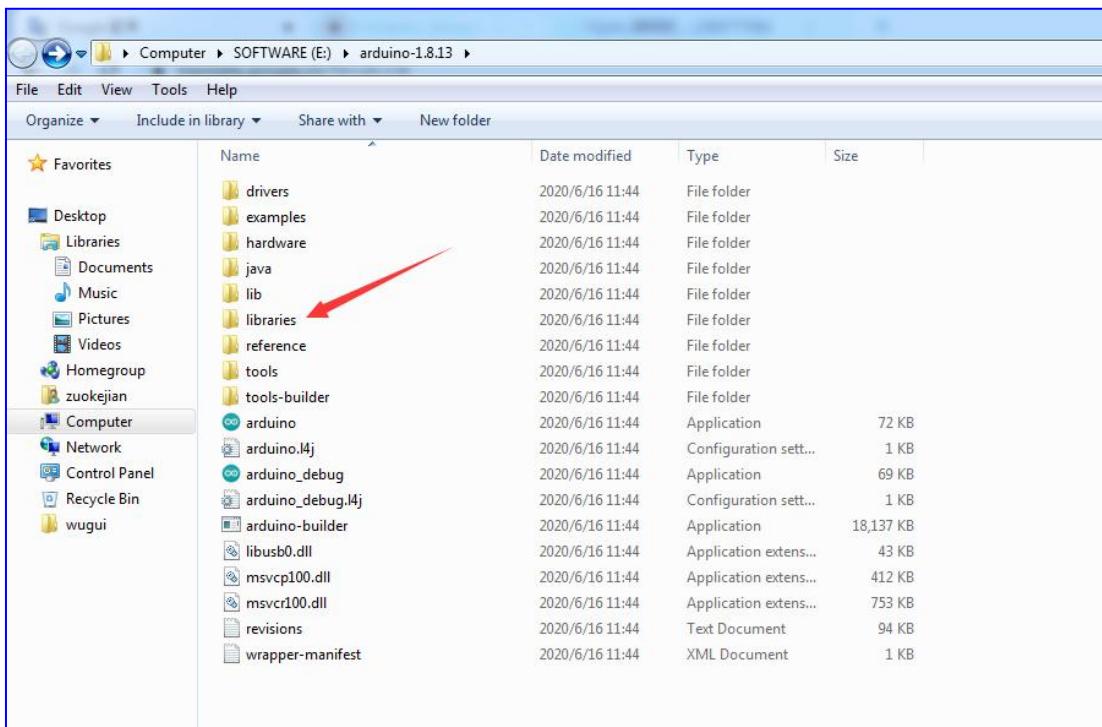
Here we will introduce the most simple way for you to add libraries .

Step 1 : After downloading well the Arduino IDE, you can right-click the icon of Arduino IDE.

Find the option "Open file location" shown as below:



Step 2: Enter app to find out libraries folder, this folder is the library file of Arduino.



Step 3: Next to find out the “libraries” folder of 4DOF robot arm smart car (seen in the link: <https://fs.keyestudiocom/KS0520>), you just need to replicate and paste it into the libraries folder of Arduino IDE.



📁 > KS0520 keyestudio 4 DOF Mechanical Robotic Arm Car Learning Kit

Overview

Click here to describe this folder and turn it into a Space

Show examples

Create new file ▾

Name	Modified	Members
1. about keyestudio	--	Only you
2. about this kit	--	Only you
3. Tutorial for arduino	--	Only you
4. assembly	--	Only you
5. APP	--	Only you



📁 > 3. Tutorial for arduino

Overview

Click here to describe this folder and turn it into a Space

Show examples

Create new file ▾

Name	Modified	Members
1. Arduino software	--	Only you
2. Getting started with arduino	--	Only you
3. Tutorial	--	Only you
4. ARDUINO Code	--	Only you
5. Libraries	--	Only you



3. Tutorial for arduino > 5. Libraries

Overview

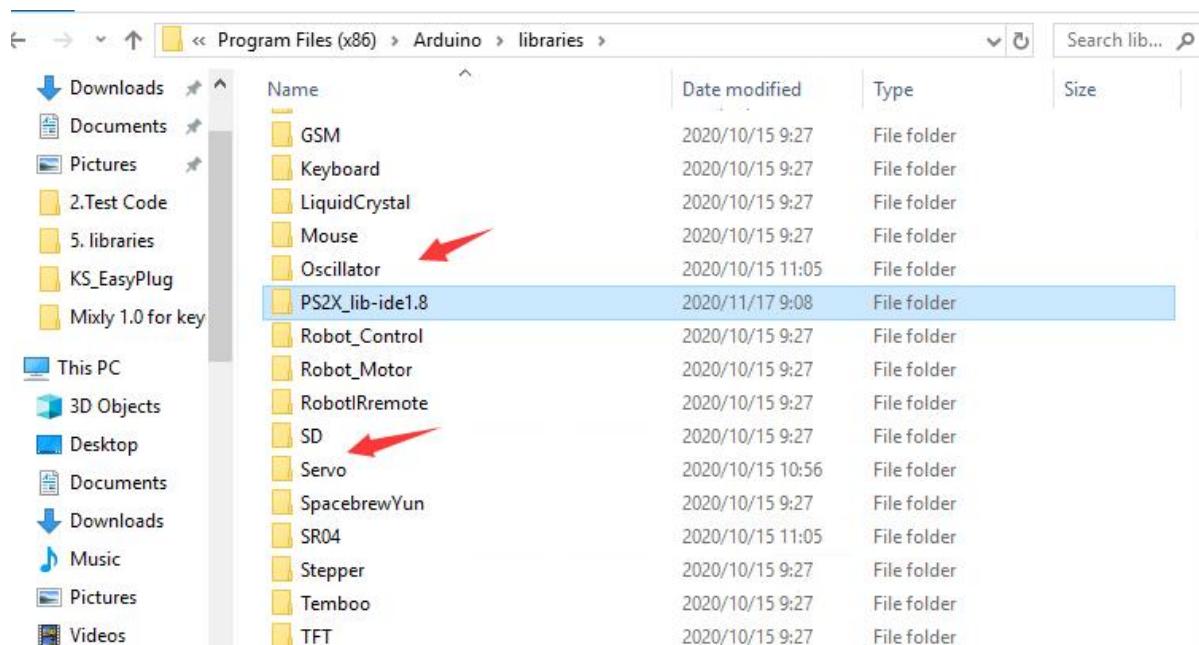
Click here to describe this folder and turn it into a Space

Show examples

Name	Modified	Members
PS2X_lib-ide1.8	--	Only you
Servo	--	Only you

Copy the above libraries into libraries folder of Arduino.

Then the libraries of robot arm car are installed successfully, as shown below:



7. Projects

Project 1 LED Light

(1) Description



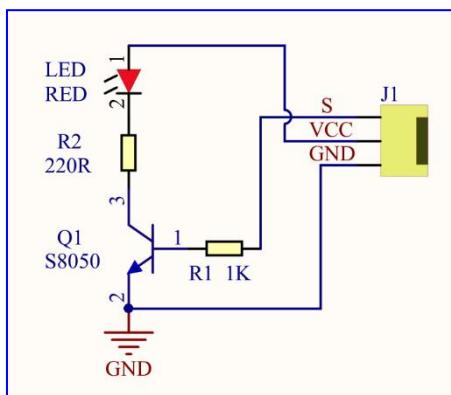
For the starter and enthusiast, this is a fundamental program---LED Blink. LED, the abbreviation of light emitting diodes, consist of Ga, As, P, N chemical compound and so on. The LED can flash diverse colors by altering the delay time in the test code. When in control, power on GND and VCC, the LED will be on if S end is high level; nevertheless, it will go off.

(2) What You Need



Control Board *1	Motor Shield*1	LED module *1	Battery Holder *1	USB Cable *1	3pin Dupont line *1

(3) Specification



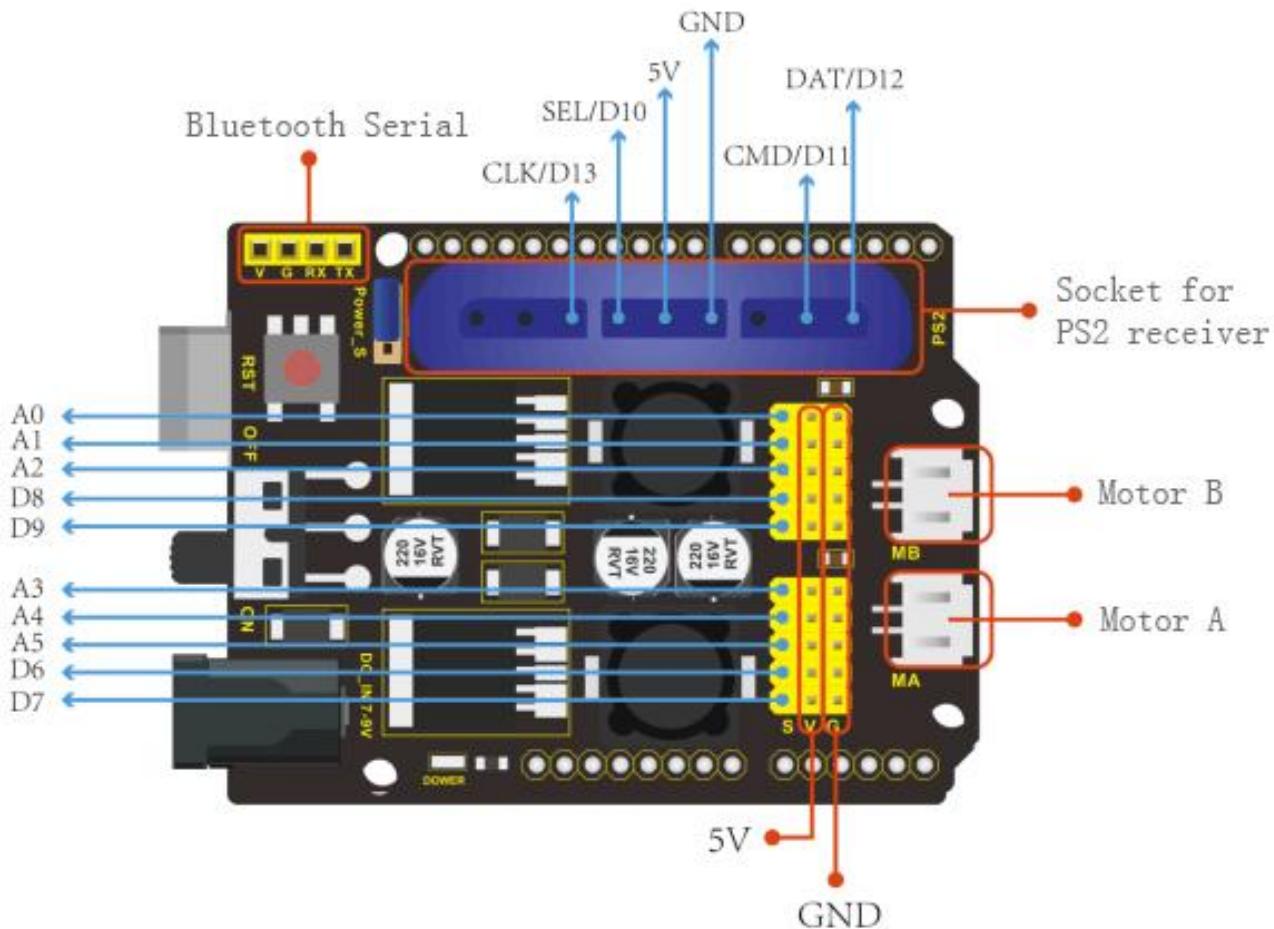
Control interface: digital port

Working voltage: DC 3.3-5V

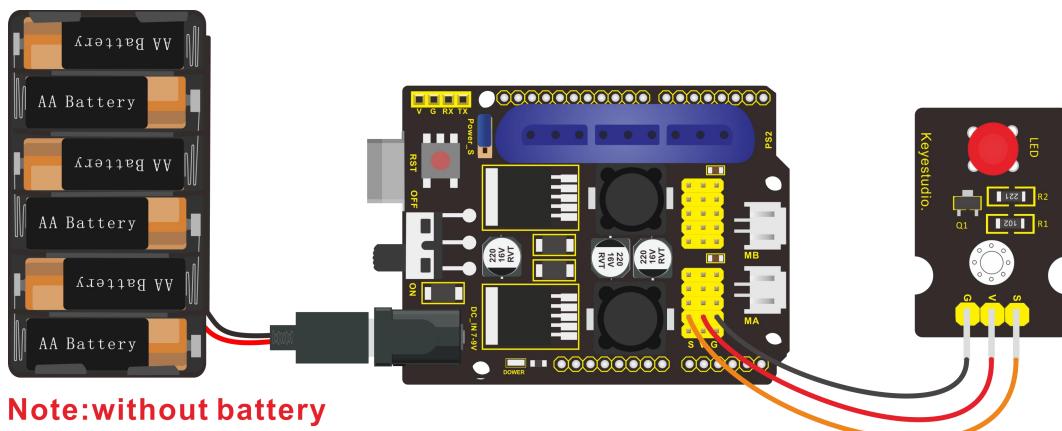
Pin spacing: 2.54mm

LED display color: red

(4) Pins of Motor Driver Shield



(5) Connection Diagram:



The pin -, + and S are connected to G(GND), V(5V) and S(D6) of shield.

(6) Test Code:

```
/*
KEYESTUDIO 4DOF Mechanical Robot Arm Car
lesson 1.1
Blink
http://www.keyestudiocom
*/
int ledPin=6;// Define the LED pin at D6
void setup()
{
    pinMode(ledPin, OUTPUT);// initialize ledpin as an output.
}
void loop() // the loop function runs over and over again forever
{
    digitalWrite(ledPin, HIGH); // turn the LED on (HIGH is the voltage level)
    delay(1000); // wait for a second
    digitalWrite(ledPin, LOW); // turn the LED off by making the voltage LOW
    delay(1000); // wait for a second
}
```

(7) Test Result:

Upload the program, LED flickers with the interval of 1s.

(8) Code Explanation:

pinMode(ledPin, OUTPUT) - This function denotes that the pin is INPUT or OUTPUT.

digitalWrite(ledPin , HIGH) - When pin is OUTPUT, we can set it to HIGH(output 5V) or LOW(output 0V)

(9) Code Explanation:

We succeed to blink LED. Next, let's observe what LED will change if we modify pins and delay time.

```
/*
```

KEYESTUDIO 4DOF Mechanical Robot Arm Car

lesson 1.2

Blink

<http://www.keyestudiocom>

```
*/
```



```
int ledPin=6;// Define the LED pin at D6
void setup()
{
    pinMode(ledPin, OUTPUT);// initialize ledpin as an output.
}
void loop() // the loop function runs over and over again forever
{
    digitalWrite(ledPin, HIGH); // turn the LED on (HIGH is the voltage level)
    delay(100); // wait for 0.1 second
    digitalWrite(ledPin, LOW); // turn the LED off by making the voltage LOW
    delay(100); // wait for 0.1 second
}
```

The LED flickers faster through the test result, therefore, delaying time could affect flash frequency.

Project 2: Adjust LED Brightness

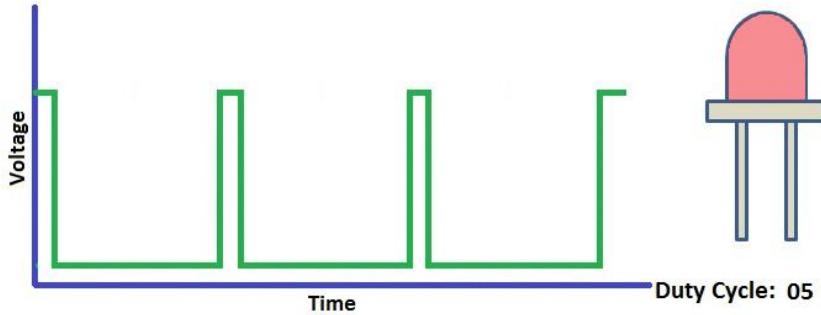


(1) Description:

In previous lesson, we control LED on and off and make it blink.

In this project, we will control LED brightness through PWM to simulate breathing effect. Similarly, you can change the step length and delay time in the code so as to demonstrate different breathing effect.

PWM is a means of controlling the analog output via digital means. Digital control is used to generate square waves with different duty cycles (a signal that constantly switches between high and low levels) to control the analog output. In general, the input voltage of port are 0V and 5V. What if the 3V is required? Or what if switch among 1V, 3V and 3.5V? We can't change resistor constantly. For this situation, we need to control by PWM.



For the Arduino digital port voltage output, there are only LOW and HIGH, which correspond to the voltage output of 0V and 5V. You can define LOW as 0 and HIGH as 1, and let the Arduino output five hundred 0 or 1 signals within 1 second.

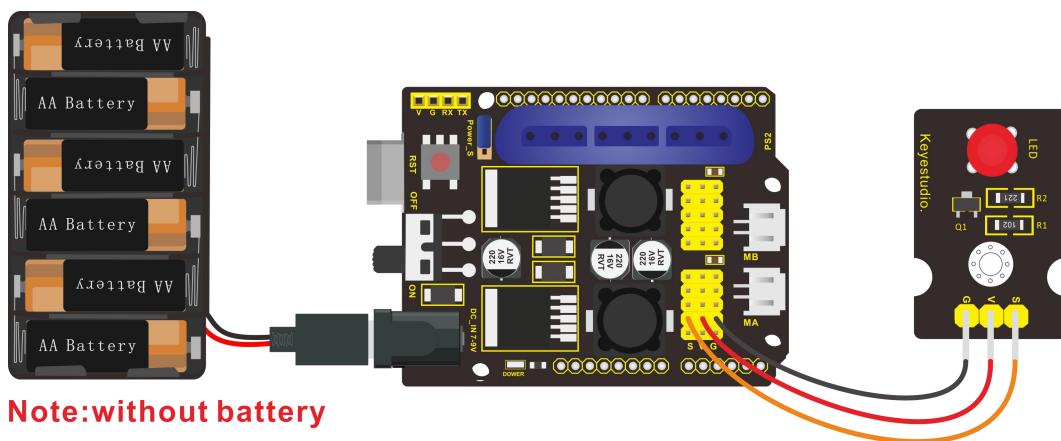
If output five hundred 1, that is 5V; if all of which is 1, that is 0V. If output 010101010101 in this way then the output port is 2.5V, which is like showing movie. The movie we watch are not completely continuous. It actually outputs 25 pictures per second. In this case, the human can't tell it, neither does PWM. If want different voltage, need to control the ratio of 0 and 1. The more 0,1 signals output per unit time, the more accurately control.

(2) What You Need



Control Board *1	Motor Shield*1	LED module *1	Battery Holder *1	USB Cable *1	3pin Dupont line *1

(3) Connection Diagram:



(4) Test Code:

```
/*
KEYESTUDIO 4DOF Mechanical Robot Arm Car
lesson 2.1
pwm
http://www.keyestudiocom
*/
int ledPin = 6; // Define the LED pin at D6
int value;
```



```
void setup () {  
    pinMode (ledPin, OUTPUT); // initialize ledpin as an output.  
}  
  
void loop () {  
    for (value = 0; value <255; value = value + 1) {  
        analogWrite (ledPin, value); // LED lights gradually light up  
        delay (5); // delay 5MS  
    }  
    for (value = 255; value> 0; value = value-1) {  
        analogWrite (ledPin, value); // LED gradually goes out  
        delay (5); // delay 5MS  
    }  
}
```

(5) Test Result:

When the test code is uploaded successfully, LED will smoothly change its brightness from dark to bright and back to dark, continuing to do so, which is similar to a lung breathing in and out.

(6) Code Explanation



When we need to repeat some statements, we could use FOR statement.

FOR statement format is shown below:

```
①           ② condition is true  ④  
for (cycle initialization; cycle condition; cycle adjustment statement) {  
③ loop body statement;  
}
```

FOR cyclic sequence:

Round 1: 1 → 2 → 3 → 4

Round 2: 2 → 3 → 4

...

Until number 2 is not established, “for” loop is over,

After knowing this order, go back to code:

```
for (int value = 0; value < 255; value=value+1){
```

```
...}
```

```
for (int value = 255; value >0; value=value-1){
```

```
...}
```

The two “for” statements make value increase from 0 to 255, then reduce from 255 to 0, then increase to 255,...infinitely loop

There is a new function in the following ----- analogWrite()

We know that digital port only has two state of 0 and 1. So how to send an analog value to a digital value? Here, this function is needed. Let's observe



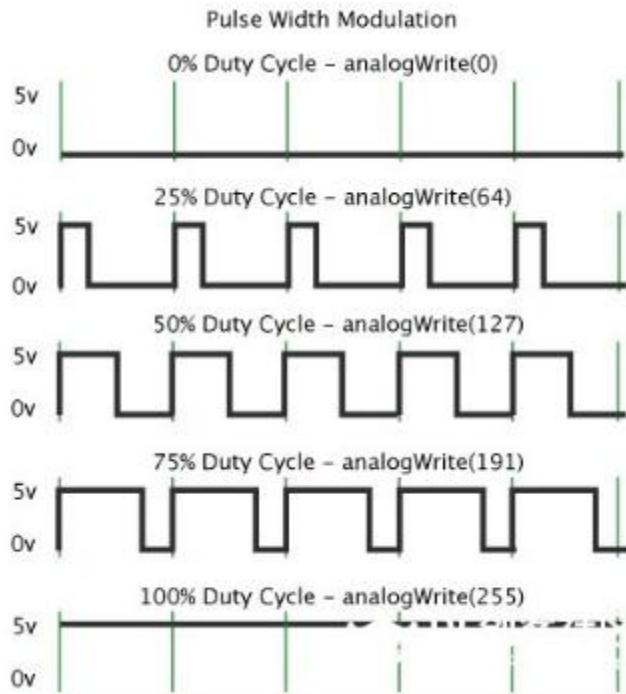
the Arduino board and find 6 pins marked “~” which can output PWM signals.

Function format as follows:

analogWrite(pin,value)

analogWrite() is used to write an analog value from 0~255 for PWM port, so the value is in the range of 0~255. Attention that you only write the digital pins with PWM function, such as pin 3, 5, 6, 9, 10, 11.

PWM is a technology to obtain analog quantity through digital method. Digital control forms a square wave, and the square wave signal only has two states of turning on and off (that is, high or low levels). By controlling the ratio of the duration of turning on and off, a voltage varying from 0 to 5V can be simulated. The time turning on(academically referred to as high level) is called pulse width, so PWM is also called pulse width modulation. Through the following five square waves, let's learn more about PWM.



In the above figure, the green line represents a period, and value of `analogWrite()` corresponds to a percentage which is called Duty Cycle as well. Duty cycle implies that high-level duration is divided by low-level duration in a cycle. From top to bottom, the duty cycle of first square wave is 0% and its corresponding value is 0. The LED brightness is lowest, that is, turn off. The more time high level lasts, the brighter the LED. Therefore, the last duty cycle is 100%, which correspond to 255, LED is brightest. 25% means darker.

PWM mostly is used for adjusting the LED brightness or rotation speed of motor.

It plays vital role in controlling smart robot car. I believe that you can't wait to enter next project.

(7) Extension Practice:

Let's modify the value of delay time and remain the pin unchanged, then observe how LED changes.

```
/*
KEYESTUDIO 4DOF Mechanical Robot Arm Car
lesson 2.2
pwm
http://www.keyestudiocom
*/
int ledPin = 6; // Define the LED pin at D6
void setup(){
    pinMode (ledPin, OUTPUT); // initialize ledpin as an output.
}
void loop(){
    for (int value = 0; value <255; value = value + 1){
        analogWrite (ledPin, value); // LED lights gradually light up
        delay (30); // delay 30MS
    }
    for(int value=255; value>0;value=value-1){
        analogWrite (ledPin, value); // LED gradually goes out
    }
}
```



```
delay (30); // delay 30MS  
}  
}//*****
```

LED flickers more slowly.

Project 3 Servo Control

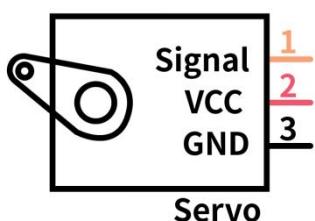


(1) Description

Servo motor is a position control rotary actuator. It mainly consists of housing, circuit board, core-less motor, gear and position sensor. Its working principle is that the servo receives the signal sent by MCU or receiver and produces a reference signal with a period of 20ms and width of 1.5ms, then compares the acquired DC bias voltage to the voltage of the potentiometer and obtain the voltage difference output.

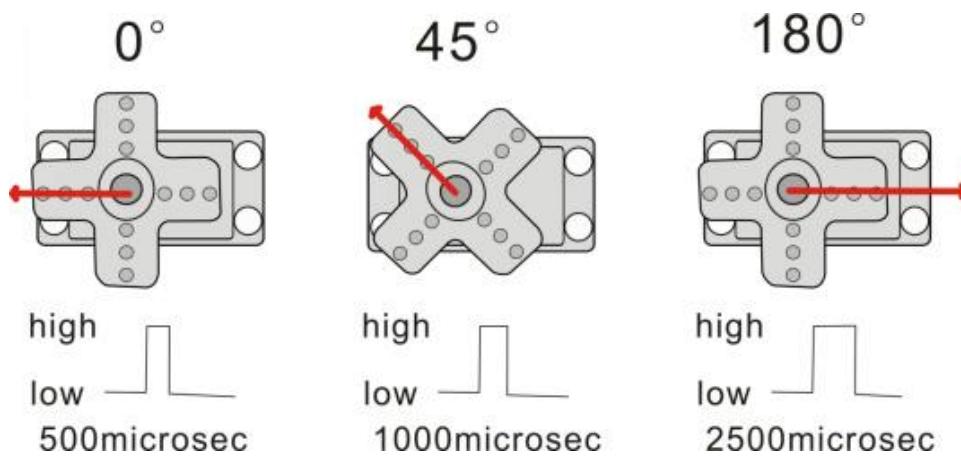
When the motor speed is constant, the potentiometer is driven to rotate through the cascade reduction gear, which leads that the voltage difference is 0, and the motor stops rotating. Generally, the angle range of servo rotation is 0° -- 180°

The rotation angle of servo motor is controlled by regulating the duty cycle of PWM (Pulse-Width Modulation) signal. The standard cycle of PWM signal is 20ms (50Hz). Theoretically, the width is distributed between 1ms-2ms, but in fact, it's between 0.5ms-2.5ms. The width corresponds the rotation angle from 0° to 180° . But note that for different brand motor, the same signal may have different rotation angle.



In general, servo has three lines in brown, red and orange. Brown wire is

grounded, red one is positive pole line and orange one is signal line.



The corresponding servo angles are shown below:

High level time	Servo angle
0.5ms	0 degree
1ms	45 degree
1.5ms	90 degree
2ms	135 degree
2.5ms	180 degree

(2) Specification

Working voltage: DC 4.8V ~ 6V

Operating angle range: about 180 ° (at 500 → 2500 μsec)

Pulse width range: 500 → 2500 μsec

No-load speed: 0.12 ± 0.01 sec / 60 (DC 4.8V) 0.1 ± 0.01 sec / 60 (DC 6V)



No-load current: $200 \pm 20\text{mA}$ (DC 4.8V) $220 \pm 20\text{mA}$ (DC 6V)

Stopping torque: $1.3 \pm 0.01\text{kg} \cdot \text{cm}$ (DC 4.8V) $1.5 \pm 0.1\text{kg} \cdot \text{cm}$ (DC 6V)

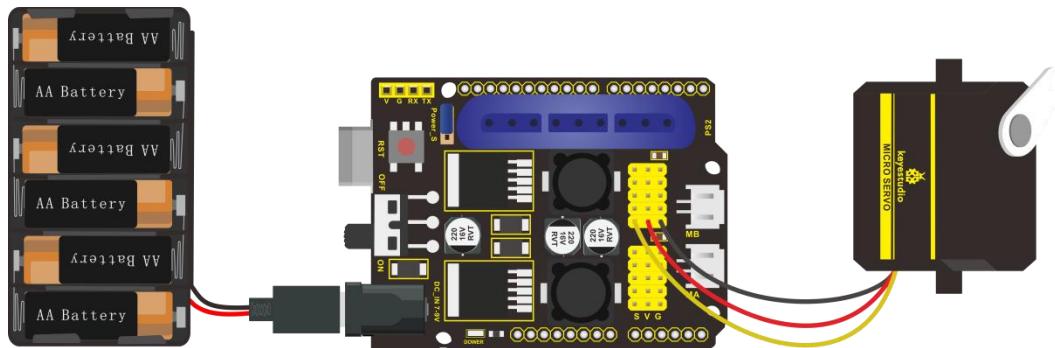
Stop current: $\leq 850\text{mA}$ (DC 4.8V) $\leq 1000\text{mA}$ (DC 6V)

Standby current: $3 \pm 1\text{mA}$ (DC 4.8V) $4 \pm 1\text{mA}$ (DC 6V)

(3) What You Need

Control Board *1	Motor Shield*1	Servo motor *1	Battery Holder *1	USB Cable *1

(4) Connection Diagram:



Note:without battery

Wiring note: the brown wire of servo is linked with Gnd(G), the red one is connected to 5v(V) and orange one is attached to digital 9.

The servo has to be connected to external power due to its high demand for driving servo current. Generally, the current of development board is not enough. If without connected power, the development board could be burnt.

(5) Test Code:

```
/*
keyestudio 4DOF Robot Arm Car
lesson 3.1

Servo

http://www.keyestudio.com

*/
#define servoPin 9 //servo Pin
int pos; //angle variable of servo
int pulsewidth; //pulsewidth variable of servo
void setup() {
    pinMode(servoPin, OUTPUT); //set pins of servo to output
    procedure(0); //set angle of servo to 0°
}
```



```
void loop() {  
    for (pos = 0; pos <= 180; pos += 1) { // goes from 0 degrees to 180  
        degrees  
        // in steps of 1 degree  
        procedure(pos); // tell servo to go to position in variable  
        'pos'  
        delay(15); //control the rotation speed of servo  
    }  
    for (pos = 180; pos >= 0; pos -= 1) { // goes from 180 degrees to 0  
        degrees  
        procedure(pos); // tell servo to go to position in variable  
        'pos'  
        delay(15);  
    }  
    //Function to control servo  
    void procedure(int myangle) {  
        pulsewidth = myangle * 11 + 500; //Calculate pulsewidth value  
        digitalWrite(servoPin,HIGH);  
        delayMicroseconds(pulsewidth); //the duration of high levle is  
        pulsewidth  
        digitalWrite(servoPin,LOW);  
        delay((20 - pulsewidth / 1000)); //the period is 20ms, low levle lasts the
```



rest of time

```
}//*****
```

```
*****
```

After the code is uploaded successfully, servo swings forth and back in the range of 0° to 180°

There is another guide for restraining servo---- servo library file, the following link of official website is as for your reference.

<https://www.arduino.cc/en/Reference/Servo>

(6) Test Code2:

```
/*
```

KEYESTUDIO 4DOF Mechanical Robot Arm Car

lesson 3.2

servo

<http://www.keyestudiocom>

```
*/
```

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

```
Servo myservo; // create servo object to control a servo
```

```
// twelve servo objects can be created on most boards
```

```
int pos = 0;      // variable to store the servo position

void setup() {
    myservo.attach(9); // attaches the servo on pin 9 to the servo object
}

void loop() {
    for (pos = 0; pos <= 180; pos += 1) { // goes from 0 degrees to 180
        degrees
        // in steps of 1 degree
        myservo.write(pos);           // tell servo to go to position in
        variable 'pos'
        delay(15);                  // waits 15ms for the servo to reach
        the position
    }

    for (pos = 180; pos >= 0; pos -= 1) { // goes from 180 degrees to 0
        degrees
        myservo.write(pos);           // tell servo to go to position in
        variable 'pos'
        delay(15);                  // waits 15ms for the servo to reach
        the position
    }
} //*****
```

**

(7) Test Result:

Upload code successfully and power on, servo swings in the range of 0° to 180°. The result is same. We usually control it by library file.

(8) Code Explanation:

Arduino comes with **#include <Servo.h>** (servo function and statement)

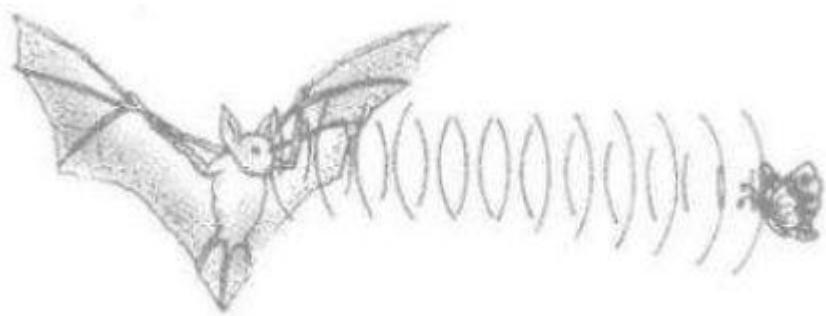
The following are some common statements of the servo function:

1. **attach (interface)** ——Set servo interface, port 9 and 10 are available
2. **write (angle)** ——The statement to set rotation angle of servo, the angle range is from 0° to 180°
3. **read ()** ——used to read angle of servo, read the command value of “write()”
4. **attached ()** ——Judge if the parameter of servo is sent to its interface

Note: The above written format is “servo variable name, specific statement

() ” , for instance: myservo.attach(9)

Project 4 Ultrasonic Sensor



(1) Description:



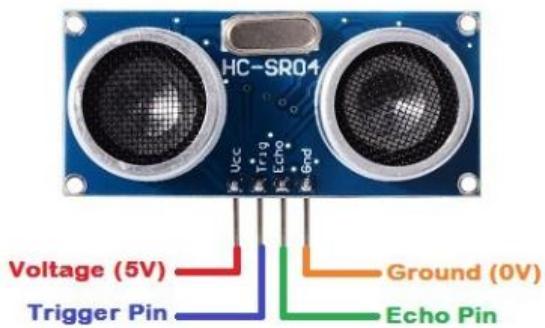
The HC-SR04 ultrasonic sensor uses sonar to determine distance to an object like bats do. It offers excellent non-contact range detection with high accuracy and stable readings in an easy-to-use package. It comes complete with ultrasonic transmitter and receiver modules.

The HC-SR04 or the ultrasonic sensor is being used in a wide range of electronics projects for creating obstacle detection and distance measuring application as well as various other applications. Here we have brought the



simple method to measure the distance with arduino and ultrasonic sensor and how to use ultrasonic sensor with arduino.

Ultrasonic Sensor Pinout



(2) Specification:

Power Supply :+5V DC

Quiescent Current : <2mA

Working Current: 15mA

Effectual Angle: <15°

Ranging Distance : 2cm – 400 cm

Resolution : 0.3 cm

Measuring Angle: 30 degree

Trigger Input Pulse width: 10uS

(3) What You Need



Control Board *1	Motor Shield*1	Ultrasonic Module *1	Battery Holder *1	4pin Dupont line *1
				USB Cable *1

(4) The principle of ultrasonic sensor

As the above picture shown, it is like two eyes. One is transmitting end, the other is receiving end.

The ultrasonic module will emit the ultrasonic waves after trigger signal.

When the ultrasonic waves encounter the object and are reflected back, the module outputs an echo signal, so it can determine the distance of object from the time difference between trigger signal and echo signal.

The t is the time that emitting signal meets obstacle and returns.

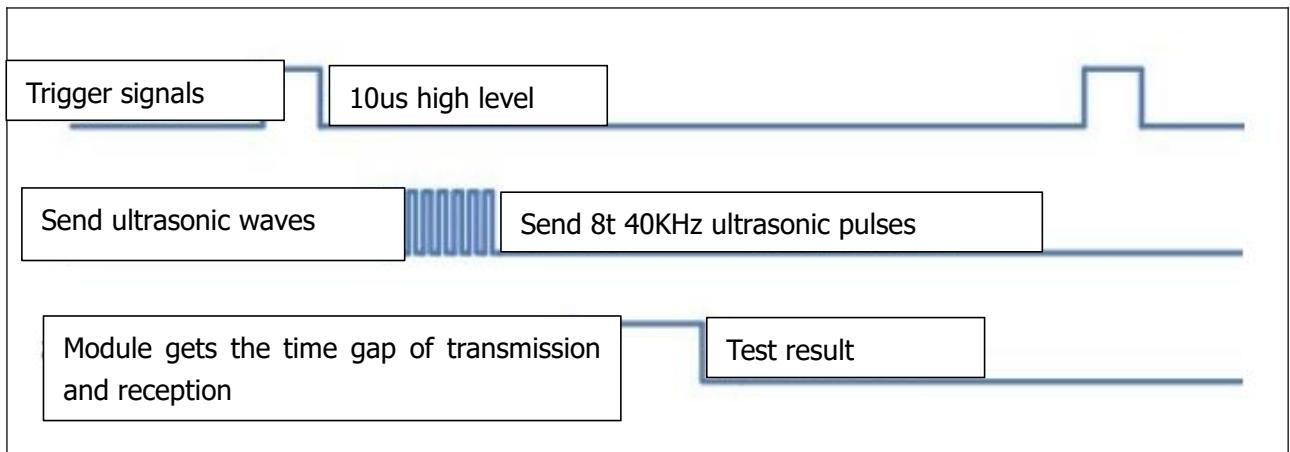
and the propagation speed of sound in the air is about 343m/s, therefore, $\text{distance} = \text{speed} * \text{time}$, because the ultrasonic wave emits and comes back, which is 2 times of distance, so it needs to be divided by 2, the distance measured by ultrasonic wave = $(\text{speed} * \text{time})/2$

1. Use method and timing chart of ultrasonic module:
2. Setting the delay time of Trig pin of SR04 to $10\mu\text{s}$ at least, which can trigger it to detect distance.
3. After triggering, the module will automatically send eight 40KHz

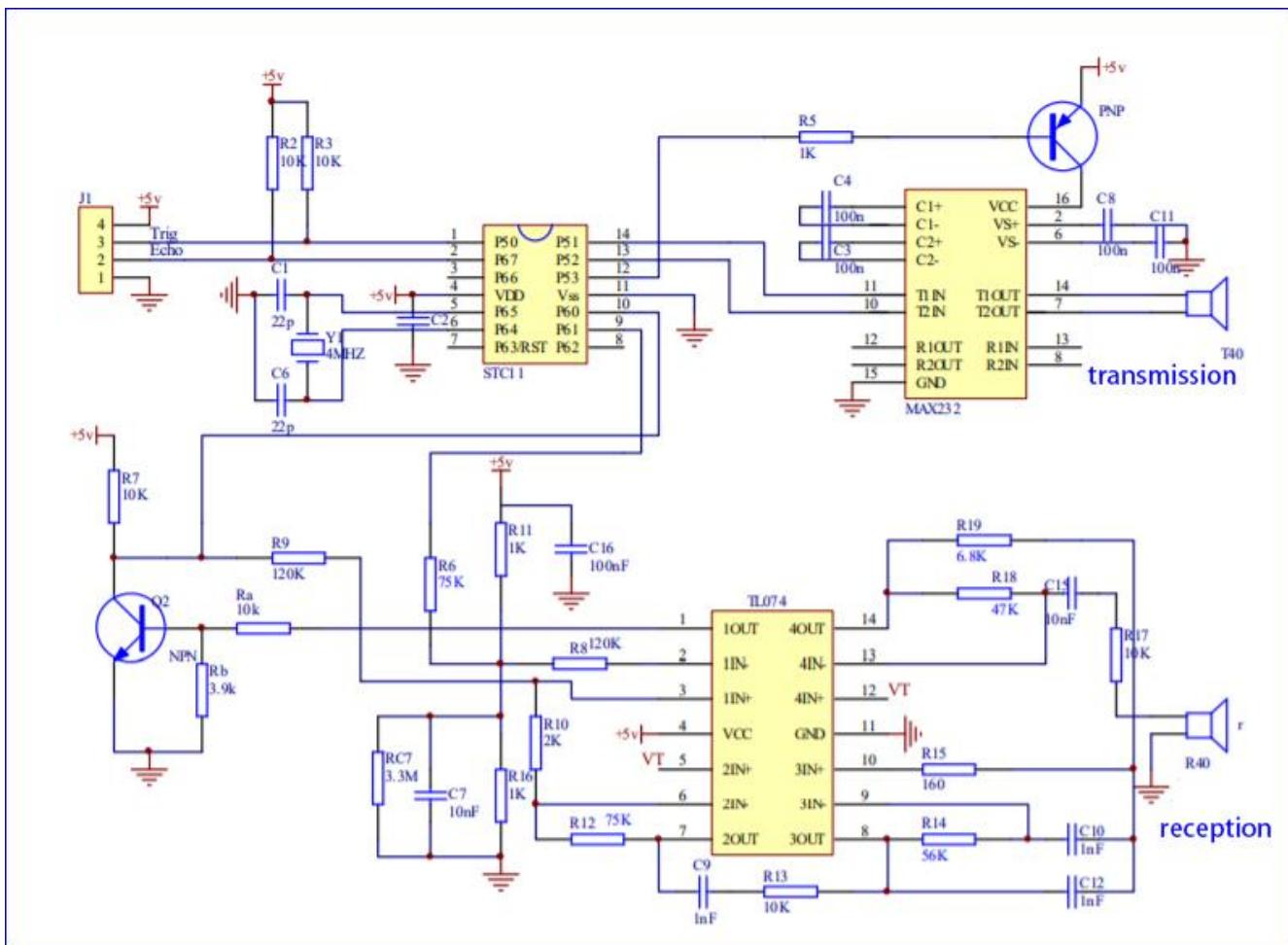


ultrasonic pulses and detect whether there is a signal return. This step will be completed automatically by the module.

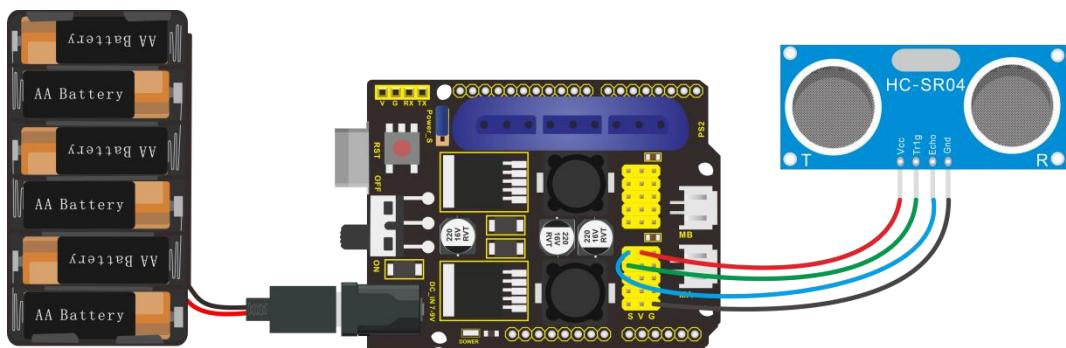
4. 3. If the signal returns, the Echo pin will output a high level, and the duration of the high level is the time from the transmission of the ultrasonic wave to the return.



Circuit diagram of ultrasonic sensor:



(5) Connection Diagram:



Note: without battery

Wiring Guide:

Ultrasonic sensor keyestudio V5 expansion board

VCC	→	5v(V)
Trig	→	A4(S)
Echo	→	A3(S)
Gnd	→	Gnd(G)

(6) Test Code:

```
/*
KEYESTUDIO 4wd Mechanical Robor Arm Car
lesson 4.1

Ultrasonic sensor

http://www.keyestudiocom

*/
int trigPin = A4;      // Trigger
int echoPin = A3;      // Echo
long duration, cm, inches;

void setup() {
    //Serial Port begin
    Serial.begin (9600);
    //Define inputs and outputs
```



```
pinMode(trigPin, OUTPUT);
pinMode(echoPin, INPUT);

}

void loop() {
    // The sensor is triggered by a HIGH pulse of 10 or more microseconds.
    // Give a short LOW pulse beforehand to ensure a clean HIGH pulse:
    digitalWrite(trigPin, LOW);
    delayMicroseconds(2);

    digitalWrite(trigPin, HIGH);
    delayMicroseconds(10);

    digitalWrite(trigPin, LOW);

    // Read the signal from the sensor: a HIGH pulse whose
    // duration is the time (in microseconds) from the sending
    // of the ping to the reception of its echo off of an object.
    duration = pulseIn(echoPin, HIGH);

    // Convert the time into a distance
    cm = (duration/2) / 29.1;      // Divide by 29.1 or multiply by 0.0343
    inches = (duration/2) / 74;     // Divide by 74 or multiply by 0.0135

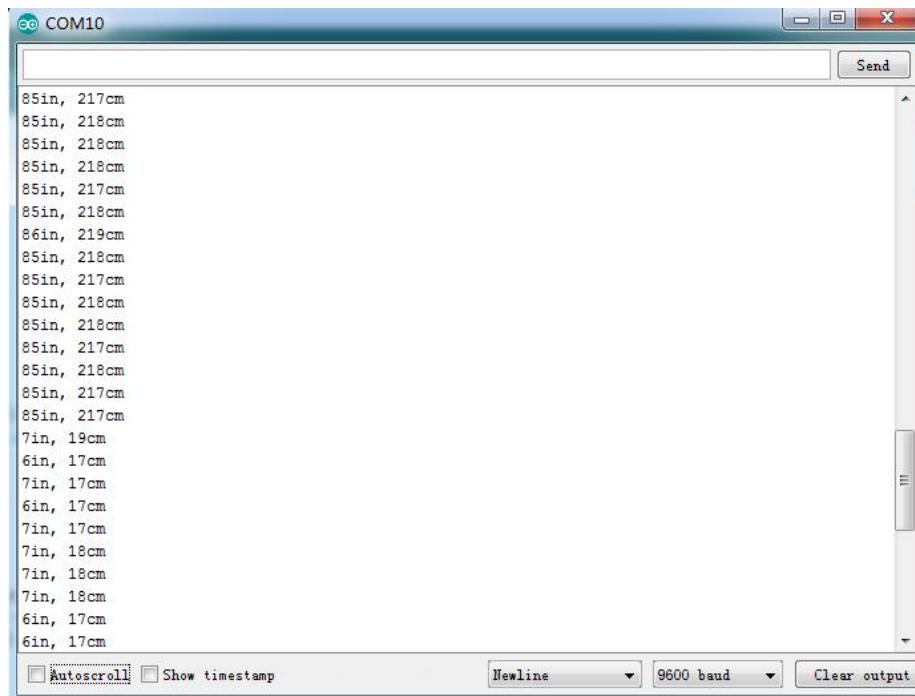
    Serial.print(inches);
    Serial.print("in, ");
    Serial.print(cm);
    Serial.print("cm");
```



```
Serial.println();  
delay(50);  
}  
//*****
```

(7) Test Result:

Upload test code on the development board, open serial monitor and set baud rate to 9600. The detected distance will be displayed(unit is cm and inch). Hinder the ultrasonic sensor by hand, then the displayed distance value gets smaller.



(8) Code Explanation:

int trigPin- this pin is defined to transmit ultrasonic waves, generally output.

int echoPin - this is defined as the pin of reception, generally input

cm = (duration/2) / 29.1-unit is cm

inches = (duration/2) / 74-unit is inch

We can calculate the distance by using the following formula:

distance = (traveltime/2) x speed of sound

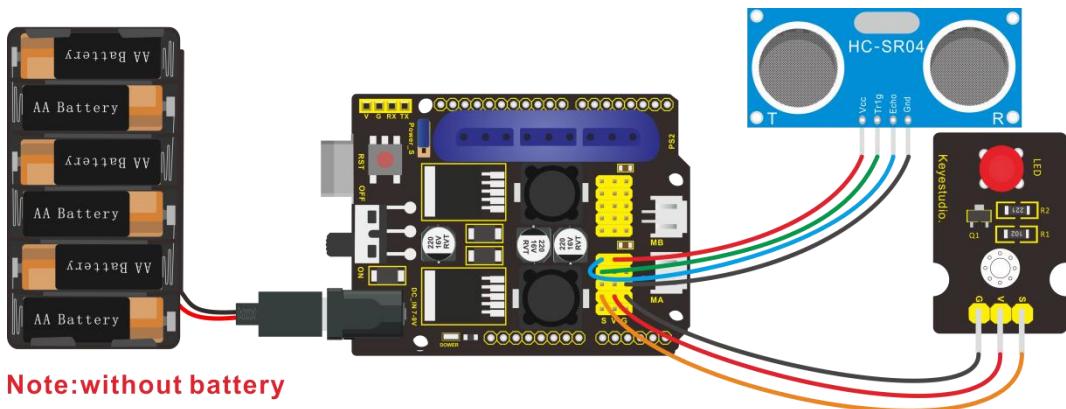
The speed of sound is: 343m/s = 0.0343 cm/uS = 1/29.1 cm/uS

Or in inches: 13503.9in/s = 0.0135in/uS = 1/74in/uS

We need to divide the traveltime by 2 because we have to take into account that the wave was sent, hit the object, and then returned back to the sensor.

(9) Extension Practice:

We have just measured the distance displayed by the ultrasonic. How about controlling the LED with the measured distance? Let's try it, connect an LED module to the D6 pin.



/*

KEYESTUDIO 4wdMechanical Robor Arm Car

lesson 4.2

Ultrasonic LED

<http://www.keyestudiocom>

*/

int trigPin = A4; // Trigger

int echoPin = A3; // Echo

long duration, cm, inches;

void setup() {

Serial.begin (9600); //Serial Port begin

pinMode(trigPin, OUTPUT); //Define inputs and outputs

pinMode(echoPin, INPUT);

pinMode(6, OUTPUT);

}

void loop()

```
{  
    // The sensor is triggered by a HIGH pulse of 10 or more microseconds.  
    // Give a short LOW pulse beforehand to ensure a clean HIGH pulse:  
    digitalWrite(trigPin, LOW);  
    delayMicroseconds(2);  
    digitalWrite(trigPin, HIGH);  
    delayMicroseconds(10);  
    digitalWrite(trigPin, LOW);  
    // Read the signal from the sensor: a HIGH pulse whose  
    // duration is the time (in microseconds) from the sending  
    // of the ping to the reception of its echo off of an object.  
    duration = pulseIn(echoPin, HIGH);  
    // Convert the time into a distance  
    cm = (duration/2) / 29.1;      // Divide by 29.1 or multiply by 0.0343  
    inches = (duration/2) / 74;    // Divide by 74 or multiply by 0.0135  
    Serial.print(inches);  
    Serial.print("in, ");  
    Serial.print(cm);  
    Serial.print("cm");  
    Serial.println();  
    delay(50);  
    if (cm>=2 && cm<=10)digitalWrite(6, HIGH);
```

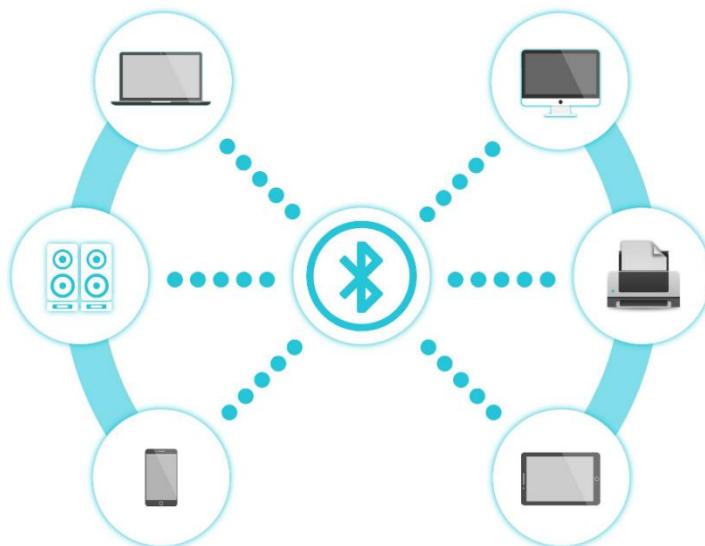
```
else digitalWrite(6, LOW);
}////////////////////////////////////////////////////////////////
```

Upload test code to development board and put your hand away from ultrasonic sensor for 2cm-10cm, then LED will be on.

Project 5 Bluetooth Remote Control

(1) Description:

Bluetooth is one of the most popular simple wireless communication modules in recent decades , which has been applied in most battery-powered devices due to its convenience.



Over the years, there have been many upgrades of Bluetooth standard to keep fulfil the demand of customers and technology according to the need of time and situation.

Over the few years, there are many things changed including data transmission rate, power consumption with wearable and IoT Devices and Security System.

Here we are going to learn about HM-10 BLE 4.0 with Arduino Board. The

HM-10 is a readily available Bluetooth 4.0 module. This module is used for establishing wireless data communication. The module is designed by using the Texas Instruments CC2540 or CC2541 Bluetooth low energy (BLE) System on Chip (SoC).

(2) Specification

Bluetooth protocol: Bluetooth

Specification V4.0 BLE

No byte limit in serial port Transceiving



In open environment, realize 100m ultra-distance communication with iphone4s

Working frequency: 2.4GHz ISM band

Modulation method: GFSK(Gaussian Frequency Shift Keying)

Transmission power: -23dbm, -6dbm, 0dbm, 6dbm, can be modified by AT command.

Sensitivity: $\leq -84\text{dBm}$ at 0.1% BER

Transmission rate: Asynchronous: 6K bytes ; Synchronous: 6k Bytes

Security feature: Authentication and encryption

Supporting service: Central & Peripheral UUID FFE0, FFE1

Power consumption: Auto sleep mode, stand by current 400uA~800uA, 8.5mA during transmission.

Power supply: 5V DC

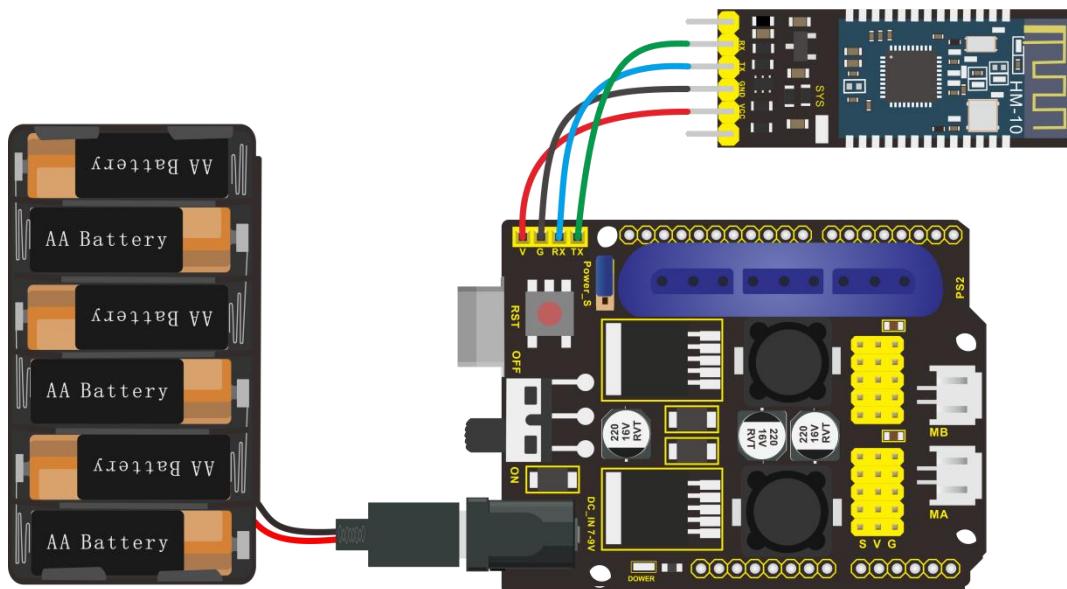


Working temperature: -5 to +65 Centigrade

(3) What You Need:

Control Board *1	Motor Shield*1	Bluetooth Module *1	Battery Holder *1	USB Cable *1

(3) Connection Diagram:



Note:without battery

Wiring Guide

Bluetooth Module

VCC

GND

Expansion Board

VCC

GND

TXD	RXD
RXD	TXD

Note: don't insert Bluetooth module reversely.

(4) Test Code:

```
/*
KEYESTUDIO 4DOF Mechanical Robot Arm Car
lesson 5
Bluetooth
http://www.keyestudiocom
*/
char blue_val; //define a variable to receiver Bluetooth signals
void setup() {
    Serial.begin(9600); //set baud rate to 9600
}
void loop() {
    if(Serial.available() > 0)//receive Bluetooth signals
```

```
{  
    blue_val = Serial.read(); //Reception  
    Serial.println(blue_val); //Serial prints Bluetooth signals  
}  
}
```

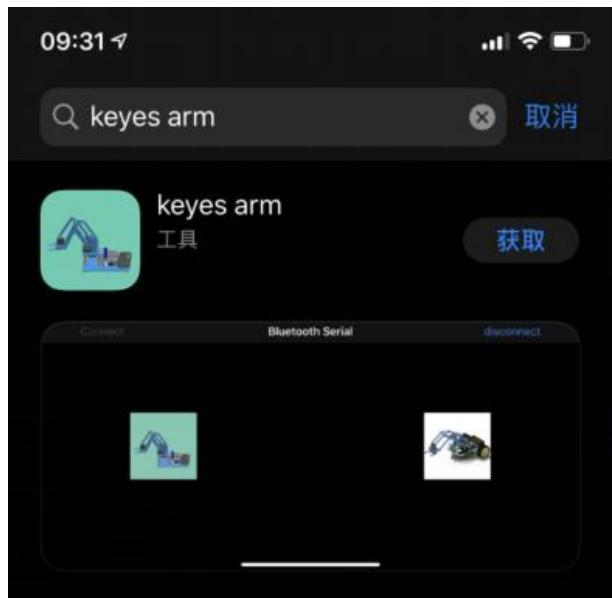
(5) Download APP:

The code is the signals received by serial port, we still need to send signals, hence the need of app which sends signals to Bluetooth module to print them on serial port.

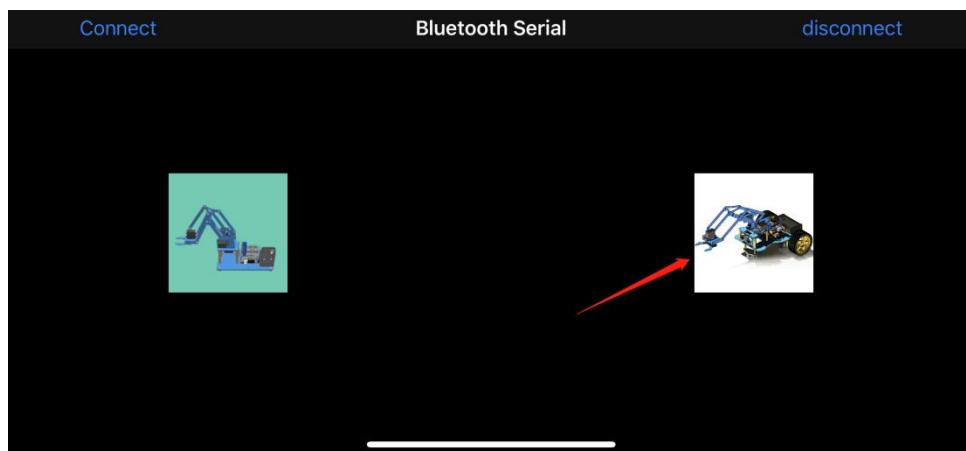
Note: Allow APP to access “location” in settings of your cellphone when connecting to Bluetooth module, otherwise, Bluetooth may not be connected.

1. iOS system

Search “keyes arm” in App store



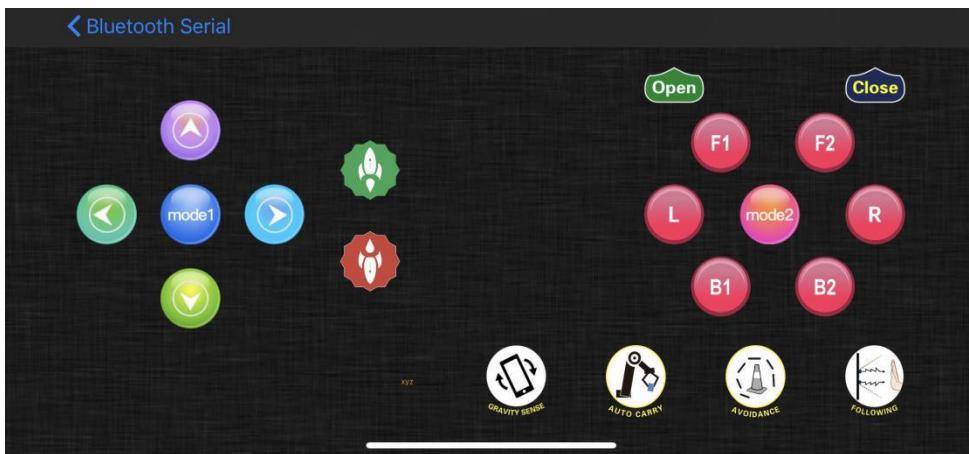
After it is downloaded, enter the main page.



Turn on Bluetooth in your cellphone.

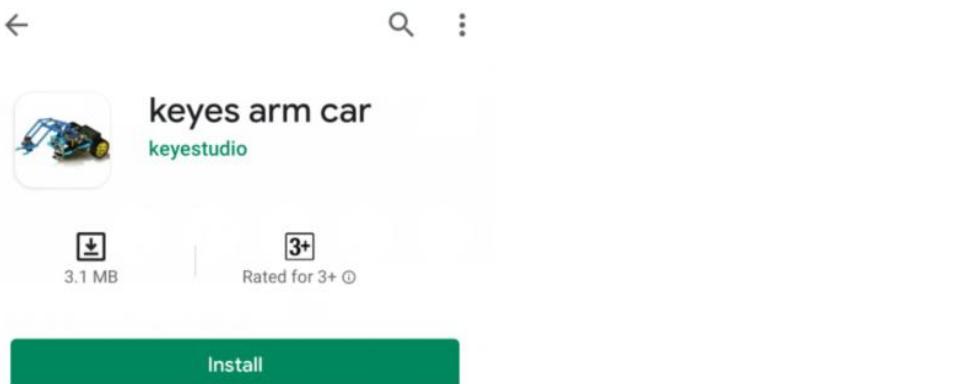
Click **Connect** to search Bluetooth, tap “connect” if HMSoft appears and

click  icon, and enter the main page.

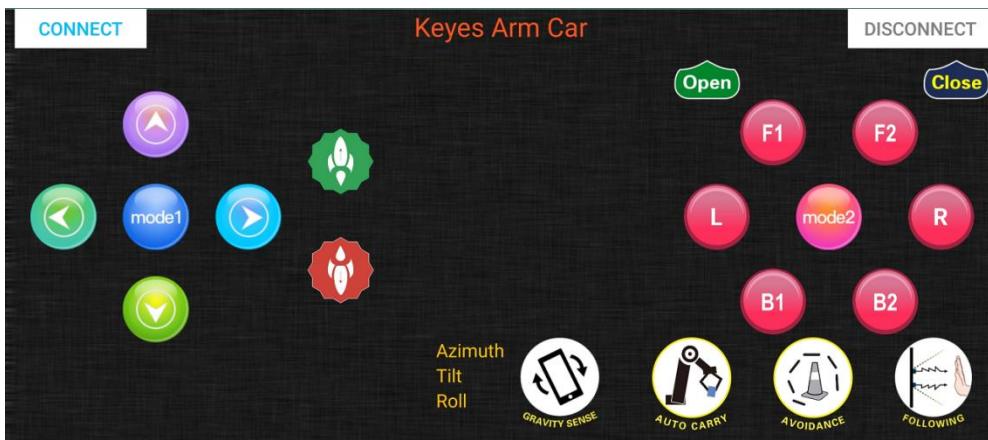


2. Android System

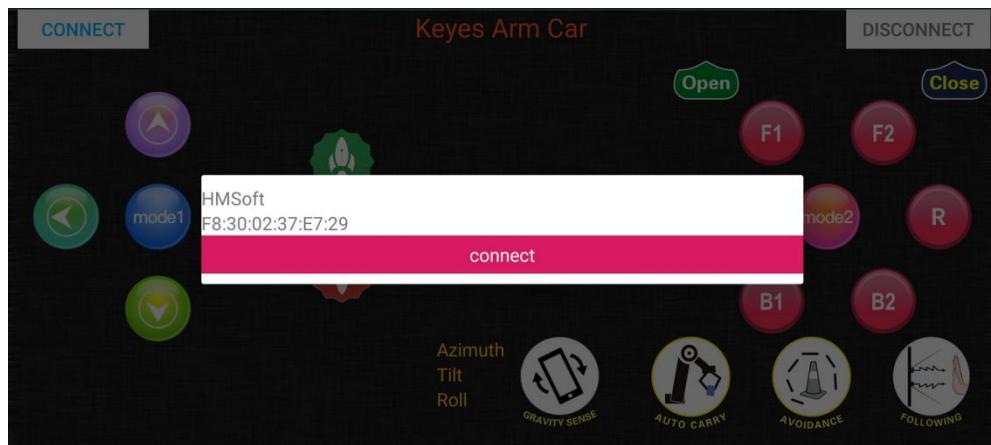
Search **keyes arm car** in Google play store and install



The interface is shown as below:



Click on APP **CONNECT** icon to search the Bluetooth.



Click “connect” if HMSoft appear, then Bluetooth LED will be turned on.

After app is downloaded, allow APP to access “location”, and you could enable “location” in settings of your cellphone.

Open Bluetooth and search HMSoft, then tap “connect” to operate App.

The function of each key on App is shown below:

Key	Function	
	Match with connection HM-10 Bluetooth module	
	Disconnect Bluetooth	
	Control character	Function
	Press: F Release: S	Press the button to go front; release to stop
	Press: L	Press button to turn left;



	Release: S	release to stop
	Press: R Release: S	Press button to turn right; release to stop
	Press: B Release: S	Press button to go back; release to stop
	Press: a Release: S	Press button to speed up; release to stop
	Press: d Release: S	Press button to speed down; release to stop
	Press: V Release: s	Press button to open claw, release to stop
	Press: P Release: s	Press button to close claw, release to stop
	Press: Q Release: s	Press F1 to lift up smaller arm, release to stop
	Press: E Release: s	Small arm lowers, release to stop
	Press: f Release: s	Large arm swings forward, release to stop
	Press: b Release: s	Large arm swings back, Release to stop



	Press: l Release: s	Press L to turn left, Release to stop
	Press: r Release: s	Press L to turn right, Release to stop
	Press: t Release: s	Press key to read and save angle value of servo
	Press: i Release: s	Save the angle value of servos
	Click to start the mobile gravity sensing; click again to exit	
	Click to send "Y", then click "S"	Press to enable obstacle avoidance,
	Click to send "U", then click "S"	Start Ultrasonic follow function; click Stop to exit

(6) Code Explanation:

Serial.available(): the number of left characters when back to buffer, this function is usually used to judge if there is data in buffer. Whenever Serial.available() is more than 0, serial receives the data in serial monitor.

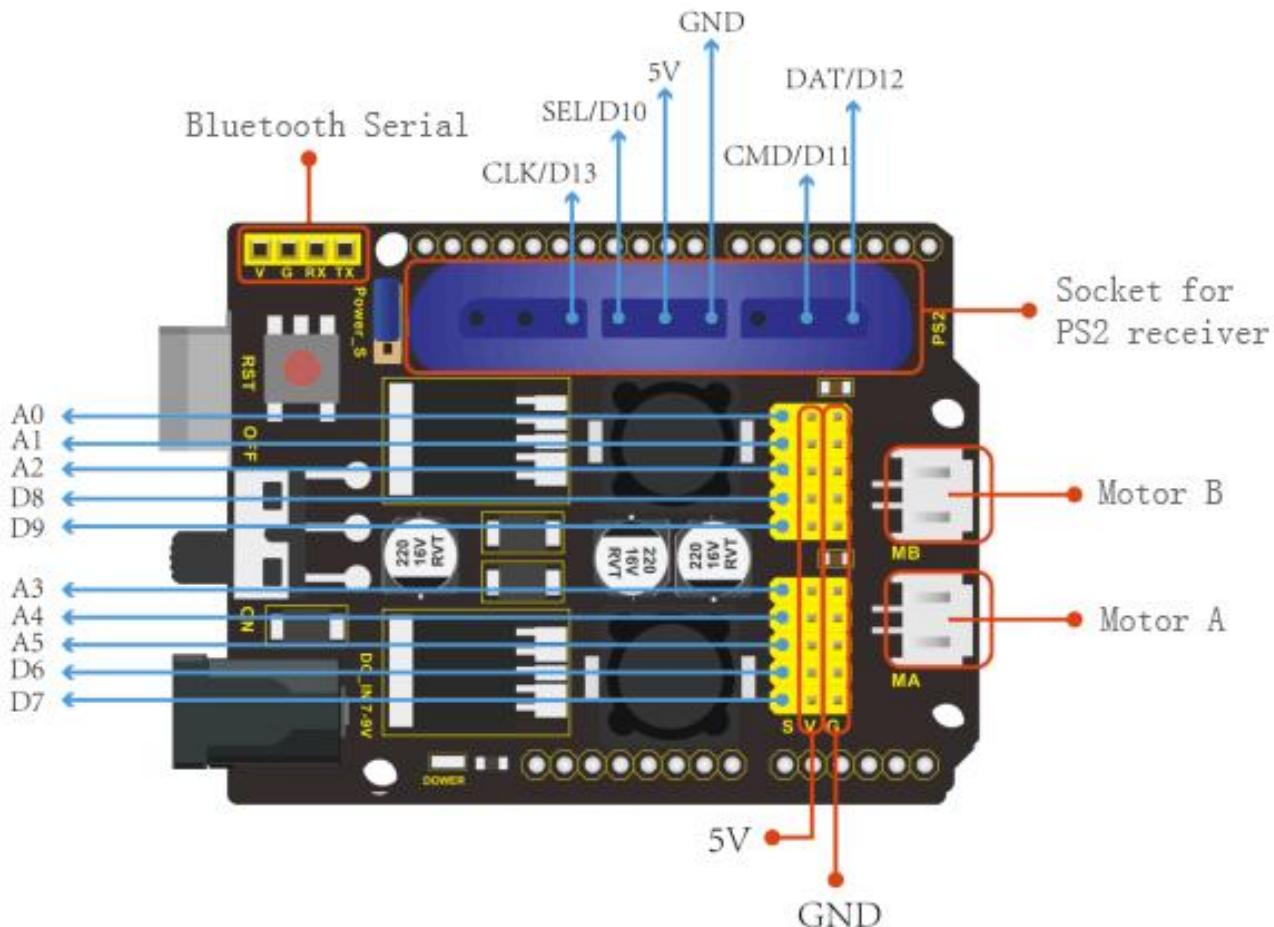
Serial.read(): read a Byte in buffer of serial, we could read the data sent with Serial.read(), for instance, some device send data to Arduino through serial monitor.

Project 6 Motor Driving and Speed Control

(1) Description:

Based on the TB6612FNG driver IC design, the motor driver on the expansion board adopts a special logic control method. Only 4 pins could achieve dual motor control. Compared with pure chips, it lacks two IO pins and can be applied in more fields, saving valuable IO resources for Arduino and other controllers.

TB6612FNG is a dual-channel full-bridge driver chip. The maximum continuous drive current of a single channel can reach 1.2A, and the peak value is 2A/3.2A (continuous pulse/single pulse), which can drive some micro DC motors.



(2) Specification:

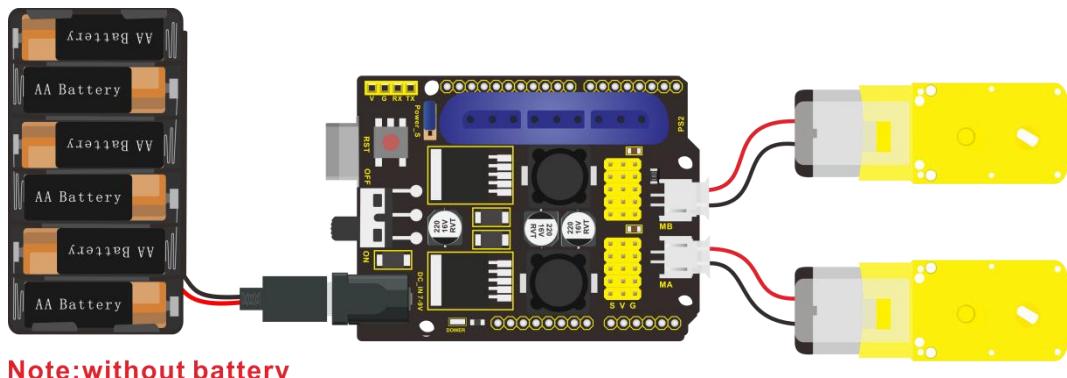
- Logic part input voltage VCC: 3.3~5V
- Drive part input voltage VM: 2.5~12V
- Number of drive motors: 2 channels
- Maximum continuous drive current of single channel: 1.2A
- Starting peak value: 2A/3.2A (continuous pulse/single pulse)



(3) What You Need

Control Board *1	Motor Shield*1	Motor *2	Battery Holder *1	USB Cable *1

(4) Connection Diagram:



(4) Test Code:

```
/*
```

keyestudio 4DOF Mechanical Robot Arm Car

lesson 6

motor driver shield

<http://www.keyestudio.com>



```
*/
```

```
int AIN2=2; //define direction control pin of motor A as D2  
int PWMA=3; //define speed control pin of motor A as D3  
int BIN2=4; //define direction control pin of motor B as D4  
int PWMB=5; //define speed control pin of motor B as D5
```

```
void setup(){
```

```
    pinMode(AIN2,OUTPUT); //set ports of motor to output  
    pinMode(PWMA,OUTPUT);  
    pinMode(BIN2,OUTPUT);  
    pinMode(PWMB,OUTPUT);
```

```
}
```

```
void loop(){ //go forward for 1s, back for 1s, turn left for 1s, right for 1s and  
stop for 1s
```

```
    //Go front
```

```
    digitalWrite(AIN2,LOW); //If AIN2 is low, AIN1 is high , motor MA turns  
clockwise
```

```
    analogWrite(PWMA,120); //rotation speed of motor MA is 120
```

```
    digitalWrite(BIN2,HIGH); //If BIN2 is high, BIN1 is low , motor MB turns  
clockwise
```

```
    analogWrite(PWMB,120);//rotation speed of motor MB is 120
```

```
    delay(1000);
```



//Go back

```
digitalWrite(BIN2,LOW); //if BIN2 is low, BIN1 is high , motor MB turns  
anticlockwise
```

```
analogWrite(PWMB,80); //rotation speed of motor MB is 80
```

```
digitalWrite(AIN2,HIGH); //AIN2 is high,AIN1 is low , motor MA turns  
anticlockwise
```

```
analogWrite(PWMA,80); //rotation speed of motor MA is 80
```

```
delay(1000);
```

//Turn Left

```
digitalWrite(AIN2,HIGH); //If AIN2 is high, AIN1 is low , motor MA turns  
anticlockwise
```

```
analogWrite(PWMA,120); //rotation speed of motor MA is 120
```

```
digitalWrite(BIN2,HIGH); //BIN2 is high,BIN1 is low , motor MB turns  
clockwise
```

```
analogWrite(PWMB,120);//rotation speed of motor MB is 120
```

```
delay(1000);
```

//Turn right

```
digitalWrite(AIN2,LOW); //If AIN2 is low, AIN1 is high , motor MA turns  
clockwise
```



```
analogWrite(PWMA,80); //rotation speed of motor MA is 80  
digitalWrite(BIN2,LOW); //If BIN2 is low, and BIN1 is high , motor MB turns  
anticlockwise  
  
analogWrite(PWMB,80); //rotation speed of motor MB is 80  
delay(1000);  
  
//Stop  
  
analogWrite(PWMA,0); //rotation speed of motor MA is 0  
analogWrite(PWMB,0); //rotation speed of motor MB is 0  
delay(1000);  
}
```

(5) Test Result:

Hook up by connection diagram, upload code and power on. The motor A and B rotate clockwise for 1s and anti-clockwise for 1s, then they stop.

Project 7 PS2 Joypad Controller



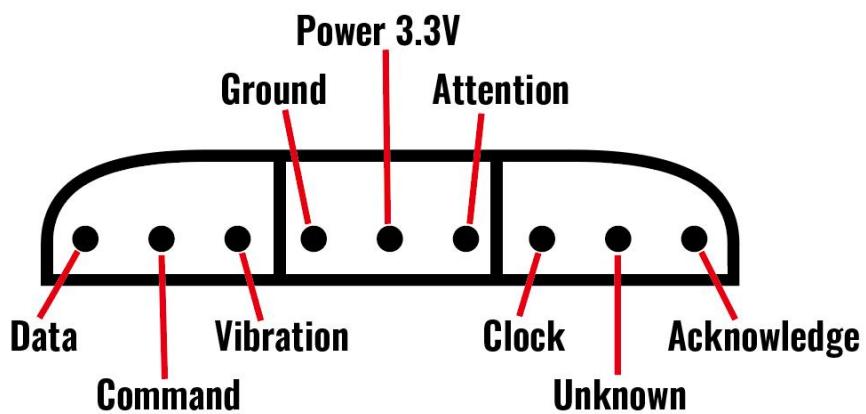
(1) Description:

The PS2 joypad controller is compatible with PlayStation2 game consoles. Sony's psx series game consoles are very popular all over the world, hence someone cracked the ps2 communication protocol so that the devices can be controlled remotely by handle, such as remote control smart car.



The PS2 joypad is composed of a handle and a receiver. The handle is used to send button information; the receiver is connected to the microcontroller (also called the host) to receive the information sent by the handle and pass it to the microcontroller. The microcontroller can also send commands to the controller and configures the sending mode of the joypad by receiver.

(2) Pins of Receiver



1. Data: host line, used to send data to the slave station (MOSI)
2. Command: Slave line, used to send data to the master station (MISO)
3. Vibration: the power supply of the vibration motor; 7.2V to 9V
4. Ground: circuit ground



5. VCC: power supply 3.3V
6. Attention: CS or chip select pin is used to call the slave and prepare to connect
7. Clock: equivalent to SCK pin of clock
8. No Connection: Useless
9. Knowledge: the response signal from the controller to the PS2 receiver

Insert PS2 receiver on development board

(3) Test Code:

```
/*
KEYESTUDIO 4DOF Mechanical Robot Arm Car
lesson 7
PS2
http://www.keyestudiocom
*/
#include <PS2X_lib.h>
#define PS2_DAT    12
#define PS2_CMD    11
#define PS2_SEL    10
#define PS2_CLK    13
```



```
#define pressures    true
//#define pressures    false

#define rumble     true
//#define rumble     false

PS2X ps2x;

int error=0;

byte type=0;
byte vibrate=0;

void setup(){

    Serial.begin(57600);

    delay(300);

    error=ps2x.config_gamepad(PS2_CLK,   PS2_CMD,   PS2_SEL,   PS2_DAT,
pressures, rumble);

    if(error==0){

        Serial.println("Found Controller, configured successful ");

        Serial.println("pressures = ");
        if(pressures) Serial.println("ture");
        else Serial.println("false");

        Serial.println("rumble = ");
        if(rumble) Serial.println("ture");
        else Serial.println("false");
    }
}
```

```
    Serial.println("Try out all the buttons, X will vibrate the controller, faster  
as you press harder;");  
  
    Serial.println("holding L1 or R1 will print out the analog stick values.");  
  
    Serial.println("Note: Go to www.billporter.info for updates and to  
report bugs.");  
  
}  
  
else if(error==1){  
  
    Serial.println("No controller found, check wiring, see readme.txt to  
enable debug. visit www.billporter.info for troubleshooting tips");  
  
}  
  
else if(error==2){  
  
    Serial.println("Controller found but not accepting commands. see  
readme.txt to enable debug. Visit www.billporter.info for troubleshooting  
tips");  
  
}  
  
else if(error==3){  
  
    Serial.println("Controller refusing to enter Pressures mode, may not  
support it. ");  
  
}  
  
type=ps2x.readType();  
switch(type){
```



```
case 0: Serial.print("Unknown Controller type found "); break;
case 1: Serial.print("DualShock Controller found "); break;
case 2: Serial.print("GuitarHero Controller found "); break;
case 3: Serial.print("Wireless Sony DualShock Controller found ");
break;
}
}

void loop(){
if(error==1) return;
if(error==2){
    ps2x.read_gamepad();
    if(ps2x.ButtonPressed(GREEN_FRET))      Serial.println("Green Fret
    Pressed");
    if(ps2x.ButtonPressed(RED_FRET))        Serial.println("Red Fret
    Pressed");
    if(ps2x.ButtonPressed(YELLOW_FRET))     Serial.println("Yellow Fret
    Pressed");
    if(ps2x.ButtonPressed(BLUE_FRET))       Serial.println("Blue Fret
    Pressed");
    if(ps2x.ButtonPressed(ORANGE_FRET))    Serial.println("Orange Fret
    Pressed");
}
```



```
if(ps2x.ButtonPressed(STAR_POWER))      Serial.println("Star Power  
Command");  
  
if(ps2x.Button(UP_STRUM))      Serial.println("Up Strum");  
if(ps2x.Button(DOWN_STRUM))  Serial.println("DOWN Strum");  
  
if(ps2x.Button(PSB_START))      Serial.println("Start is being held");  
if(ps2x.Button(PSB_SELECT))    Serial.println("Select is being held");  
  
if(ps2x.Button(ORANGE_FRET)){  
    Serial.print("Wammy Bar Position:");  
    Serial.println(ps2x.Analog(WHAMMY_BAR), DEC);  
}  
}  
else{  
    ps2x.read_gamepad(false, vibrate);  
    if(ps2x.Button(PSB_START))      Serial.println("Start is being held");  
    if(ps2x.Button(PSB_SELECT))    Serial.println("Select is being held");  
  
    if(ps2x.Button(PSB_PAD_UP)){  
        Serial.print("Up held this hard: ");  
    }  
}
```



```
    Serial.println(ps2x.Analog(PSAB_PAD_UP), DEC);
}

if(ps2x.Button(PSB_PAD_RIGHT)){
    Serial.print("Right held this hard: ");
    Serial.println(ps2x.Analog(PSAB_PAD_RIGHT), DEC);
}

if(ps2x.Button(PSB_PAD_LEFT)){
    Serial.print("LEFT held this hard: ");
    Serial.println(ps2x.Analog(PSAB_PAD_LEFT), DEC);
}

if(ps2x.Button(PSB_PAD_DOWN)){
    Serial.print("DOWN held this hard: ");
    Serial.println(ps2x.Analog(PSAB_PAD_DOWN), DEC);
}

vibrate = ps2x.Analog(PSAB_CROSS);

if (ps2x.NewButtonState()){

    if(ps2x.Button(PSB_L3))        Serial.println("L3 pressed");
    if(ps2x.Button(PSB_R3))        Serial.println("R3 pressed");
    if(ps2x.Button(PSB_L2))        Serial.println("L2 pressed");
    if(ps2x.Button(PSB_R2))        Serial.println("R2 pressed");
}
```



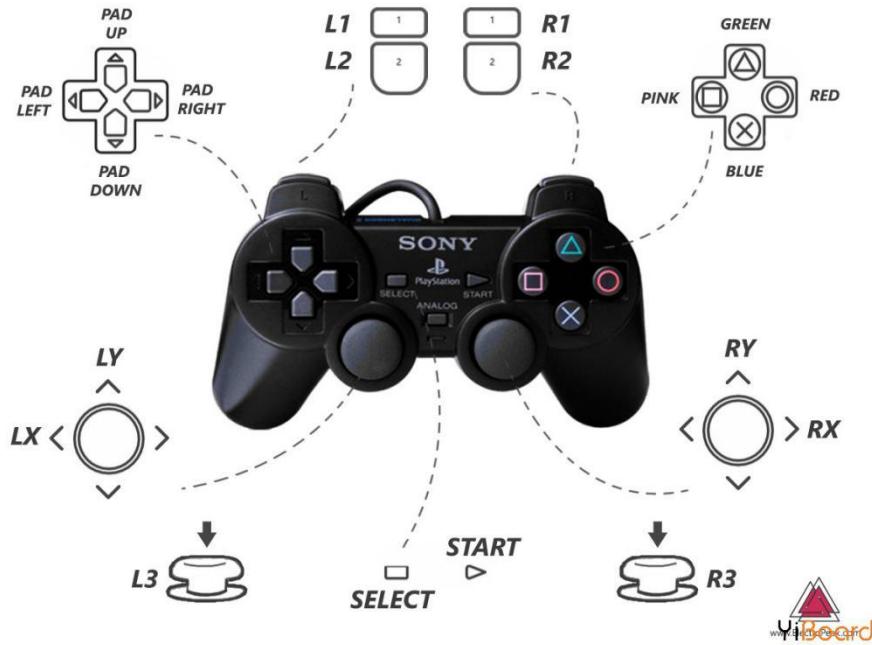
```
if(ps2x.Button(PSB_GREEN)) Serial.println("GREEN pressed");
if(ps2x.Button(PSB_RED)) Serial.println("RED pressed");
if(ps2x.Button(PSB_BLUE)) Serial.println("BLUE pressed");
if(ps2x.Button(PSB_PINK)) Serial.println("PINK pressed");
}

if(ps2x.Button(PSB_L1) || ps2x.Button(PSB_R1)){
    Serial.print("Stick Values:");
    Serial.print(ps2x.Analog(PSS_LY), DEC); //Left stick, Y axis. Other
options: LX, RY, RX
    Serial.print(",");
    Serial.print(ps2x.Analog(PSS_LX), DEC);
    Serial.print(",");
    Serial.print(ps2x.Analog(PSS_RY), DEC);
    Serial.print(",");
    Serial.println(ps2x.Analog(PSS_RX), DEC);
}
delay(50);
}

//*****
```



Read each key value on PS2 joypad and record in the following form.



Key	Logic
PAD UP	ps2x.Button(PSB_PAD_UP) will be TRUE as long as button is pressed
PAD LEFT	ps2x.Button(PSB_PAD_LEFT) will be TRUE as long as button is pressed
PAD RIGHT	ps2x.Button(PSB_PAD_RIGHT) will be TRUE as long as button is pressed
PAD DOWN	ps2x.Button(PSB_PAD_DOWN) will be TRUE as long as button is pressed



L1	ps2x.Button(PSB_L1) will be TRUE if the button changes state (on to off, or off to on)
L2	ps2x.Button(PSB_L2) will be TRUE if the button changes state (on to off, or off to on)
R1	ps2x.Button(PSB_R1) will be TRUE if the button changes state (on to off, or off to on)
R2	ps2x.Button(PSB_R2) will be TRUE if the button changes state (on to off, or off to on)
L3	ps2x.Button(PSB_L3) will be TRUE if the button changes state (on to off, or off to on)
R3	ps2x.Button(PSB_R3) will be TRUE if the button changes state (on to off, or off to on)
GREEN	ps2x.Button(PSB_GREEN) will be TRUE if the button changes state (on to off, or off to on)
PINK	ps2x.ButtonReleased(PSB_PINK) will



	be TRUE if button was JUST released
RED	ps2x.ButtonPressed(PSB_RED) will be TRUE if button was JUST pressed
BLUE	ps2x.NewButtonState(PSB_BLUE) will be TRUE if button was JUST pressed OR released
SELECT	ps2x.Button(PSB_SELECT) will be TRUE as long as button is pressed
START	ps2x.Button(PSB_START) will be TRUE as long as button is pressed
LX	Left stick, X axis. value:0~255
LY	Left stick, Y axis. value:0~255
RX	Right stick, X axis. value:0~255
RY	Right stick, Y axis. value:0~255



Note: print stick values if L1 or L2 is TRUE, you have to press L1 or L2 to print the value of joystick.

(4) Test Result:

Upload code, plug in PS2 receiver and joypad, open serial monitor and set baud rate to 9600. The corresponding value will be shown when pressing the keys on joypad.

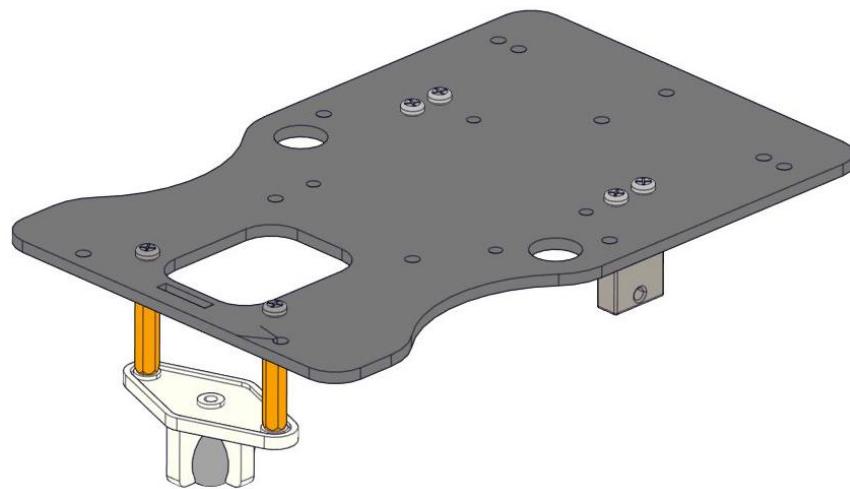
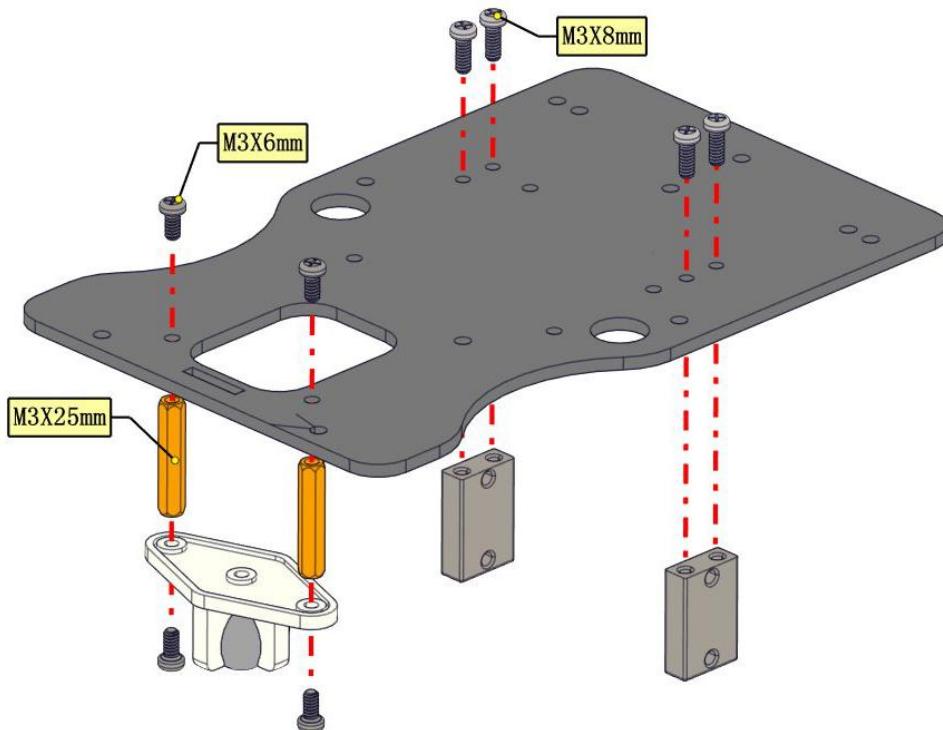


Project 8 Smart Car

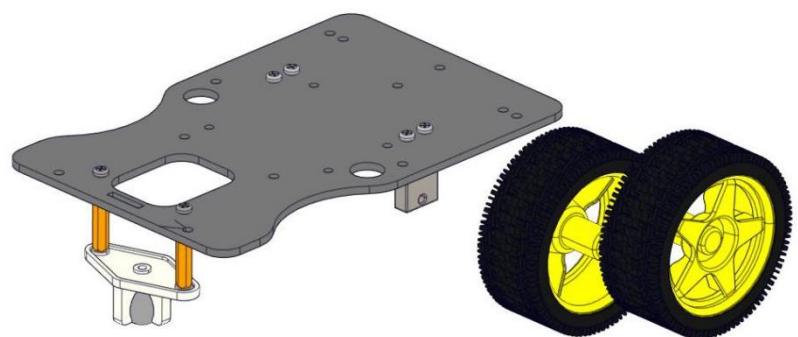
Note: Peel the plastic film off the board first when installing the smart car.

Installation Guide



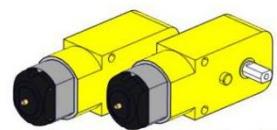


Mount Car Wheels



Car Wheel

×2



Motor 4.5V 200rpm

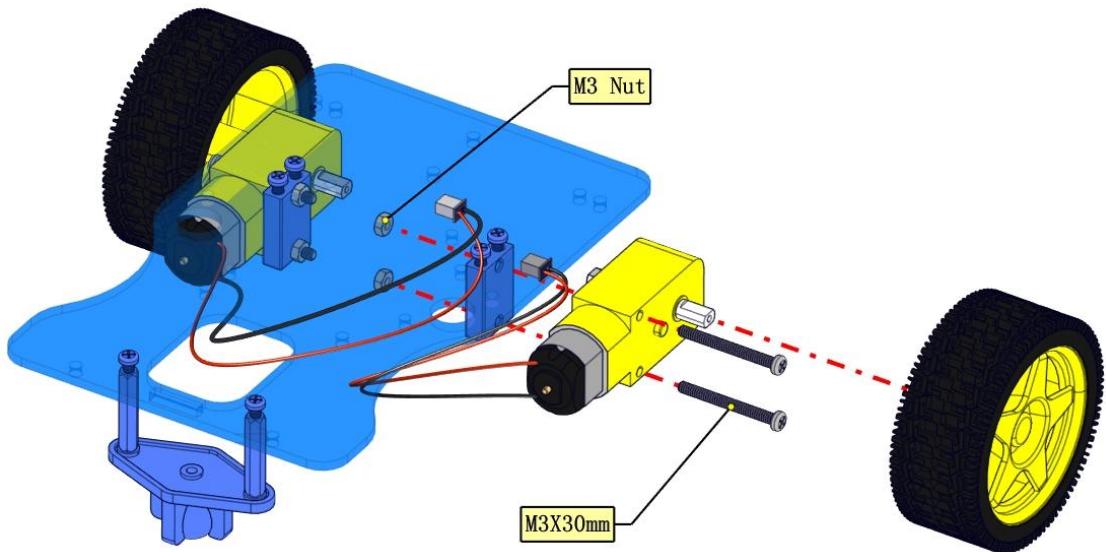


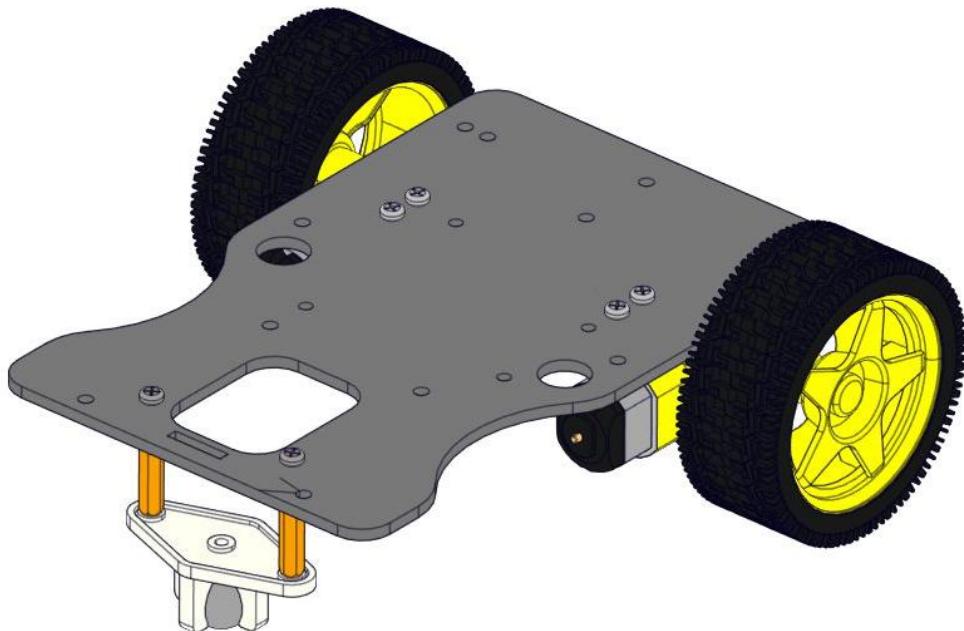
M3*30MM round head screw

×4

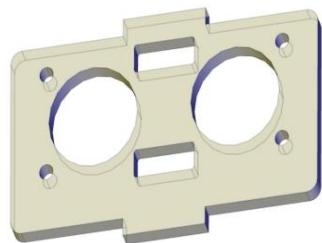
M3 Nickel-plating nut

×4



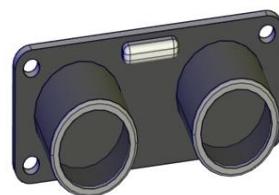


Assemble Ultrasonic Sensor



Baseplate for ultrasonic sensor

×1



HC-SR04 ultrasonic sensor

×1



M1.4*8MM round head screw

×4



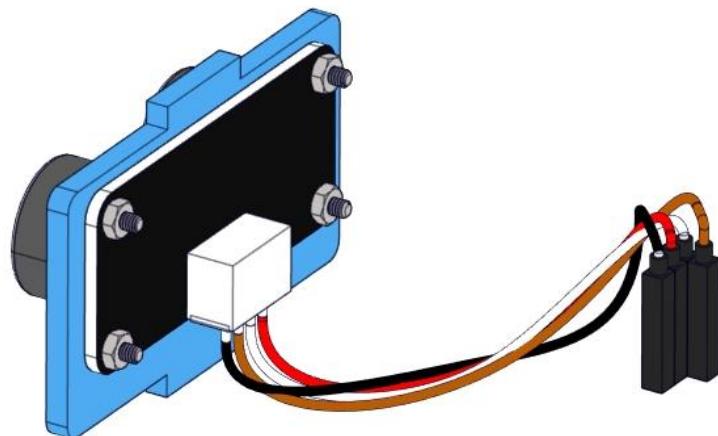
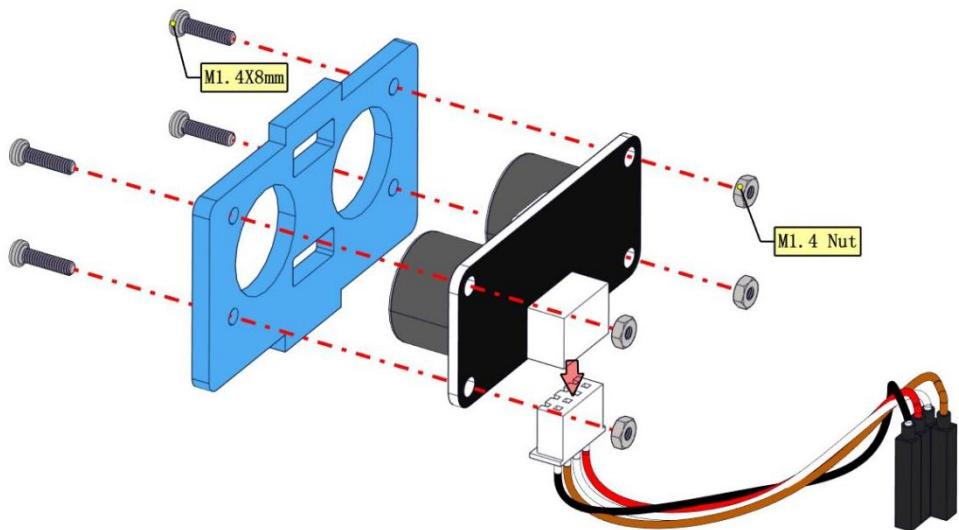
M1.4 Nickel-plating nut

×4

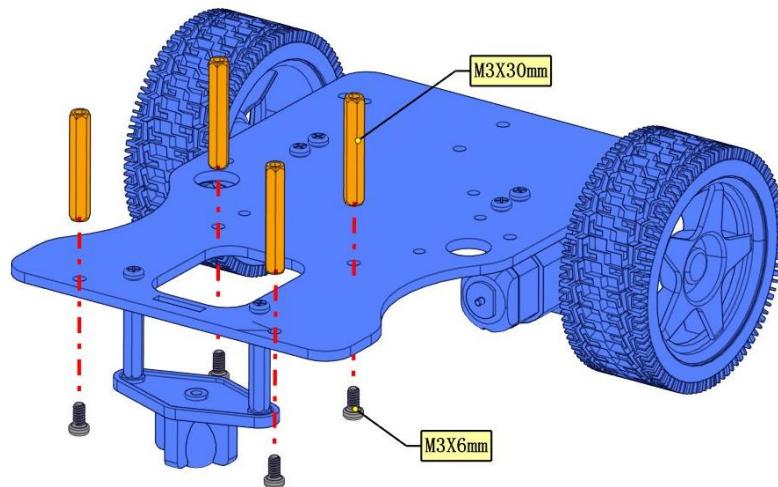
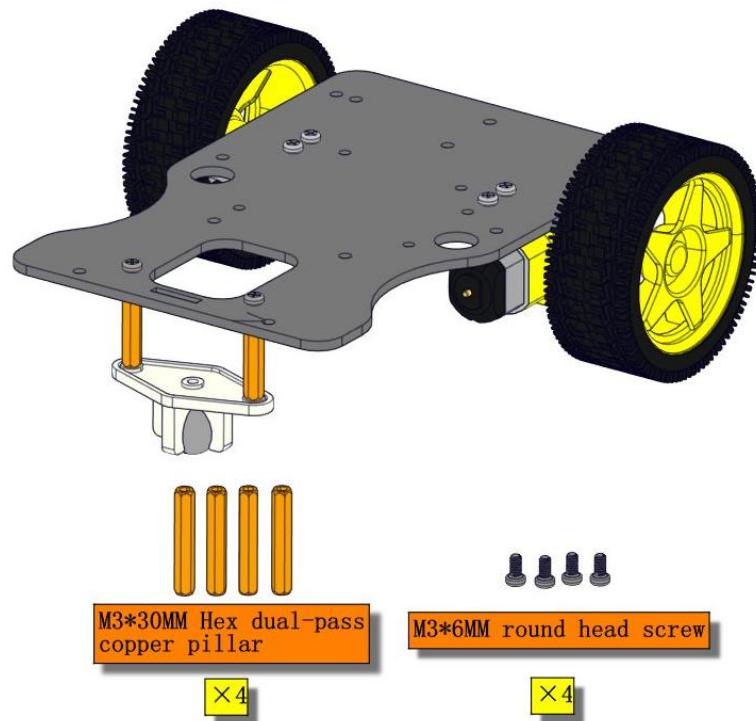


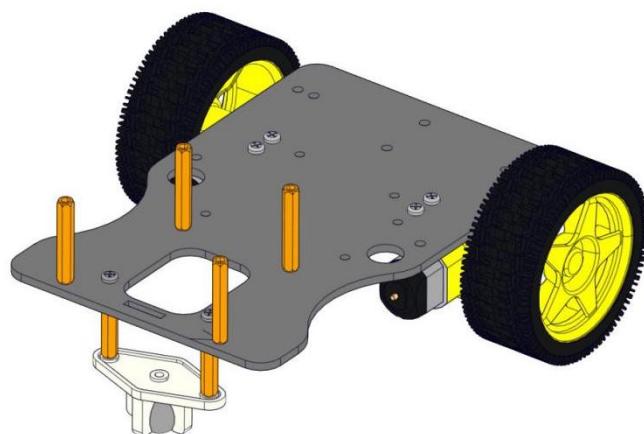
HX-2.54 4P dupont line

×1

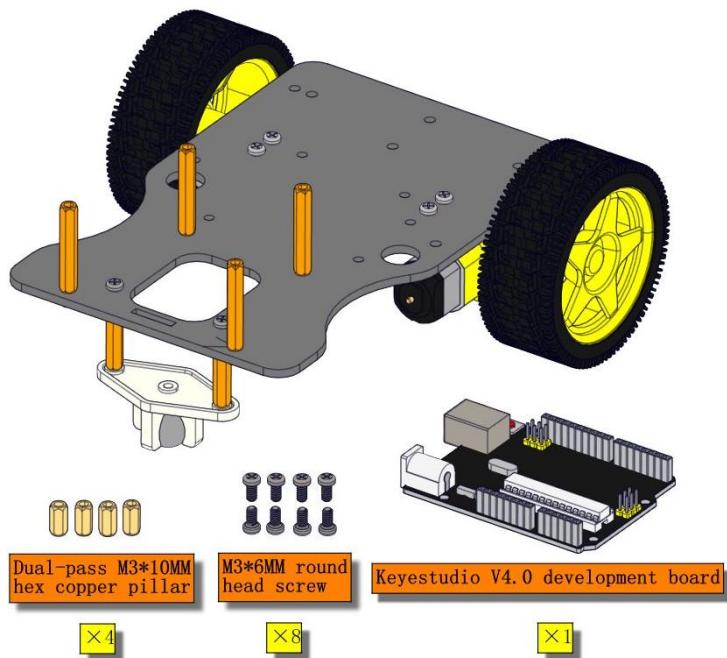


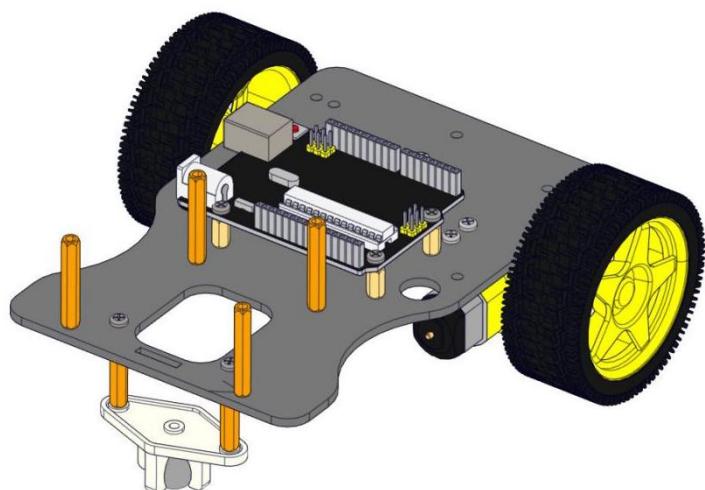
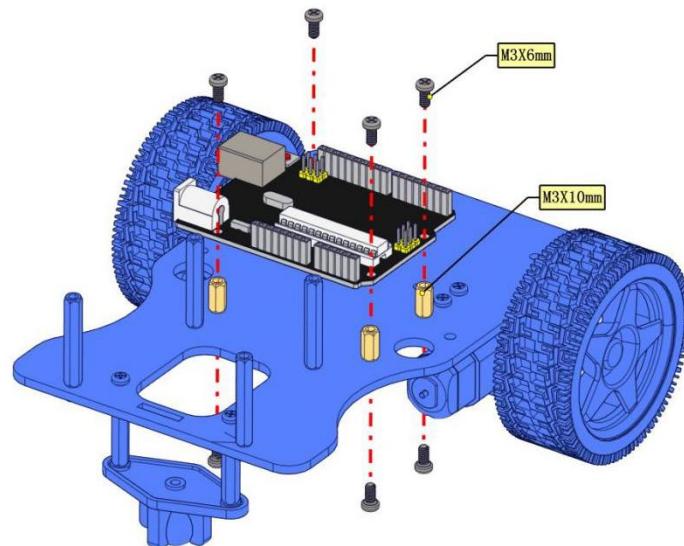
Screw Copper Bushes



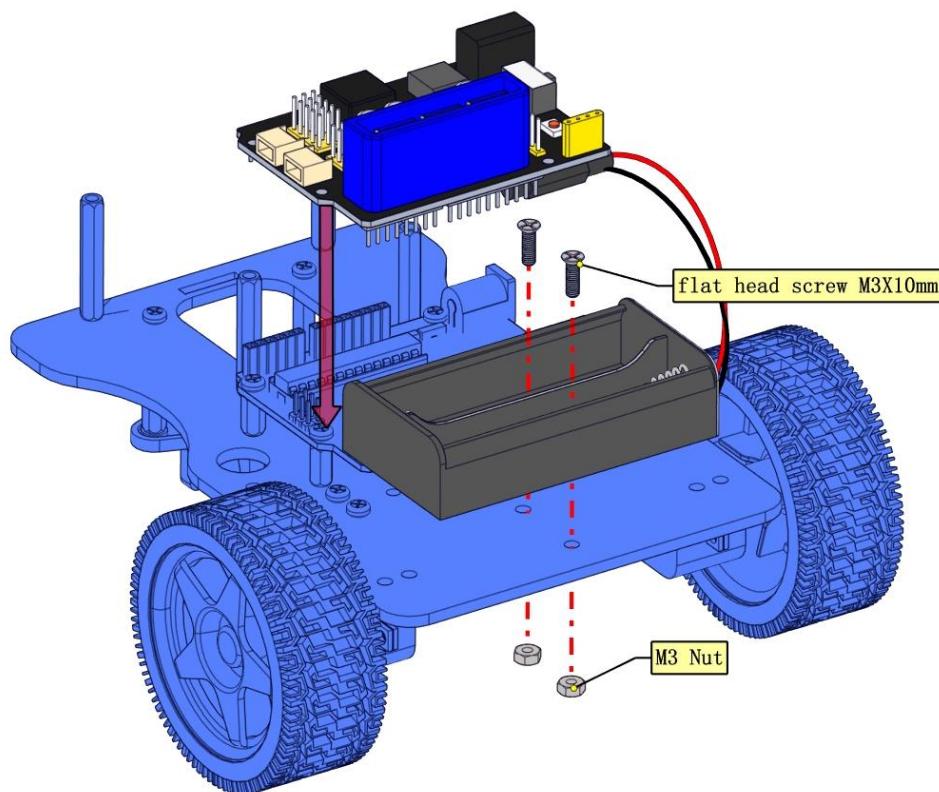
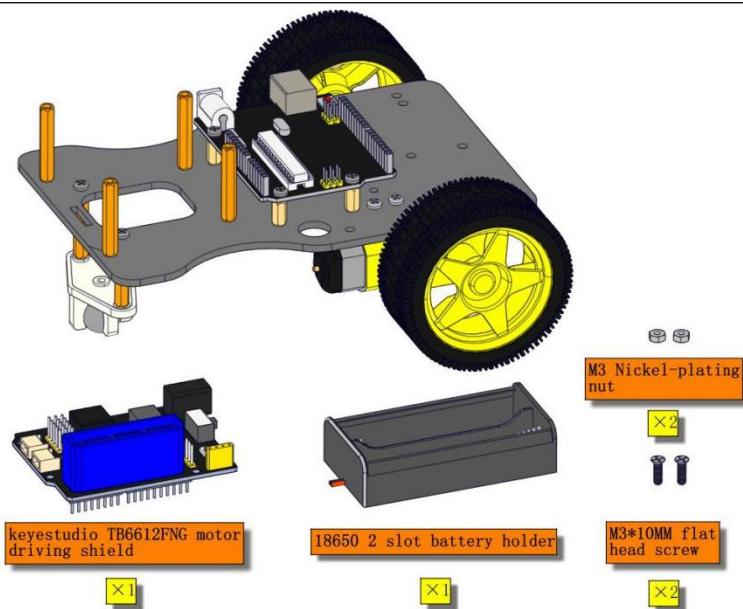


Install the V 4.0 Development Board



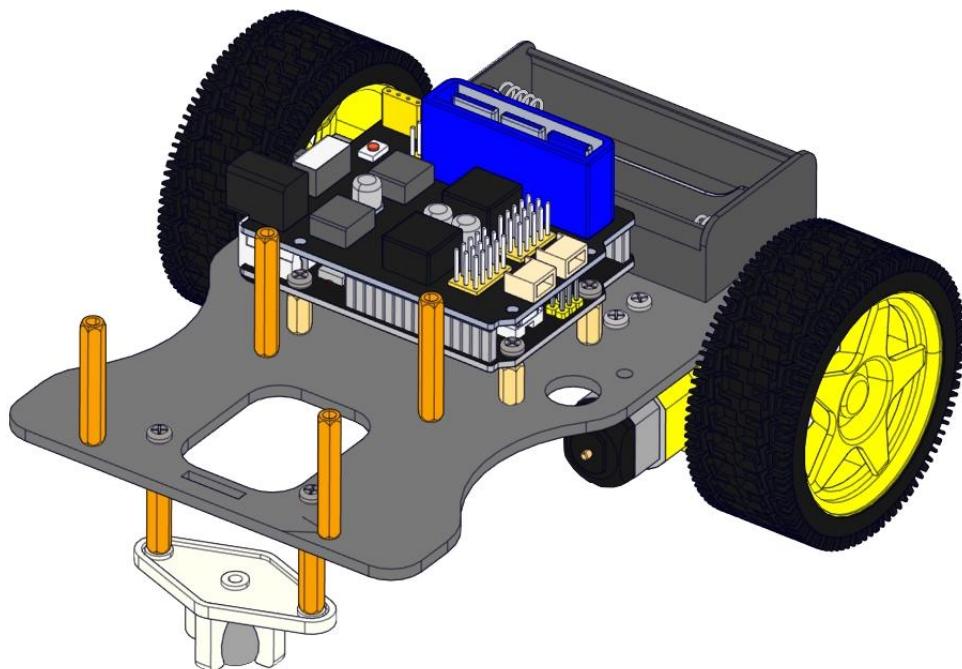
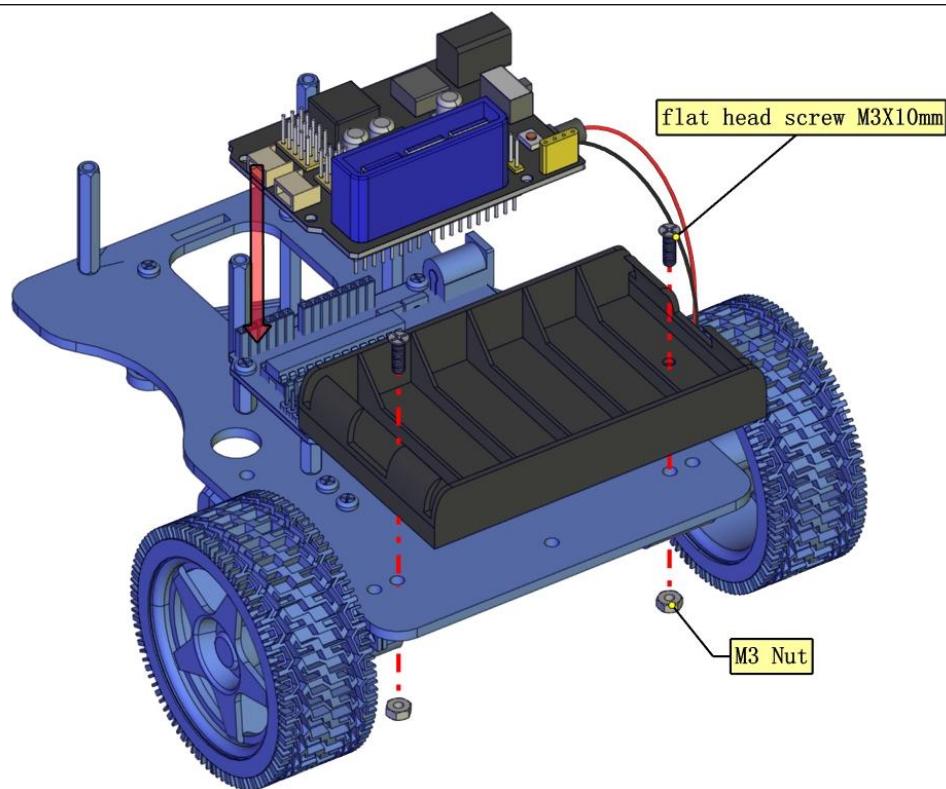


Mount Battery Holder and Motor Shield

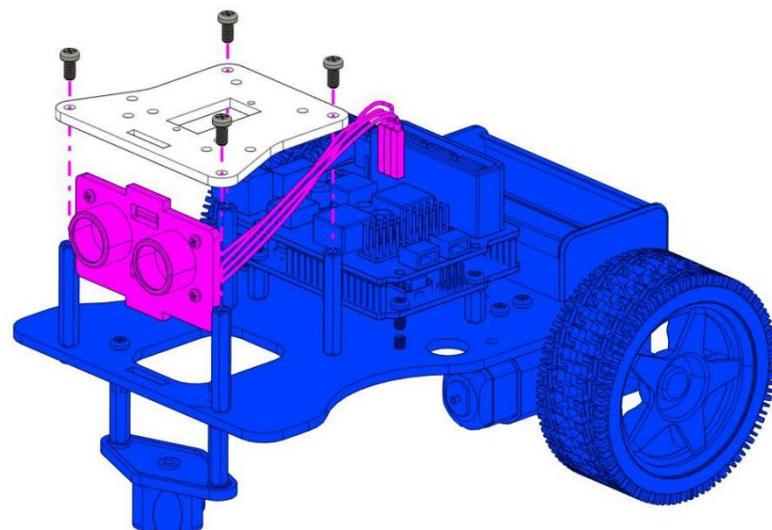
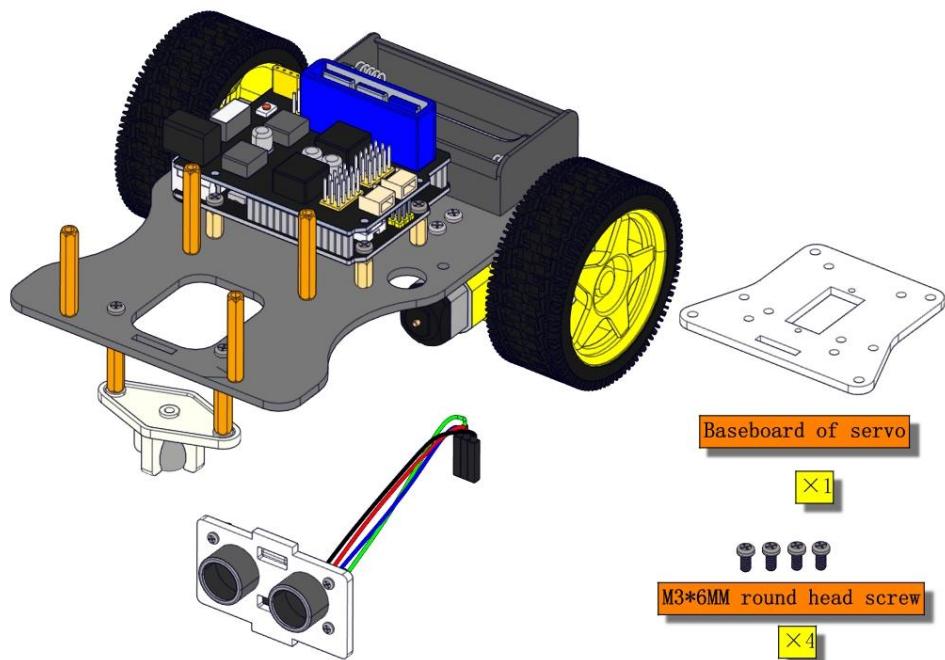


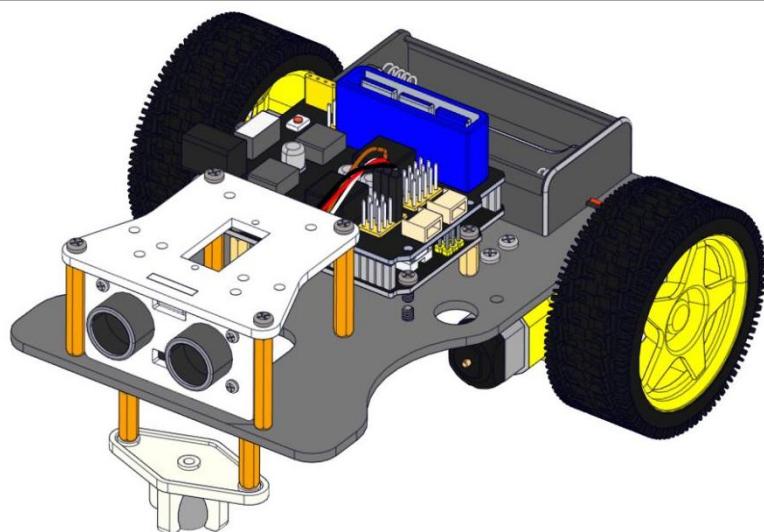


You could choose the battery holder you want.(2-slot or 6-slot)

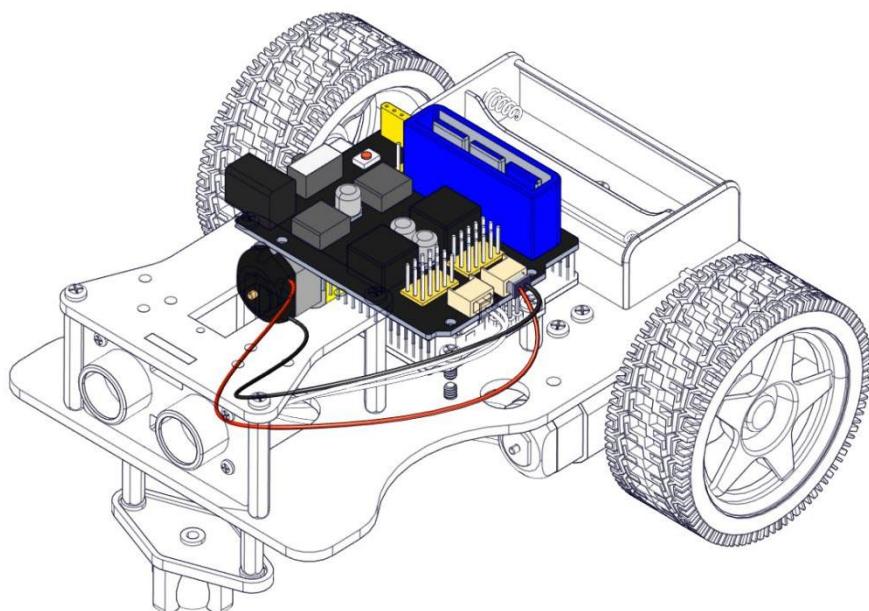
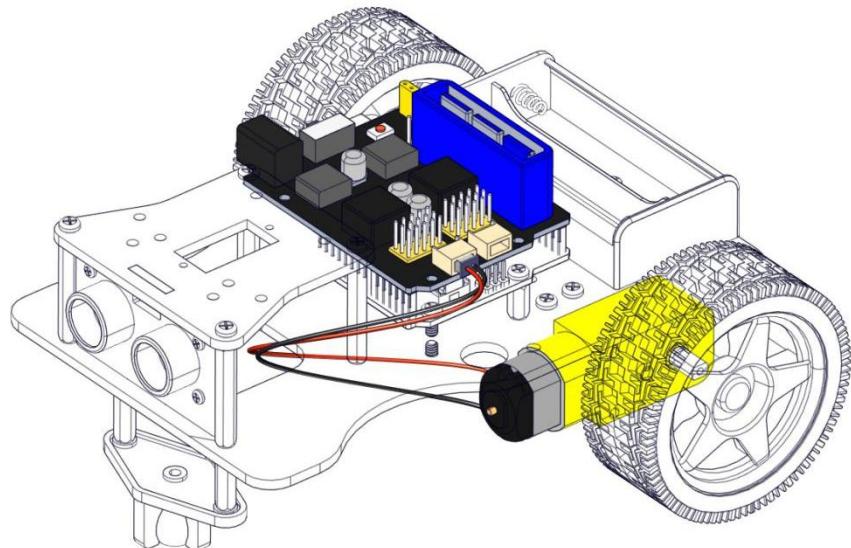


Assemble Baseboard of Servo

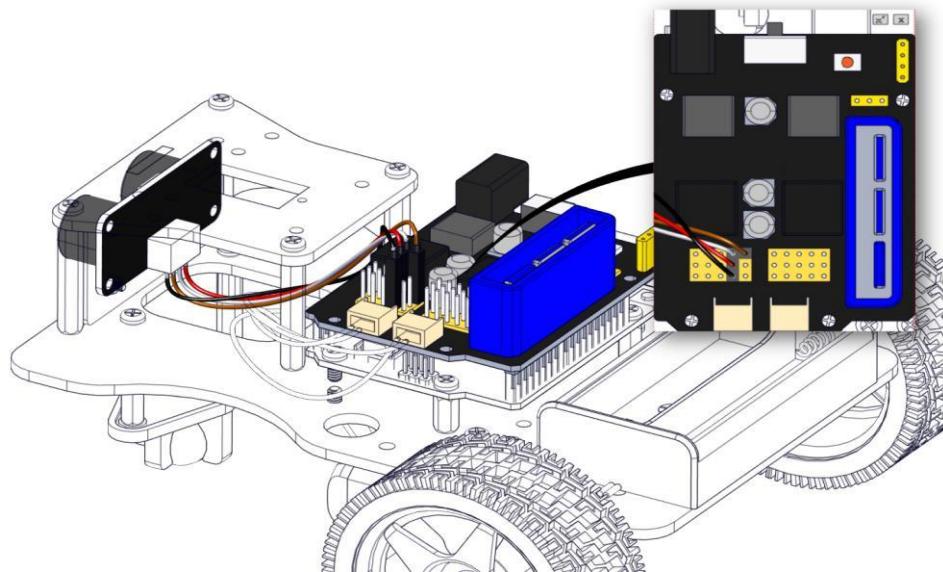




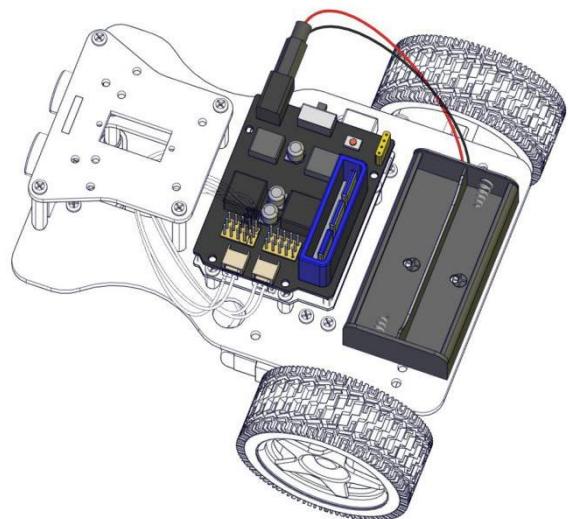
Wire up Motor



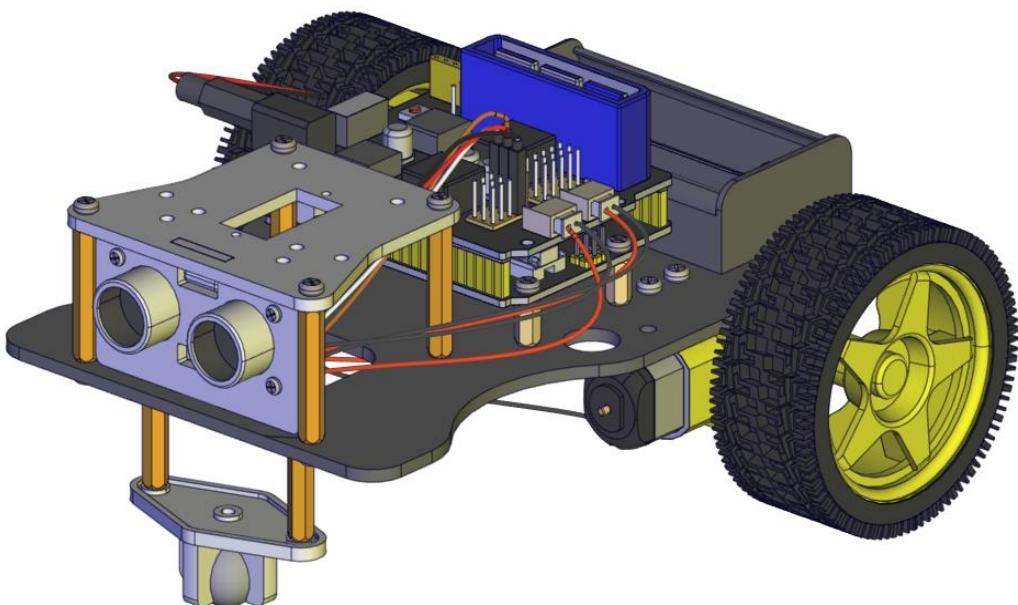
Wire up Ultrasonic Sensor



Connect
Battery
Holder



Turtle Smart Car



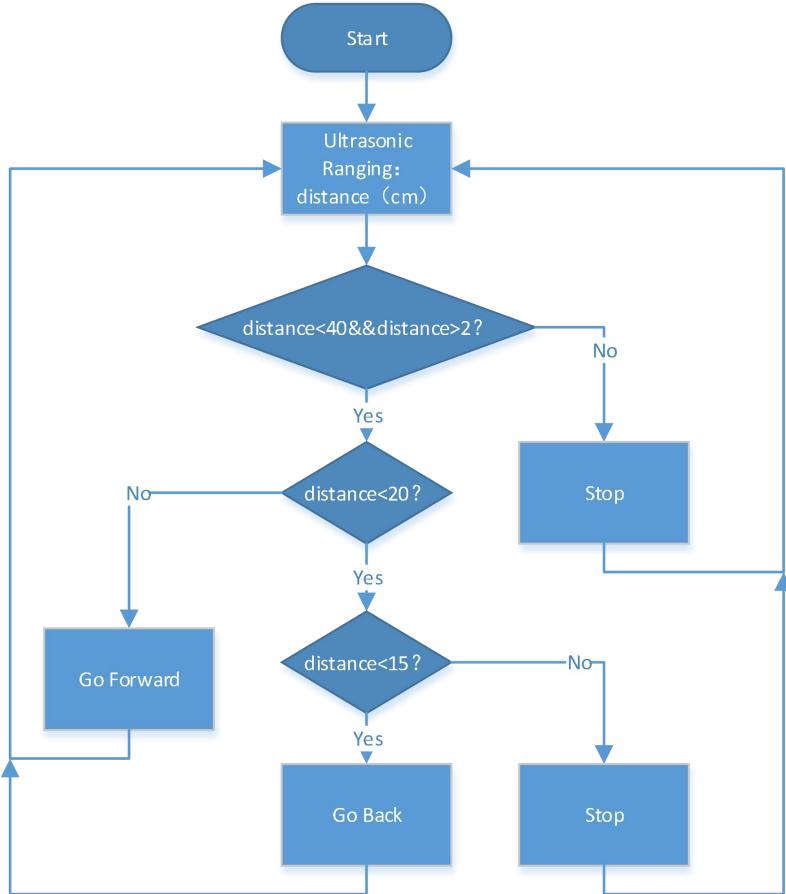
Project 9 Ultrasonic Follow Robot

(1) Description:

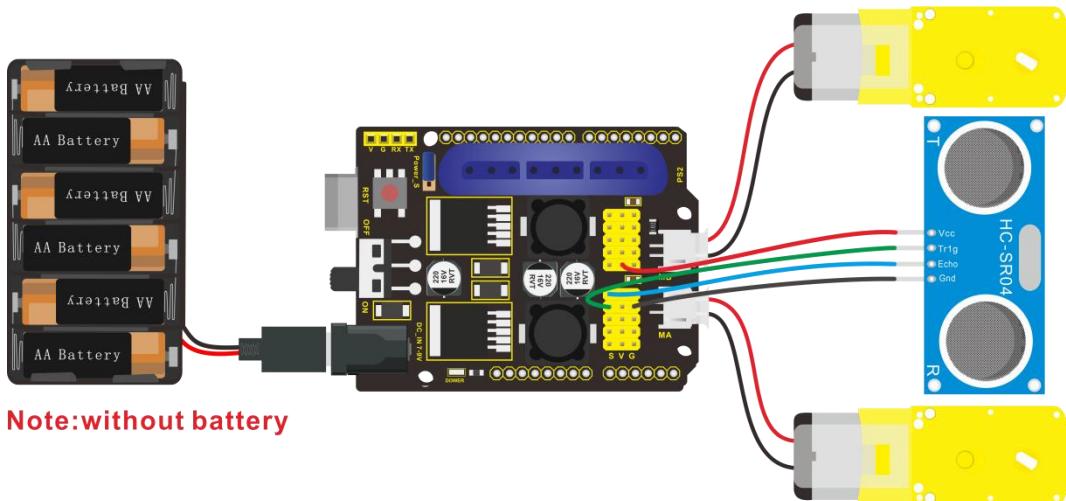
In this project, we will make robot car demonstrate ultrasonic following effect.

Ultrasonic sensor detects the distance away from obstacle and sends data to single-chip controller, hence the two motors are driven by data.

Flow Chart



(2) Connection Diagram:



(3) Test Code:

```
/*
```



keyestudio 4DOF Mechanical Robot Car

lesson 9.1

Ultrasonic Follow Robot

<http://www.keyestudio.com>

*/

```
int AIN2=2; //define driving pins of servo  
int PWMA=3;  
int BIN2=4; //When AIN2 is high and AIN1 is low,  
int PWMB=5;  
int echoPin=A3; // ultrasonic module ECHO to A3  
int trigPin=A4; // ultrasonic module TRIG to A4
```

```
int Ultrasonic_Ranging(){ //Ultrasonic_Ranging Function  
    digitalWrite(trigPin, LOW);  
    delayMicroseconds(2);  
    digitalWrite(trigPin, HIGH);  
    delayMicroseconds(10); //send least 10us high level to trigger ultrasonic  
    waves to trig pin  
    digitalWrite(trigPin, LOW);  
    int distance = pulseIn(echoPin, HIGH); // reading the duration of high level  
    distance= distance/58; // Transform pulse time to distance  
    delay(50);
```



```
return distance;      //return distance to this function
}

void advance(){      //car goes front
    digitalWrite(AIN2,LOW); //when AIN2 is low and AIN1 is high, motor MA turns
clockwise
    analogWrite(PWMA,100); //rotation speed of motor MA is 100
    digitalWrite(BIN2,HIGH); //when BIN2 is high and BIN1 is low, motor MB
turns clockwise
    analogWrite(PWMB,100);//rotation speed of motor MB is 100
}

void turnL(){ //turn left
    digitalWrite(AIN2,HIGH); //when AIN2 is high and AIN1 is low, motor MA
turns anticlockwise
    analogWrite(PWMA,100); //rotation speed of motor MA is 100
    digitalWrite(BIN2,HIGH); //When BIN2 is high and BIN1 is low, motor MB
turns clockwise
    analogWrite(PWMB,100);//rotation speed of motor MB is 100
}

void turnR(){ //turn right
    digitalWrite(AIN2,LOW); //When AIN2 is low and AIN1 is high, motor MA turns
clockwise
}
```



```
analogWrite(PWMA,100); //rotation speed of motor MA is 100
digitalWrite(BIN2,LOW); //When BIN2 is low and BIN1 is high, motor MB turns
anticlockwise

analogWrite(PWMB,100); //Rotation speed of motor MB is 100
}

void back(){ //go back
    digitalWrite(BIN2,LOW); //When BIN2 is low and BIN1 is high, motor MB turns
    anticlockwise

    analogWrite(PWMB,100); //rotation speed of motor MB is 100,
    digitalWrite(AIN2,HIGH); //When AIN2 is high and AIN1 is low, motor MA
turns anticlockwise

    analogWrite(PWMA,100); //rotation speed of motor MA is 100
}

void stopp(){ //stop
    analogWrite(PWMA,0); //rotation speed of motor MA is 0
    analogWrite(PWMB,0); //rotation speed of motor MB is 0
}

void setup(){
    Serial.begin(9600);
    pinMode(2,OUTPUT); //set ports of motor to output
    pinMode(3,OUTPUT);
```



```
pinMode(4,OUTPUT);
pinMode(5,OUTPUT);
pinMode(echoPin,INPUT);      //set echoPin to input
pinMode(trigPin,OUTPUT);   //set trigPin to output
stopp(); //stop car

}

void loop(){
    int distance=Ultrasonic_Ranging();
    Serial.print("distance=");
    Serial.println(distance);
    if(distance<40&&distance>2){ //When distance<40 or distance>2
        if(distance<20){ //if distance<20, go back
            if(distance<15){
                back();
            }
        }
        else{
            stopp();
        }
    }
    else{ //When 20< distance<35, go forward
        advance();
    }
}
```



```
    }  
    }  
else{ //distance>35 or distance≤20, stop  
    stop();  
}  
}  
}
```

(3) Test Result:

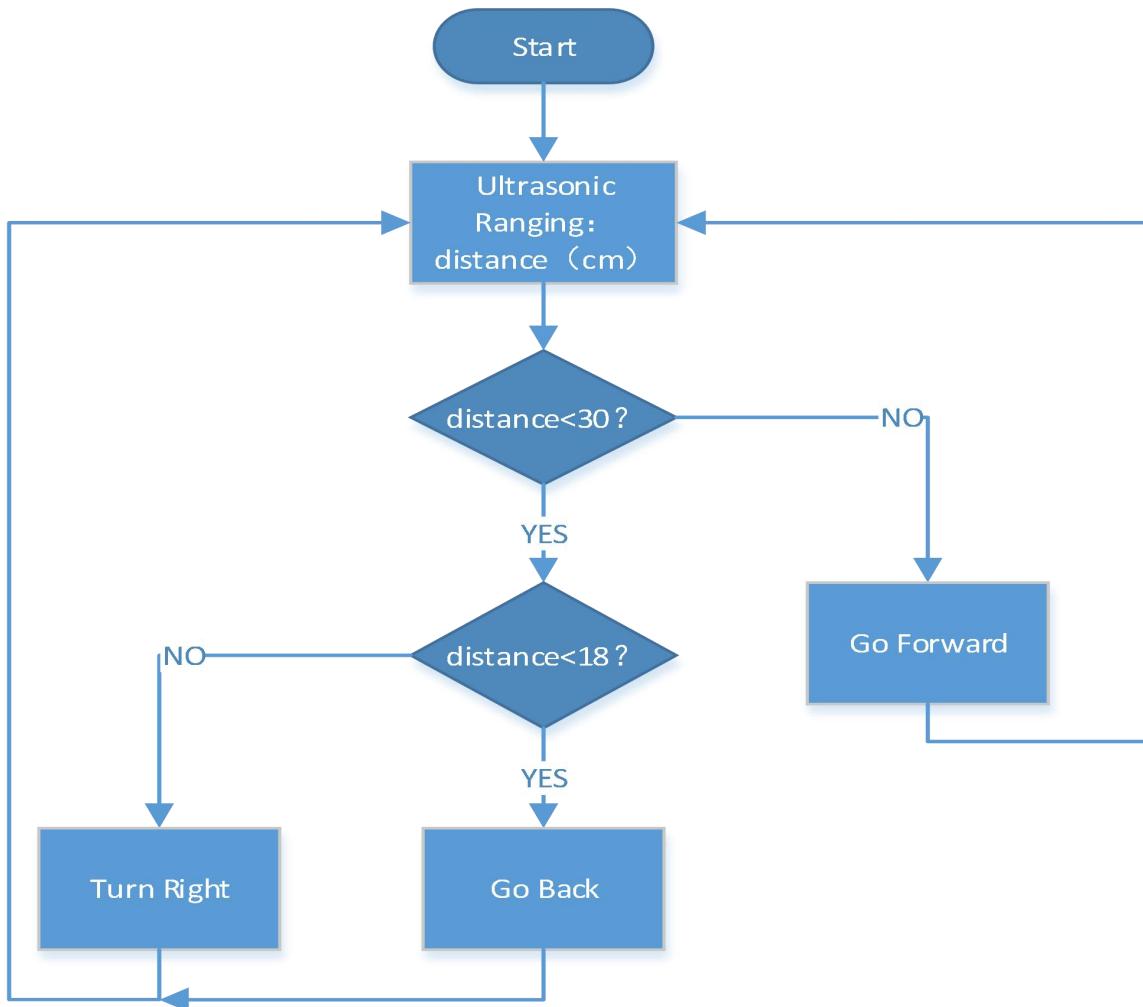
Upload code to development board, wire up, plug in power and dial DIP switch to “ON” end. You will view robot car follow the obstacle to move.

Project 10 Ultrasonic Avoiding Robot

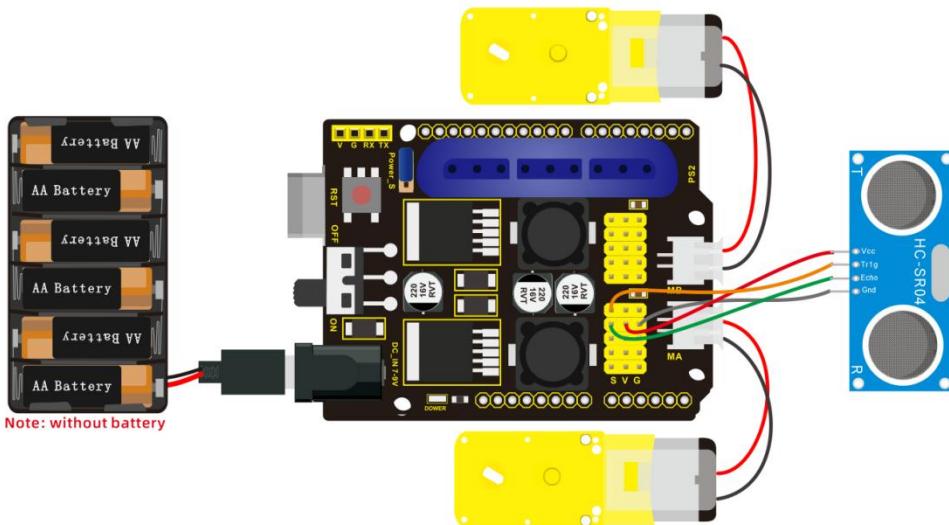
(1) Description:

We will use ultrasonic sensor to make an ultrasonic avoiding robot.

Flow Chart



(2) Connection Diagram:



(3) Test Code:

```
/*
```

Keyestudio 4DOF Mechanical Robot Arm Car

lesson 9.1

Ultrasonic avoiding robot

<http://www.keyestudio.com>

```
*/
```

```
int AIN2=2; //define driving pins of motor
```

```
int PWMA=3;
```

```
int BIN2=4; //when AIN2 is low and AIN1 is high, when BIN2 is high and BIN1 is  
low
```

```
int PWMB=5;
```

```
int echoPin=A3; // ultrasonic module ECHO to A3
```

```
int trigPin=A4; // ultrasonic module TRIG to A4
```



```
int Ultrasonic_Ranging(){ //function of Ultrasonic Ranging
    digitalWrite(trigPin, LOW);
    delayMicroseconds(2);
    digitalWrite(trigPin, HIGH);
    delayMicroseconds(10); //send least 10us high level to trigger ultrasonic
waves to trig pin
    digitalWrite(trigPin, LOW);
    int distance = pulseIn(echoPin, HIGH); // reading the duration of high level
distance= distance/58; // Transform pulse time to distance
    delay(50);
    return distance; //return distance to function
}
```

```
void advance(){ //go front
    digitalWrite(AIN2,LOW); //when AIN2 is low and AIN1 is high, motor MA turns
clockwise
    analogWrite(PWMA,100); //rotation speed of motor MA is 100
    digitalWrite(BIN2,HIGH); //when BIN2 is high and BIN1 is low, motor MB
turns clockwise
    analogWrite(PWMB,100);//rotation speed of motor MB is 100
}
void turnL(){ //turn left
```



```
digitalWrite(AIN2,HIGH); //When AIN2 is high and AIN1 low, motor MA turns  
anticlockwise  
  
analogWrite(PWMA,100); //rotation speed of motor MB is 100  
  
digitalWrite(BIN2,HIGH); //when BIN2 is high and BIN1 is low, motor MB  
turns clockwise  
  
analogWrite(PWMB,100);//rotation speed of motor MB is 100  
  
}  
  
void turnR(){ //turn right  
  
digitalWrite(AIN2,LOW); //When AIN2 is low and AIN1 is high, motor MA turns  
clockwise  
  
analogWrite(PWMA,100); //rotation speed of motor MA is 100  
  
digitalWrite(BIN2,LOW); //When BIN2 is low and BIN1 is high, motor MB turns  
anticlockwise  
  
analogWrite(PWMB,100); //rotation speed of motor MB is 100  
  
}  
  
void back(){ //go back  
  
digitalWrite(BIN2,LOW); //when BIN2 is low and BIN1 is high, motor MB  
rotates anticlockwise  
  
analogWrite(PWMB,100); //rotation speed of MB is 100  
  
digitalWrite(AIN2,HIGH); //when AIN2 is high and AIN1 is low, motor MA  
rotates anticlockwise  
  
analogWrite(PWMA,100); //rotation speed of MA is 100
```



```
}
```

```
void stopp(){ //stop  
analogWrite(PWMA,0); //rotation speed of MA is 0  
analogWrite(PWMB,0); //rotation speed of MB is 0  
}  
  
}
```

```
void setup(){  
Serial.begin(9600);  
pinMode(2,OUTPUT); //set ports of motor to output  
pinMode(3,OUTPUT);  
pinMode(4,OUTPUT);  
pinMode(5,OUTPUT);  
pinMode(echoPin,INPUT); //set echoPin to input  
pinMode(trigPin,OUTPUT); //set trigPin to output  
stopp(); //stop car  
}  
  
}
```

```
void loop(){  
int distance=Ultrasonic_Ranging();  
Serial.print("distance=");  
Serial.println(distance);  
if(distance<30&&distance>2){ //distance<30cm
```



```
if(distance<18){ //if distance<18, go back  
    back();  
    delay(300);  
}  
  
else{ //18<distance<30, turn right  
    turnR();  
    delay(300);  
}  
  
}  
  
else{ //distance>30, go forward  
    advance();  
}  
  
}
```

(4) Test Result:

Upload code, plug in power, and dial DIP switch to “ON” end. The smart car will go forward and avoid the obstacle.

Project 11 Bluetooth Control Car

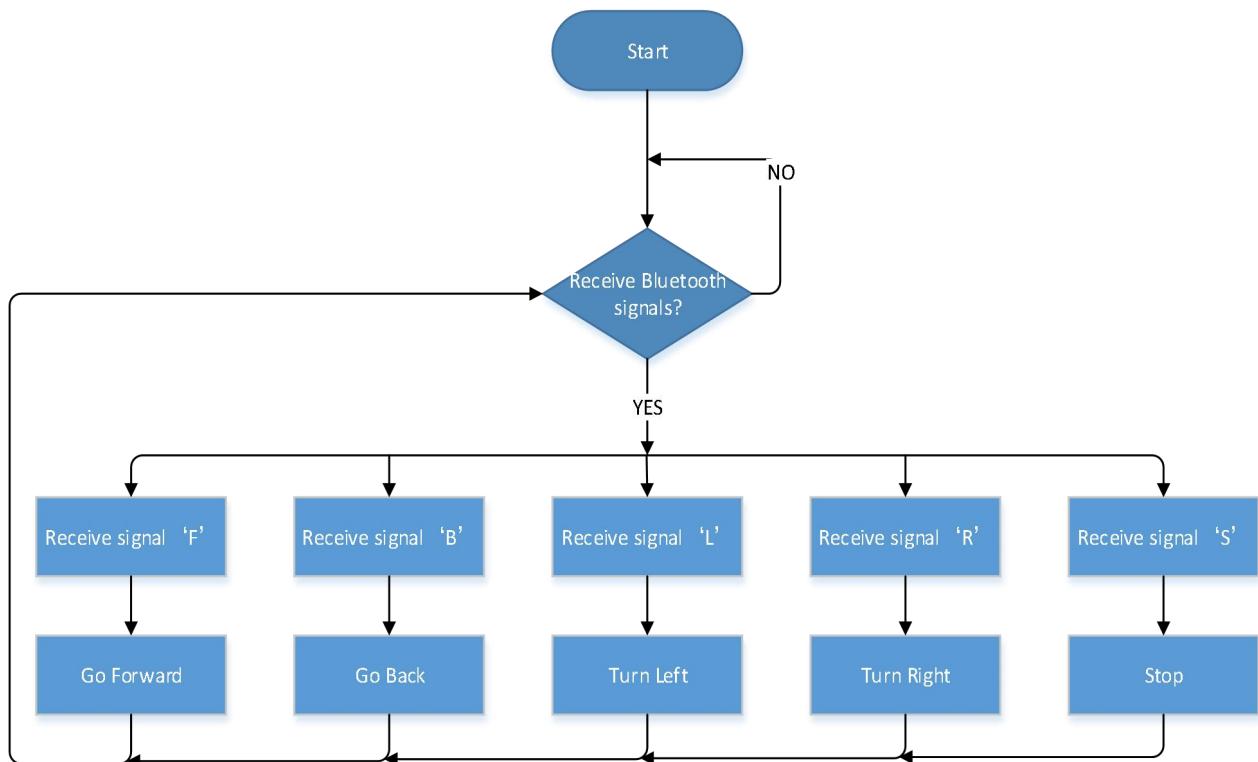
(1) Description:

In this lesson, we will make a Bluetooth control car which is composed of

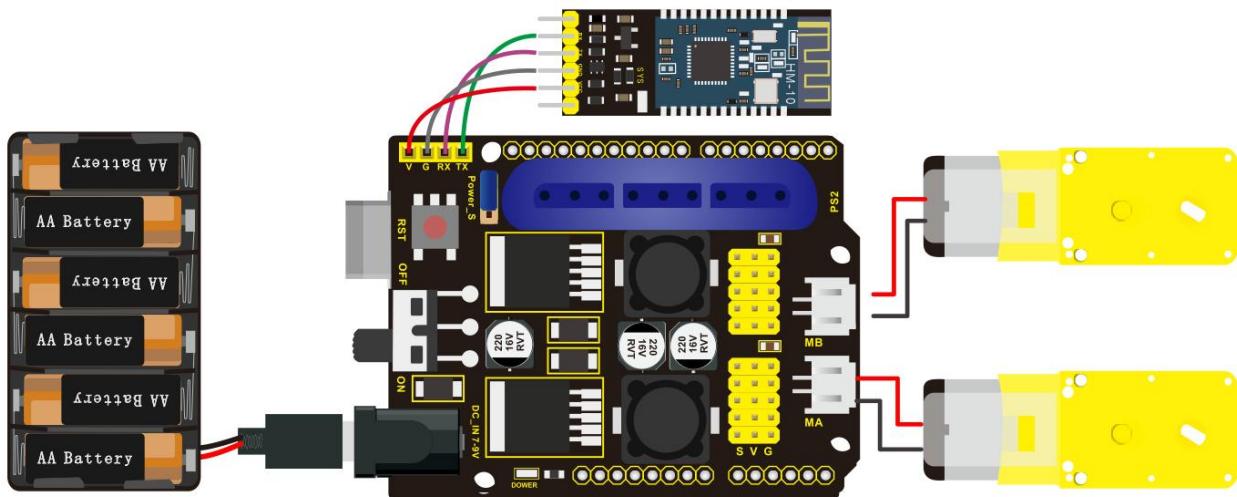


two sections---controlling and controlled end. The cellphone is host machine and HM-10 Bluetooth module is slave machine which is connected to controlled end. To control this car, we devised an APP.

Flow Chart



(2) Connection Diagram:



(3) Test Code:

```
/*
keyestudio 4DOF Mechanical Robot Arm Car
lesson 11.1

Bluetooth Remote Control

http://www.keyestudio.com

*/
int AIN2 = 2; //define the driving pins of motor
int PWMA = 3;
int BIN2 = 4; //when AIN2 is low and AIN1 is high, when BIN2 is high and BIN1
is low
int PWMB = 5;

void setup() {
    Serial.begin(9600);
```



```
pinMode(AIN2, OUTPUT); //set ports of motor to output  
pinMode(PWMA, OUTPUT);  
pinMode(BIN2, OUTPUT);  
pinMode(PWMB, OUTPUT);  
stopp(); //stop  
  
}  
  
void loop() {  
  
if (Serial.available() > 0) { //receive Bluetooth signals  
switch (Serial.read()) {  
  
case 'F': advance(); Serial.println("advance"); break; //receive 'F' ,  
go forward  
  
case 'B': back(); Serial.println("back"); break; //receive 'B' , go back  
  
case 'L': turnL(); Serial.println("left"); break; //receive 'L' , turn left  
  
case 'R': turnR(); Serial.println("right"); break; //receive 'R' , turn right  
  
case 'S': stopp(); Serial.println("stop"); break; //receive 'S' , stop  
}  
}  
}
```



```
void advance() { //go forward
    digitalWrite(AIN2, LOW); //when AIN2 is low and AIN1 is high, motor MA turns
    clockwise
    analogWrite(PWMA, 100); //rotation speed of motor MA is 100
    digitalWrite(BIN2, HIGH); //when BIN2 is high and BIN1 is low, motor MB turns
    clockwise
    analogWrite(PWMB, 100); //rotation speed of motor MB is 100
}

void turnL() { //turn left
    digitalWrite(AIN2, HIGH); //when AIN2 is high and AIN1 is low, motor MA turns
    anticlockwise
    analogWrite(PWMA, 100); //rotation speed of motor MA is 100
    digitalWrite(BIN2, HIGH); //When BIN2 is high and BIN1 is low, motor MB turns
    clockwise
    analogWrite(PWMB, 100); //rotation speed of motor MB is 100
}

void turnR() { //turn right
    digitalWrite(AIN2, LOW); //when AIN2 is low and AIN1 is high, motor MA turns
    clockwise
    analogWrite(PWMA, 100); //rotation speed of motor MA is 100
    digitalWrite(BIN2, LOW); //when BIN2 is low and BIN1 is high, motor MB turns
```

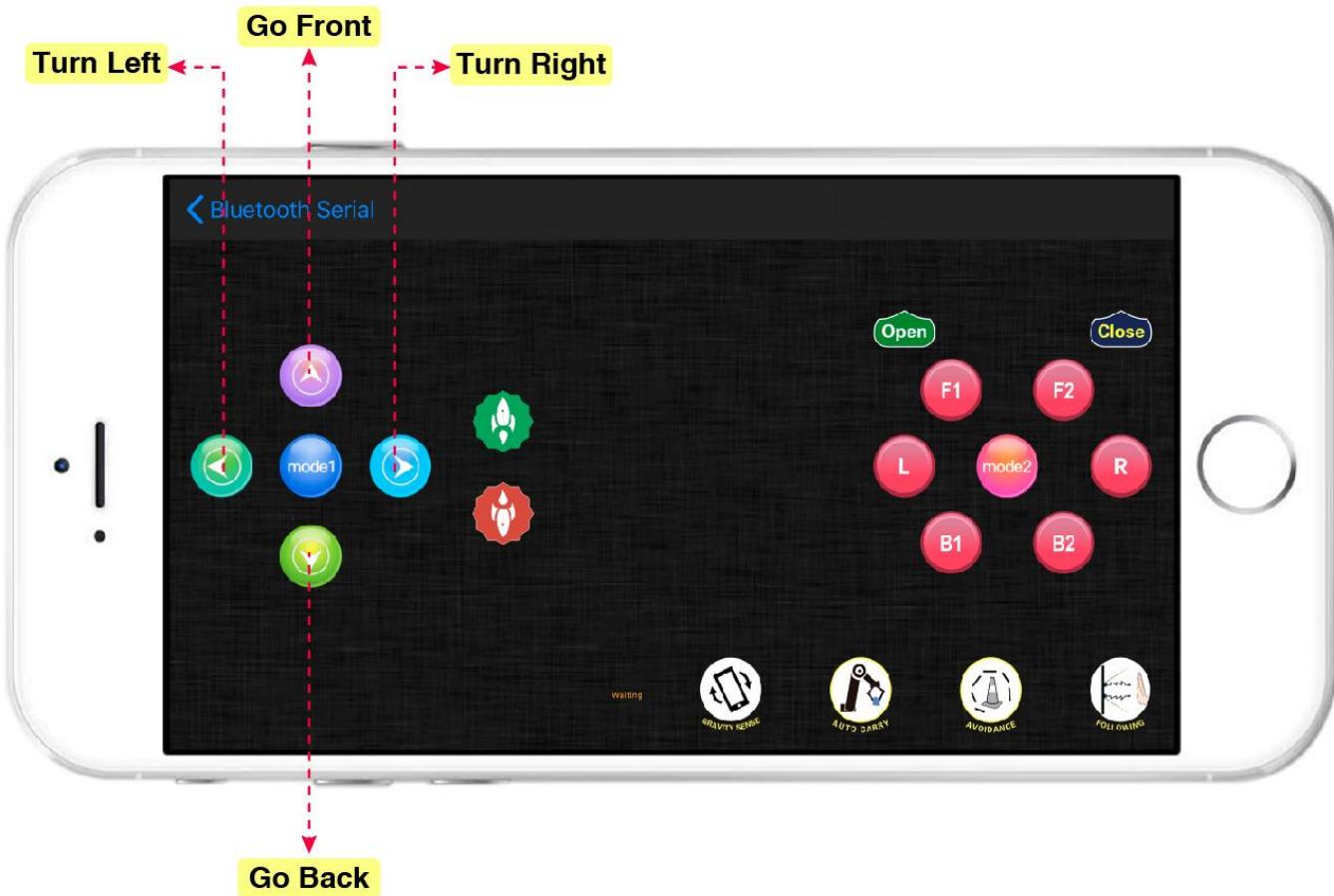


anticlockwise

```
analogWrite(PWMB, 100); //rotation speed of motor MB is 100  
}  
  
void back() { //go back  
    digitalWrite(BIN2, LOW); //when BIN2 is low and BIN1 is high, motor MB turns  
    anticlockwise  
    analogWrite(PWMB, 100); //rotation speed of motor MB is 100  
    digitalWrite(AIN2, HIGH); //when AIN2 is high and AIN1 is low, motor MA turns  
    anticlockwise  
    analogWrite(PWMA, 100); //rotation speed of motor MA is 100  
}  
  
void stopp() { //stop  
    analogWrite(PWMA, 0); //rotation speed of motor MA is 0  
    analogWrite(PWMB, 0); //rotation speed of motor MB is 0  
}
```

(4) Test Result:

Upload code, insert Bluetooth module and connect APP. Try left keys to drive smart car move.



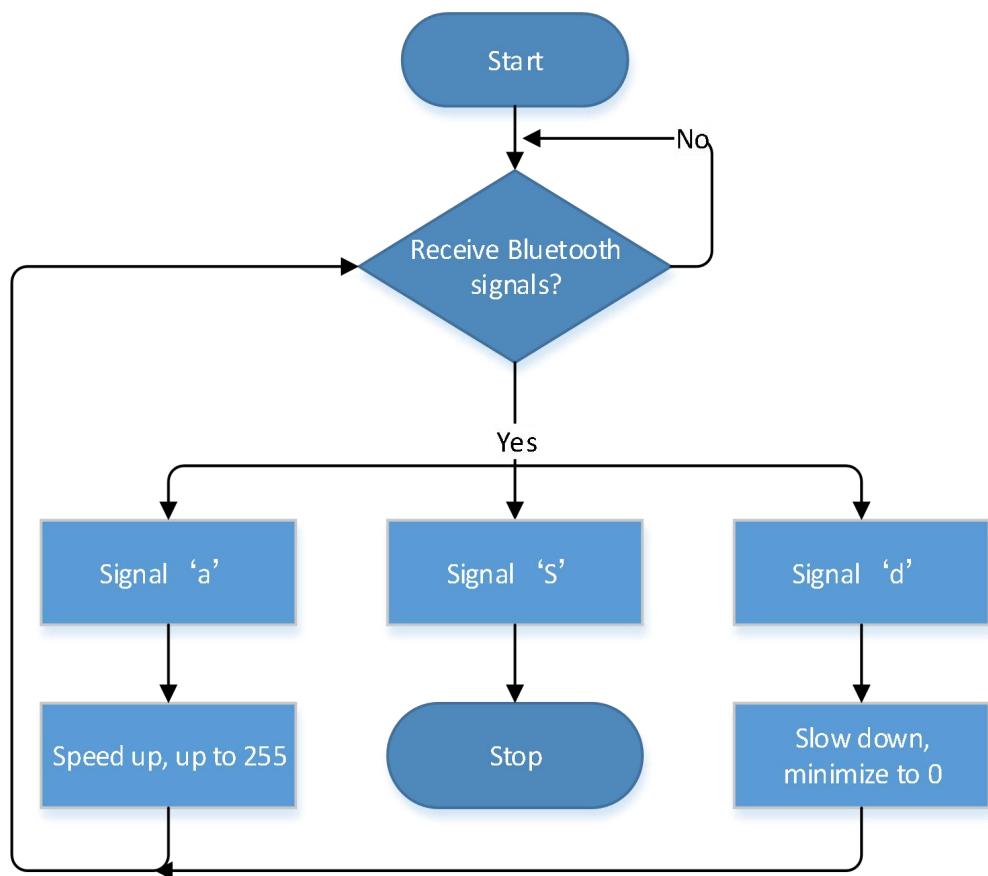
Project 12 Speed Control Robot

(1) Description:

We send commands to modulate the PWM values through app, so as to speed of car.

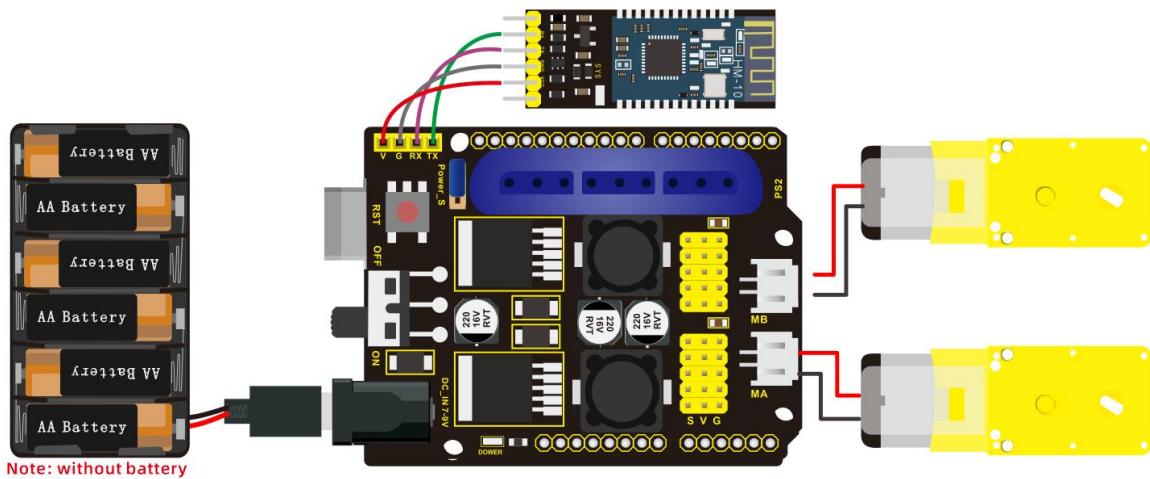


Flow Chart





(2) Connection Diagram:



(3) Test Code:

```
/*
```

keyestudio 4DOF Mechanical Robot Arm Car

lesson 12.1

Speed control robot

<http://www.keyestudio.com>

```
*/
```

```
int AIN2 = 2; //define driving pins of motor
```

```
int PWMA = 3;
```

```
int BIN2 = 4; //when AIN2 is low and AIN1 is high, when BIN2 is high and BIN1  
is low
```

```
int PWMB = 5;
```

```
int speeds=100;
```



```
void setup() {  
    Serial.begin(9600);  
    pinMode(AIN2, OUTPUT); //set ports of motor to output  
    pinMode(PWMA, OUTPUT);  
    pinMode(BIN2, OUTPUT);  
    pinMode(PWMB, OUTPUT);  
    stopp(); //stop  
  
void loop() {  
    if (Serial.available() > 0) { //receive Bluetooth signals  
        switch (Serial.read()) {  
            case 'F': advance(); Serial.println("advance"); break; //receive 'F' ,  
go forward  
  
            case 'B': back(); Serial.println("back"); break; //receive 'B' , go back  
  
            case 'L': turnL(); Serial.println("turn left"); break; //receive 'L' , turn left  
  
            case 'R': turnR(); Serial.println("turn right"); break; //receive 'R' , turn right  
  
            case 'S': stopp(); Serial.println("stop"); break; //receive 'S' , stop
```



```
case 'a': speeds_a(); break; //receive 'a'

case 'd': speeds_d(); break; //receive 'd'

}

}

void advance() { //go back

    digitalWrite(AIN2, LOW); //When AIN2 is low and AIN1 is high, motor MA turns
clockwise

    analogWrite(PWMA, speeds); //rotation speed of motor MA is speeds

    digitalWrite(BIN2, HIGH); //When BIN2 is high and BIN1 is low, motor MB turns
clockwise

    analogWrite(PWMB, speeds); //rotation speed of motor MB is speeds

}

void turnL() { //turn left

    digitalWrite(AIN2, HIGH); //When AIN2 is high and AIN1 is low, motor MA turns
anticlockwise

    analogWrite(PWMA, speeds); //rotation speed of motor MA is speeds

    digitalWrite(BIN2, HIGH); //When BIN2 is high and BIN1 is low, motor MB turns
clockwise

    analogWrite(PWMB, speeds); //rotation speed of motor MB is speeds
```



```
}

void turnR() { //turn right

    digitalWrite(AIN2, LOW); //When AIN2 is low and AIN1 is high, motor MA turns
    clockwise

    analogWrite(PWMA, speeds); //rotation speed of motor MA is speeds

    digitalWrite(BIN2, LOW); //When BIN2 is low and BIN1 is high, motor MB turns
    anticlockwise

    analogWrite(PWMB, speeds); //rotation speed of motor MB is speeds

}

void back() { //go back

    digitalWrite(BIN2, LOW); //When BIN2 is low and BIN1 is high, motor MB
    turns anticlockwise

    analogWrite(PWMB, speeds); //rotation speed of motor MB is speeds

    digitalWrite(AIN2, HIGH); //When AIN2 is high and AIN1 is low, motor MA turns
    anticlockwise

    analogWrite(PWMA, speeds); //rotation speed of motor MA is speeds

}

void stopp() { //stop

    analogWrite(PWMA, 0); //rotation speed of MA is 0
    analogWrite(PWMB, 0); //rotation speed of MB is 0

}
```



```
void speeds_a(){

    int a_flag=1;

    while(a_flag){

        Serial.println(speeds);

        if(speeds<=254){ //add speed up to 255

            speeds++;

            delay(10); //change the delayed time to alter the acceleration

        }

        char blue_val=Serial.read();

        if(blue_val=='S') a_flag=0; //receive 'S' to stop acceleration

    }

}
```

```
void speeds_d(){

    int d_flag=1;

    while(d_flag){

        Serial.println(speeds);

        if(speeds>=1){ //reduce speed to 0 at least

            speeds--;

            delay(10); //change the delayed time to speed down

        }

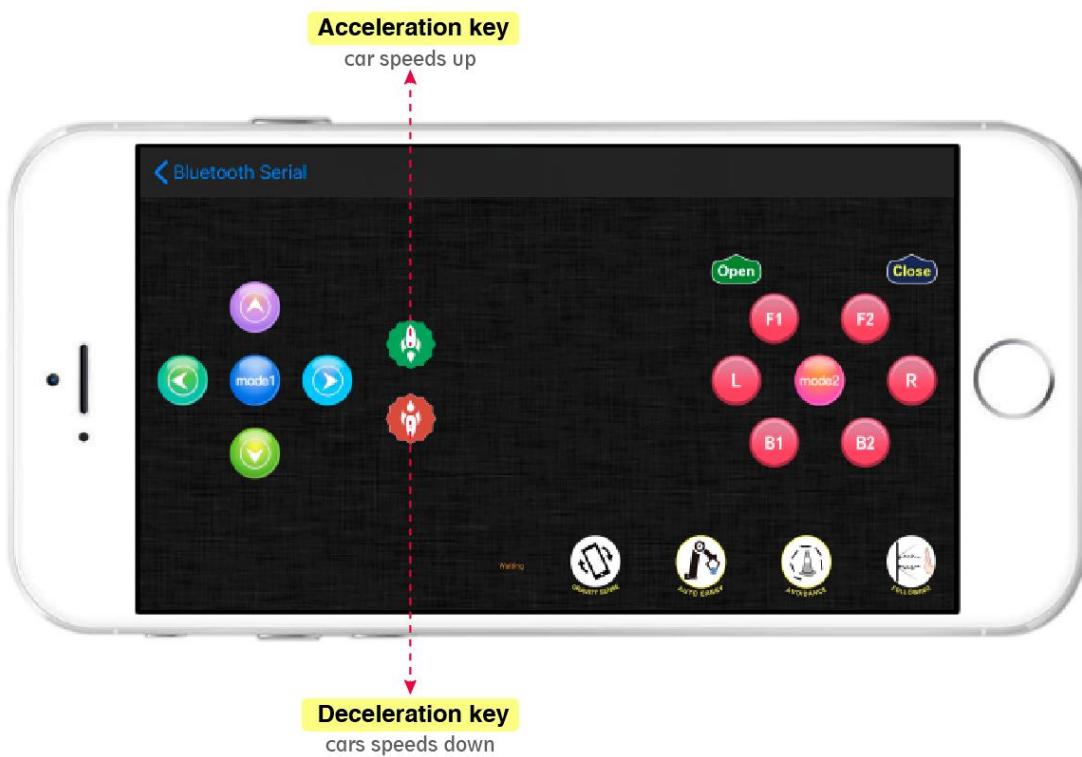
        char blue_val=Serial.read();
```

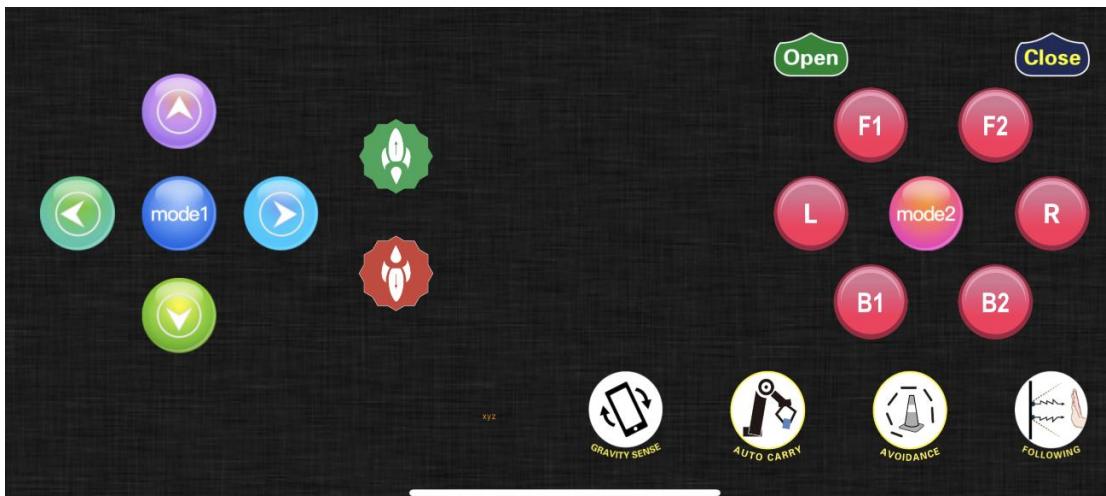


```
if(blue_val=='S') d_flag=0; //receive 'S' , stop to reduce speed  
}  
}  
}
```

(4) Test Result:

When the acceleration key is pressed, car will speed up to maximum value; if you press the deceleration key, car will slow down to minimum 0; and release the button to stop.



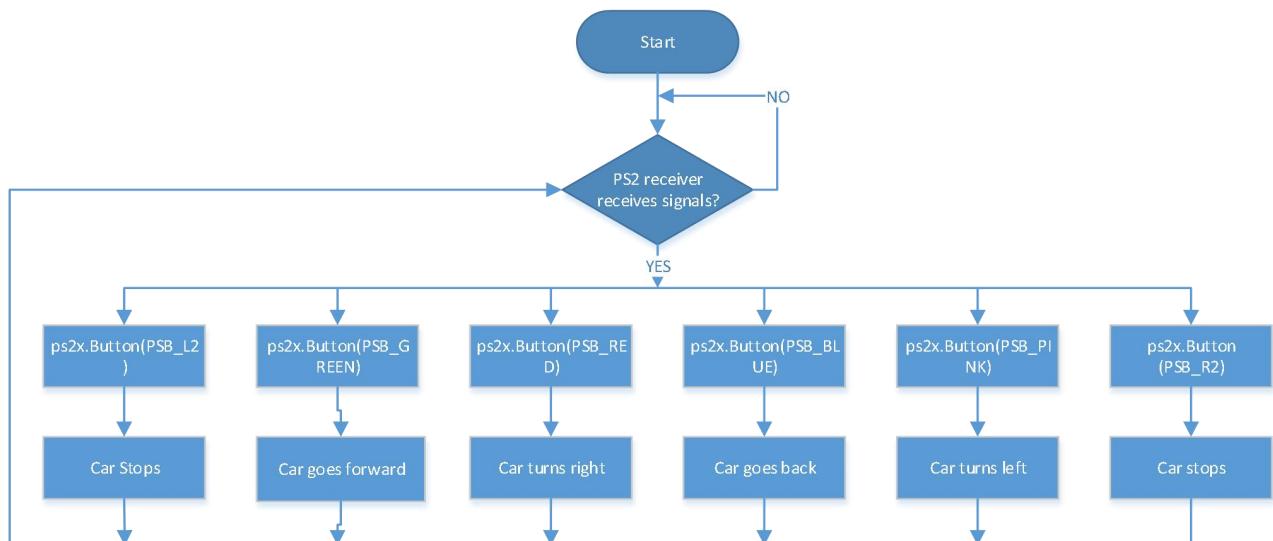


Project 13 PS2 Joypad Control

(1) Description:

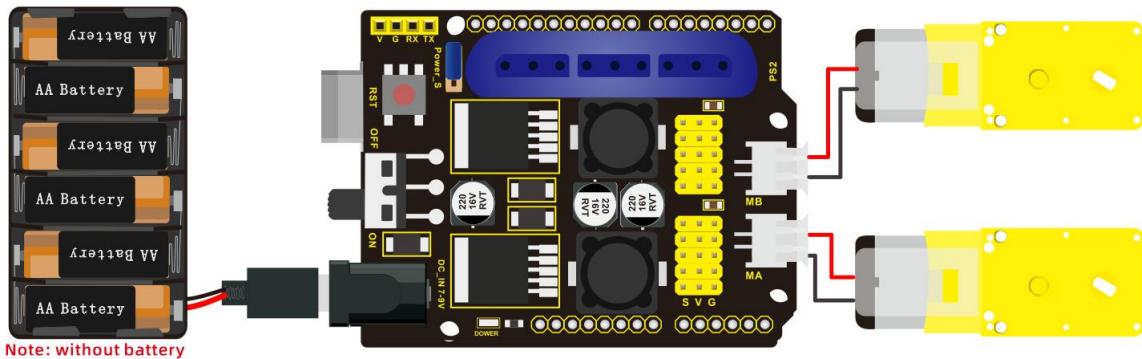
The key values on PS2 joypad are tested. Next, let's control smart car by PS2 joypad.

Flow Chart





(2) Connection Diagram:



(3) Test Code:

```
/*
keyestudio 4DOF Mechanical Robot Arm Car
lesson 13.1

PS2 control robot

http://www.keyestudio.com

*/
#include <PS2X_lib.h>

#define PS2_DAT    12
#define PS2_CMD    11
#define PS2_SEL    10
#define PS2_CLK    13

int AIN2=2; //define the driving pins of motor
int PWMA=3;
```



```
int BIN2=4; //when AIN2 is low and AIN1 is high, BIN2 is high and BIN1 is low
int PWMB=5;
#define pressures    false
#define rumble      false
PS2X ps2x;
int error=0;
byte type=0;
byte vibrate=0;

void setup(){
    Serial.begin(9600);
    pinMode(AIN2, OUTPUT); //set ports of motor to output
    pinMode(PWMA, OUTPUT);
    pinMode(BIN2, OUTPUT);
    pinMode(PWMB, OUTPUT);
    delay(300);
    error=ps2x.config_gamepad(PS2_CLK,    PS2_CMD,    PS2_SEL,    PS2_DAT,
pressures, rumble);
    if(error==0){
        Serial.println("Found Controller, configured successful ");
    }
    stopp();
```



{}

```
void loop(){
    if(error!=0) return;
    else{
        ps2x.read_gamepad(false, vibrate);

        vibrate = ps2x.Analog(PSAB_CROSS);
        if (ps2x.NewButtonState()){
            if(ps2x.Button(PSB_L2)) {Serial.println("L2
pressed,stop");stopp();}
            if(ps2x.Button(PSB_R2)) {Serial.println("R2
pressed,stop");stopp();}
            if(ps2x.Button(PSB_GREEN)) {Serial.println("Triangle
pressed,advance");advance();}
            if(ps2x.Button(PSB_RED)) {Serial.println("Circle  pressed,turn
right");turnR();}
            if(ps2x.Button(PSB_BLUE)) {Serial.println("X pressed,back");back();}
            if(ps2x.Button(PSB_PINK)) {Serial.println("Square  pressed,turn
left");turnL();}
        }
    }
}
```



```
delay(50);

}

void advance() { //go forward
    digitalWrite(AIN2, LOW); //when AIN2 is low and AIN1 is high, motor MA turns
clockwise
    analogWrite(PWMA, 100); //rotation speed of motor MA is 100
    digitalWrite(BIN2, HIGH); //When BIN2 is high and BIN1 is low, motor MB turns
clockwise
    analogWrite(PWMB, 100); //rotation speed of motor MB is 100
}

void turnL() { //turn left
    digitalWrite(AIN2, HIGH); //when AIN2 is high and AIN1 is low, motor MA turns
anticlockwise
    analogWrite(PWMA, 100); //rotation speed of motor MA is 100
    digitalWrite(BIN2, HIGH); //When BIN2 is high and BIN1 is low, motor MB turns
clockwise
    analogWrite(PWMB, 100); //rotation speed of motor MB is 100
}

void turnR() { //turn right
    digitalWrite(AIN2, LOW); //when AIN2 is low and AIN1 is high, motor MA turns
clockwise
```



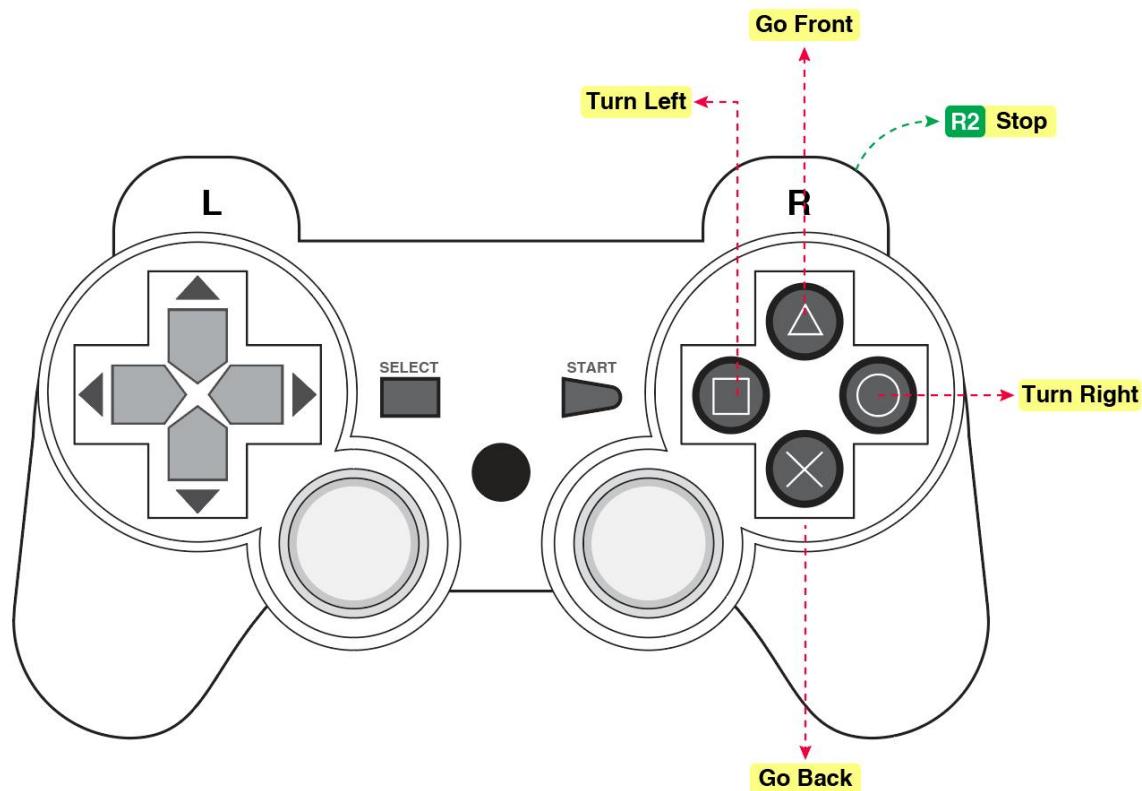
```
analogWrite(PWMA, 100); //rotation speed of motor MA is 100
digitalWrite(BIN2, LOW); //When BIN2 is low and BIN1 is high, motor MB turns
clockwise
analogWrite(PWMB, 100); //rotation speed of motor MB is 100
}

void back() { //go back
    digitalWrite(BIN2, LOW); //When BIN2 is low and BIN1 is high motor MB turns
anticlockwise
    analogWrite(PWMB, 100); //rotation speed of motor MB is 100
    digitalWrite(AIN2, HIGH); //when AIN2 is high and AIN1 is low, motor MA turns
anticlockwise
    analogWrite(PWMA, 100); //rotation speed of motor MA is 100
}

void stopp() { //stop
    analogWrite(PWMA, 0); //rotation speed of motor MA is 0
    analogWrite(PWMB, 0); //rotation speed of motor MB is 0
}
```

(4) Test Result:

Upload code and connect PS2 joypad, then smart car can demonstrate forward, back, stop and left and right turning.



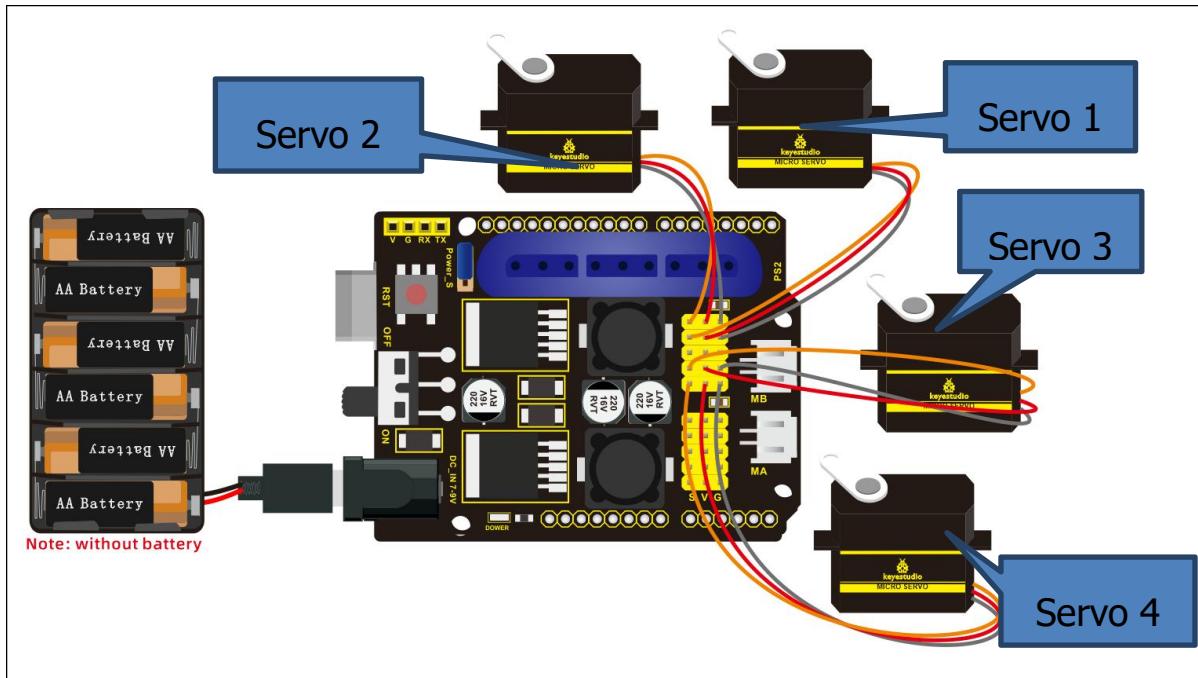
Project 14 Adjust Servo and Install Robot Arm

(1) Description:

We need to adjust angles of servo before installing robot arm. The following code is to initialize angle value of servo, which facilitates to install and adjust robot arm.



(2) Connection Diagram:



(3) Test Code:

```
/*
```

```
keyestudio 4DOF Mechanical Robot Arm Car
```

lesson 14

<http://www.keyestudio.com>

```
*/
```

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

```
Servo myservo1,myservo2,myservo3,myservo4;
```

```
int pos1=90,pos2=100,pos3=80,pos4=90;//initialize angle value of four
```



servos

```
void setup(){
```

```
    myservo1.attach(A1); //0~180---90,servo 1, servo on base is connected  
to A1
```

```
    myservo2.attach(A0); //0~100---100,servo 2, left servo is connected to  
A0
```

```
    myservo3.attach(8); //80~180---80,servo 3, right servo is connected to  
D8
```

```
    myservo4.attach(9); //90~180---90, servo 4, servo on claw is connected  
to D9
```

```
    delay(1000);
```

```
    myservo1.write(pos1); //servo 1 rotates to 90°
```

```
    myservo2.write(pos2); //servo 2 rotates to 100°
```

```
    myservo3.write(pos3); //servo 3 rotates to 80°
```

```
    myservo4.write(pos4); //servo 4 rotates to 90°
```

```
}
```

```
void loop(){
```

```
}
```

(4) Test Result:

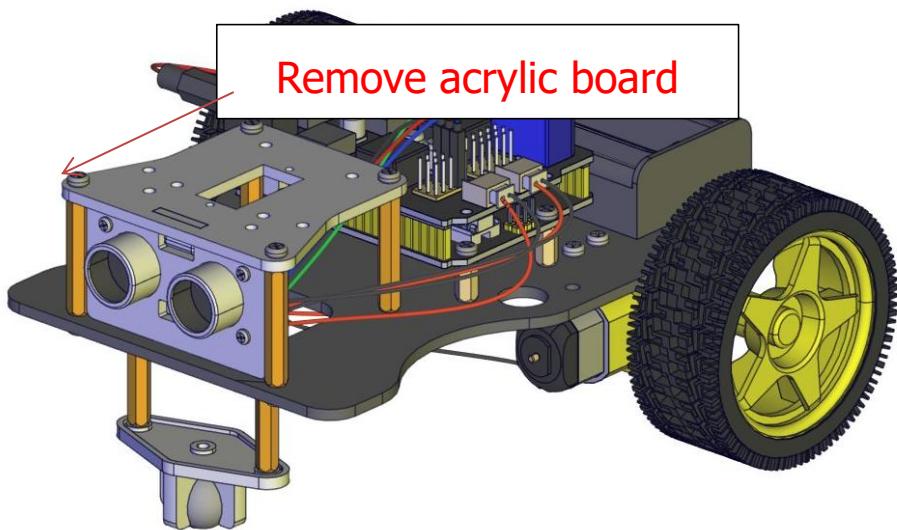
Servo 1 and 4 rotate to 90°, servo 2 rotates to 100°, and servo 3 rotates to 80°.



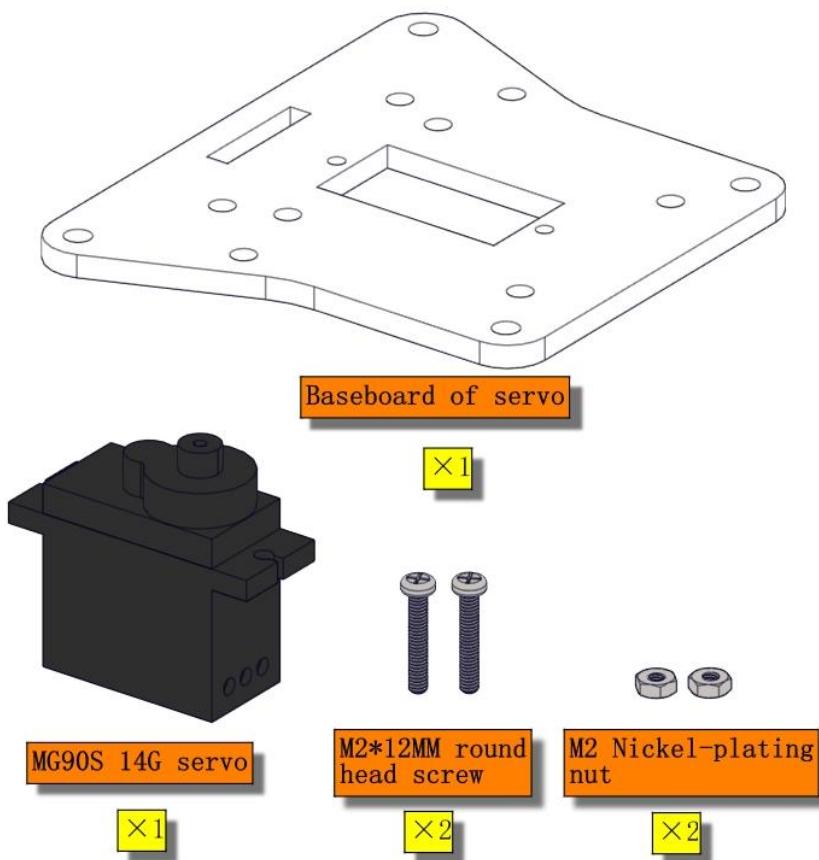
Note: Don't make servo rotate before finishing the installation of robot arm. Otherwise, the initial angle of servo will be influenced, causing failure installation.

(5) Install Arm:

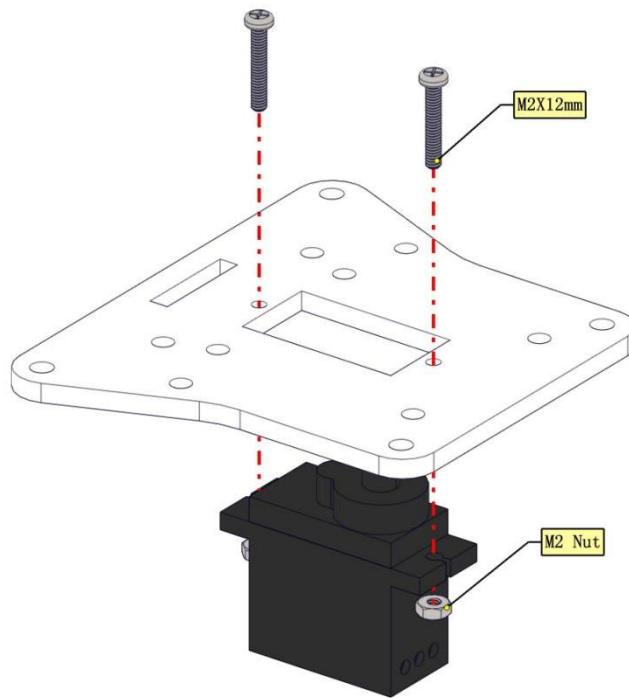
Part 1

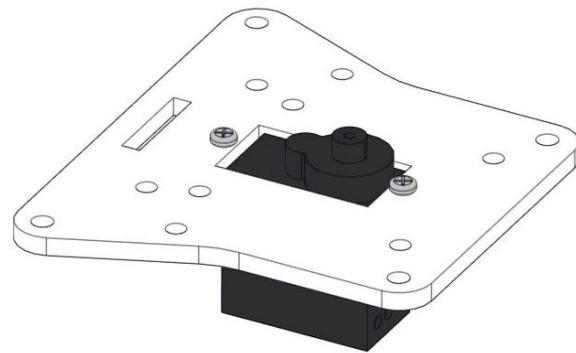


Mount Servo 1

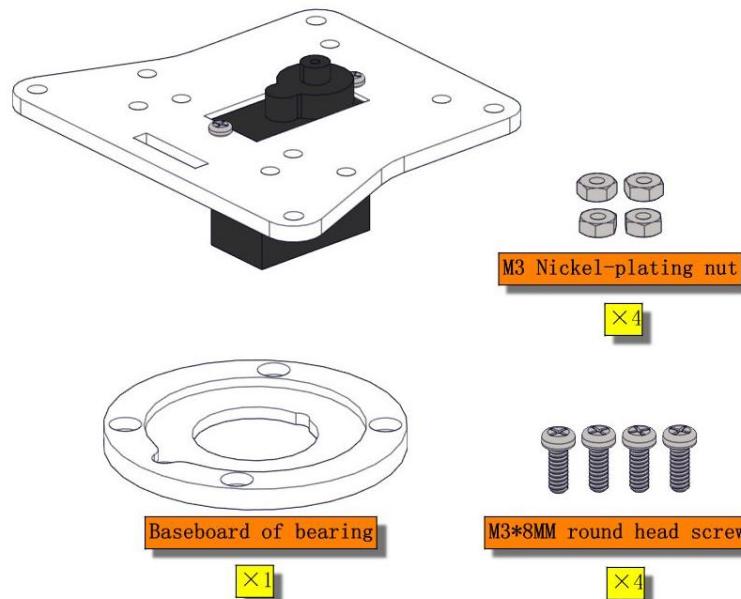


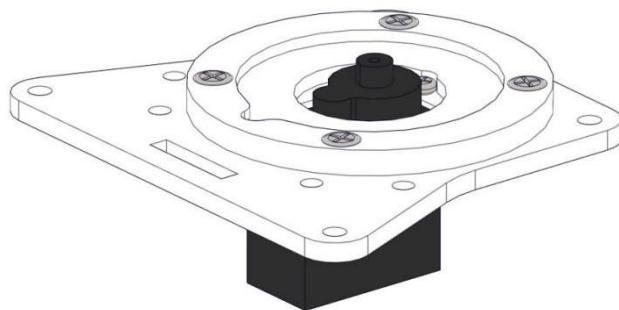
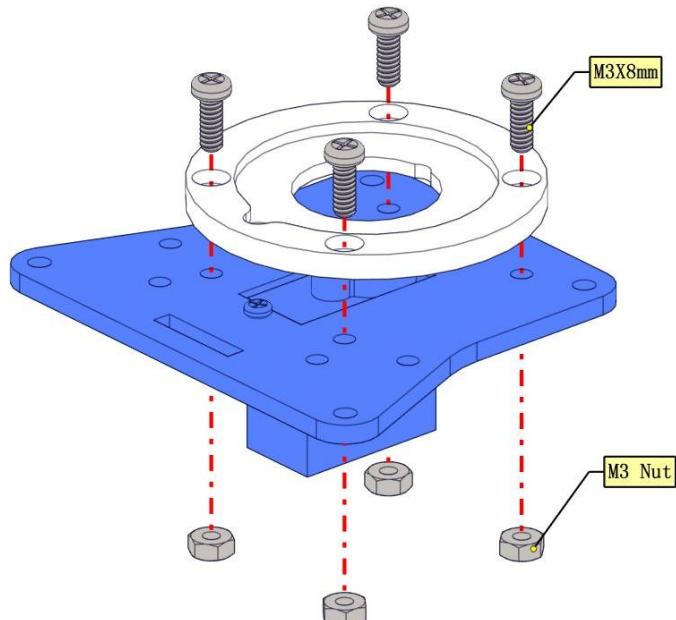
Use purple
screwdriver



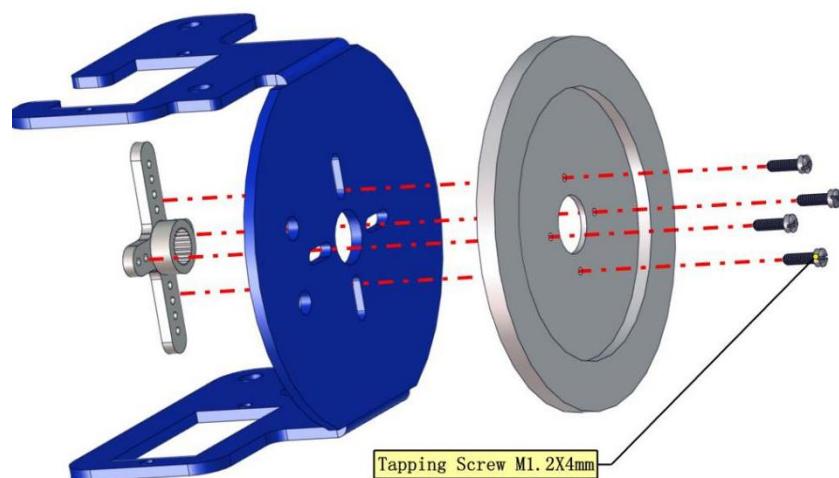
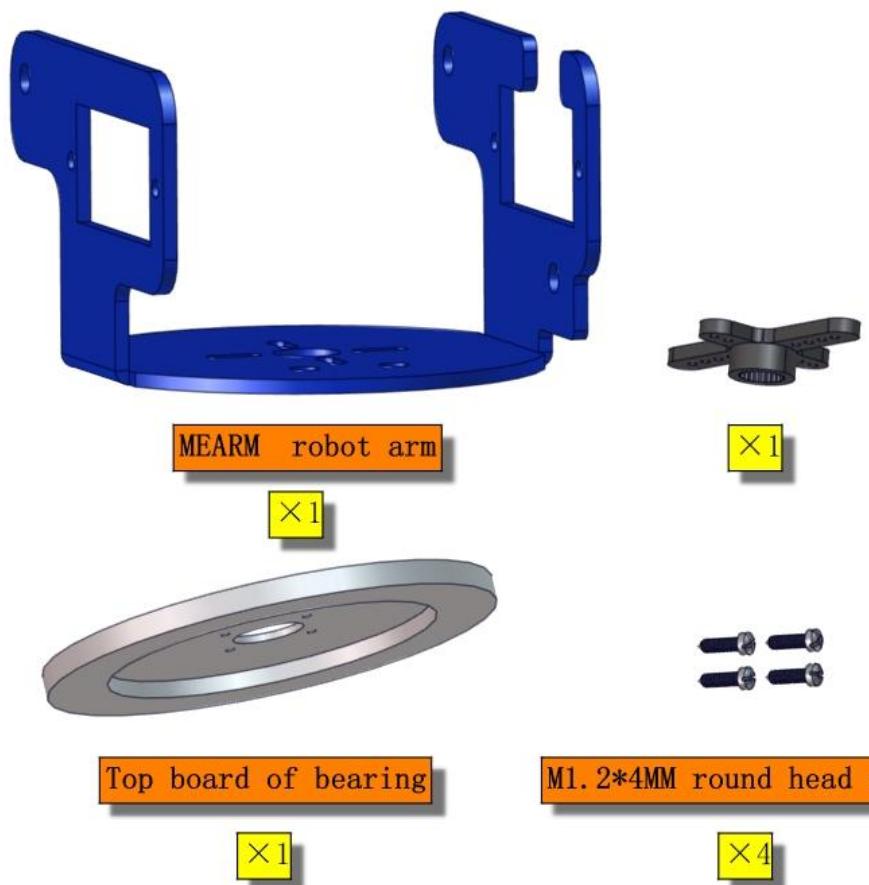


Install bearing



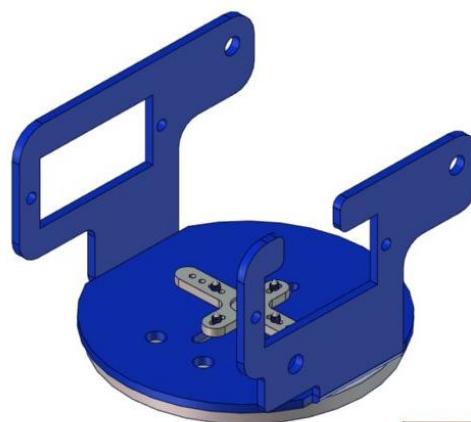


Mount Arm Parts



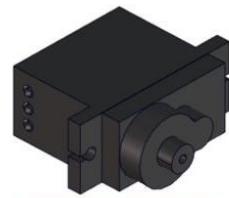


This is servo 3



M2 Nickel-plating nut

×2



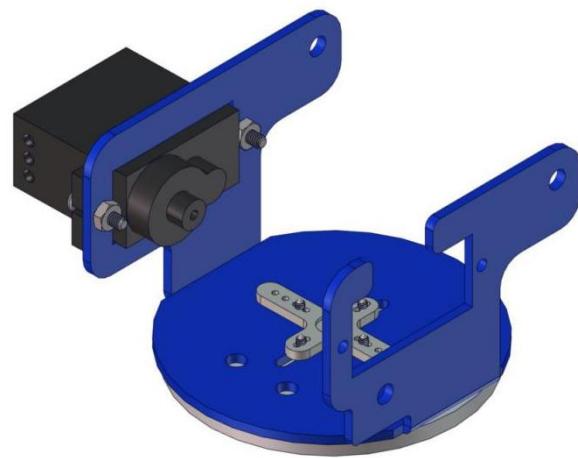
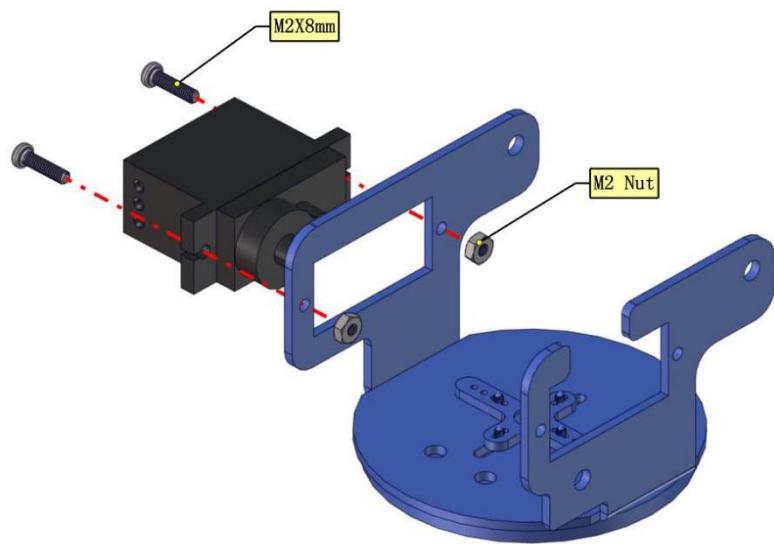
MG90S 14G servo

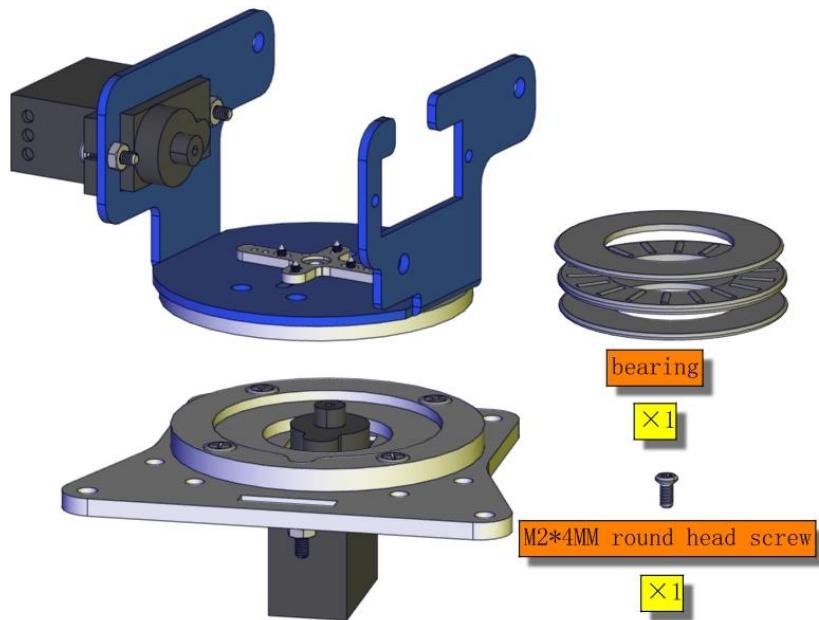
×1



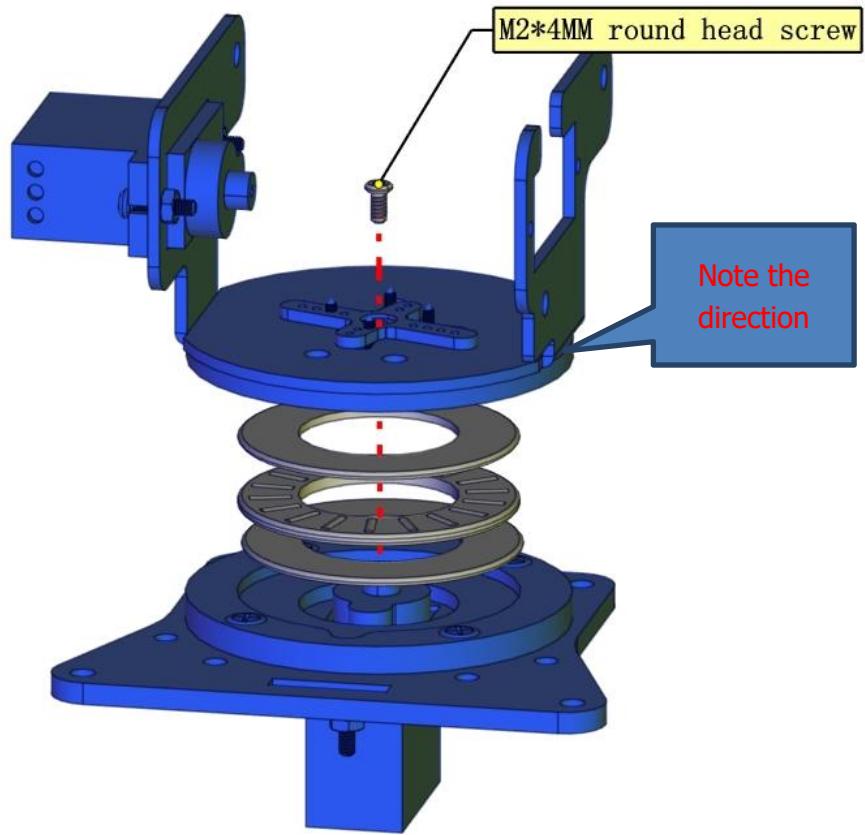
M2*8MM round head screw

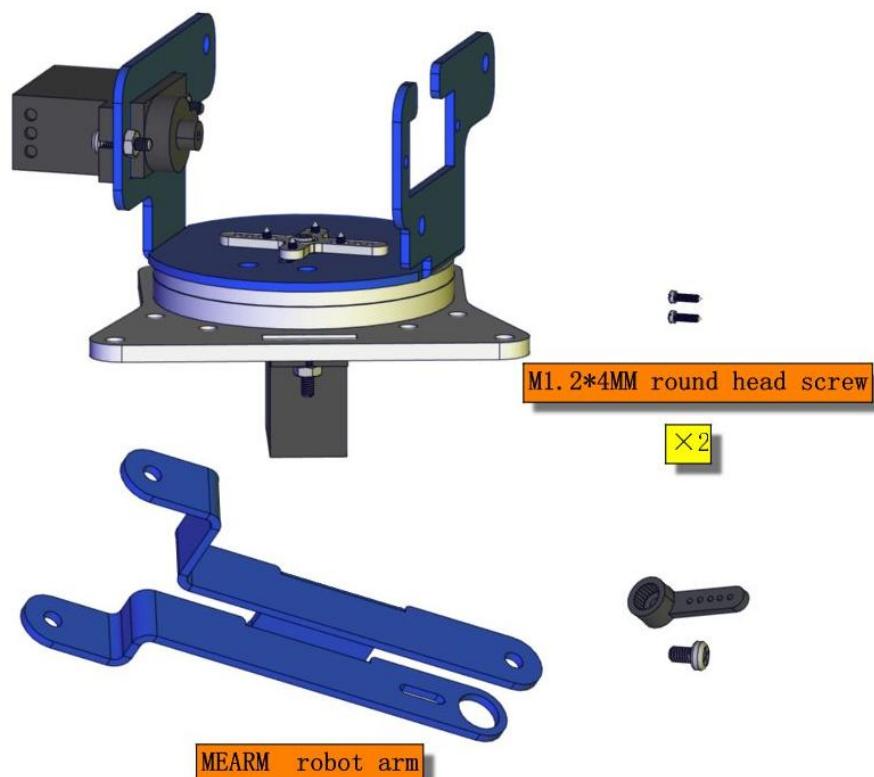
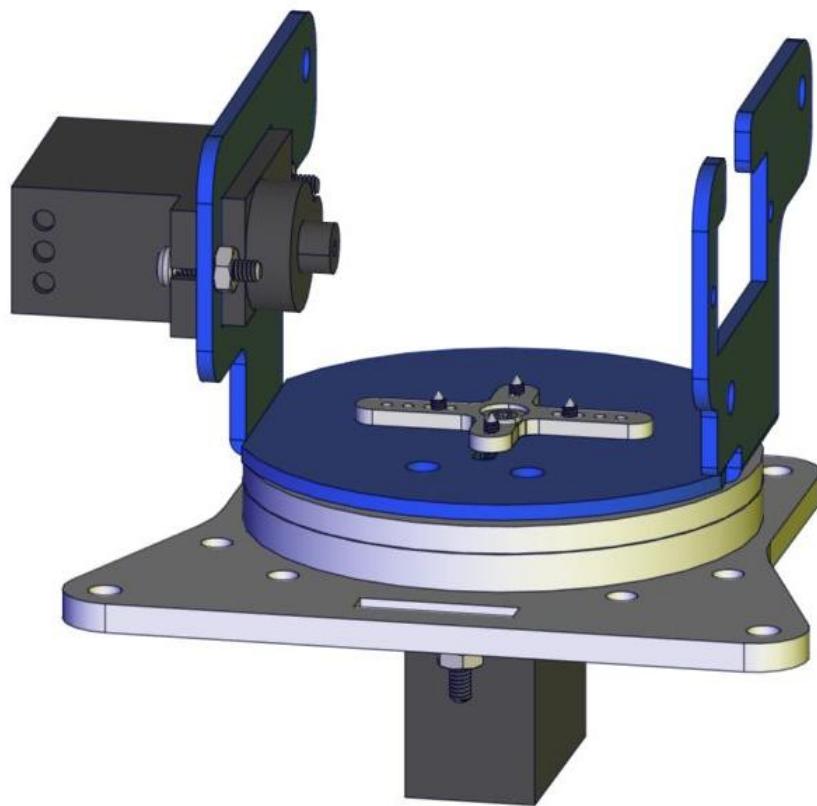
×2

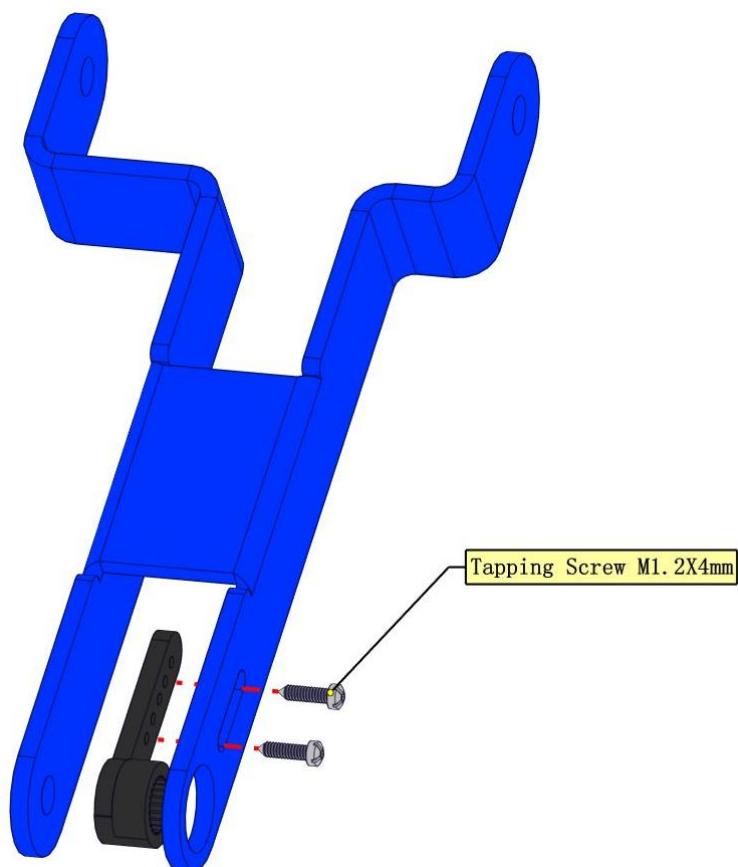


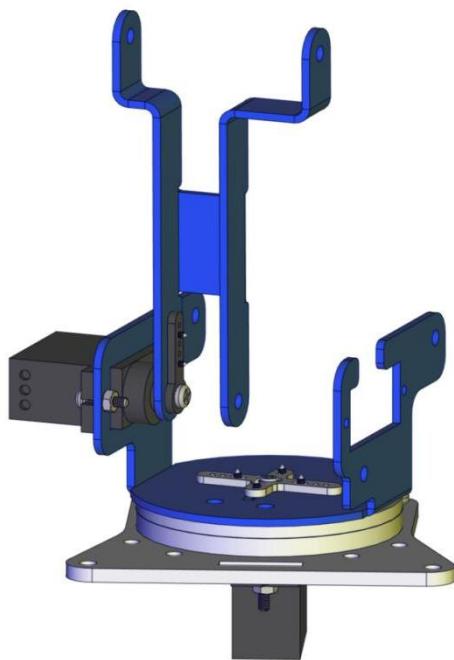
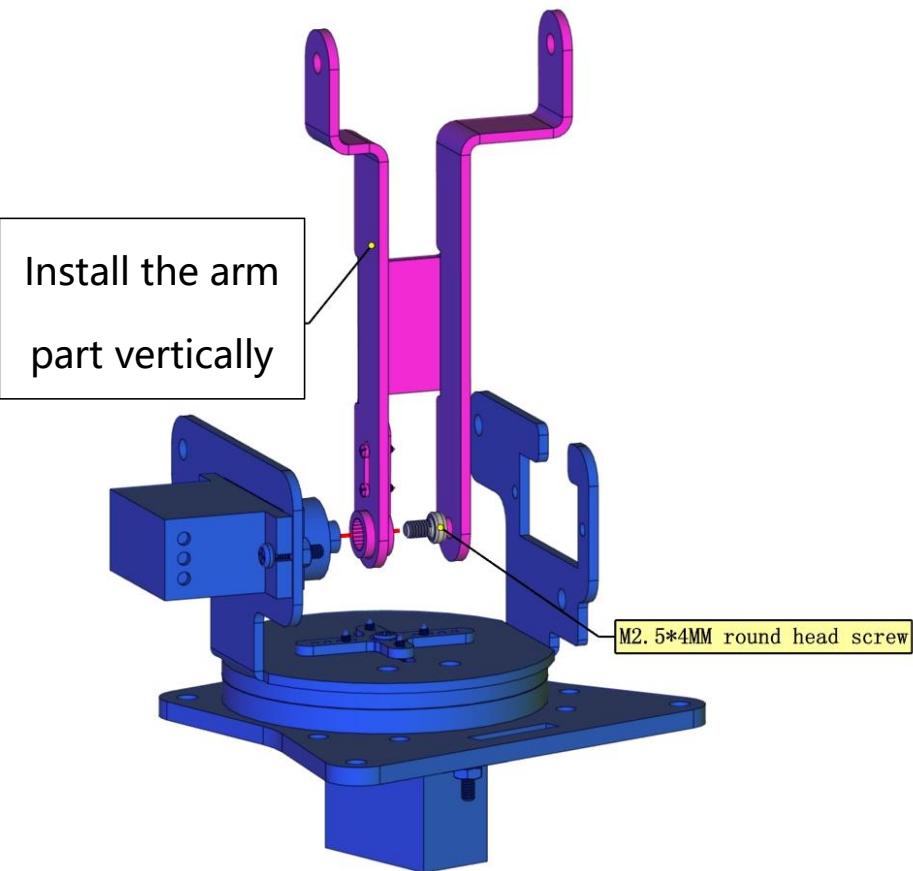


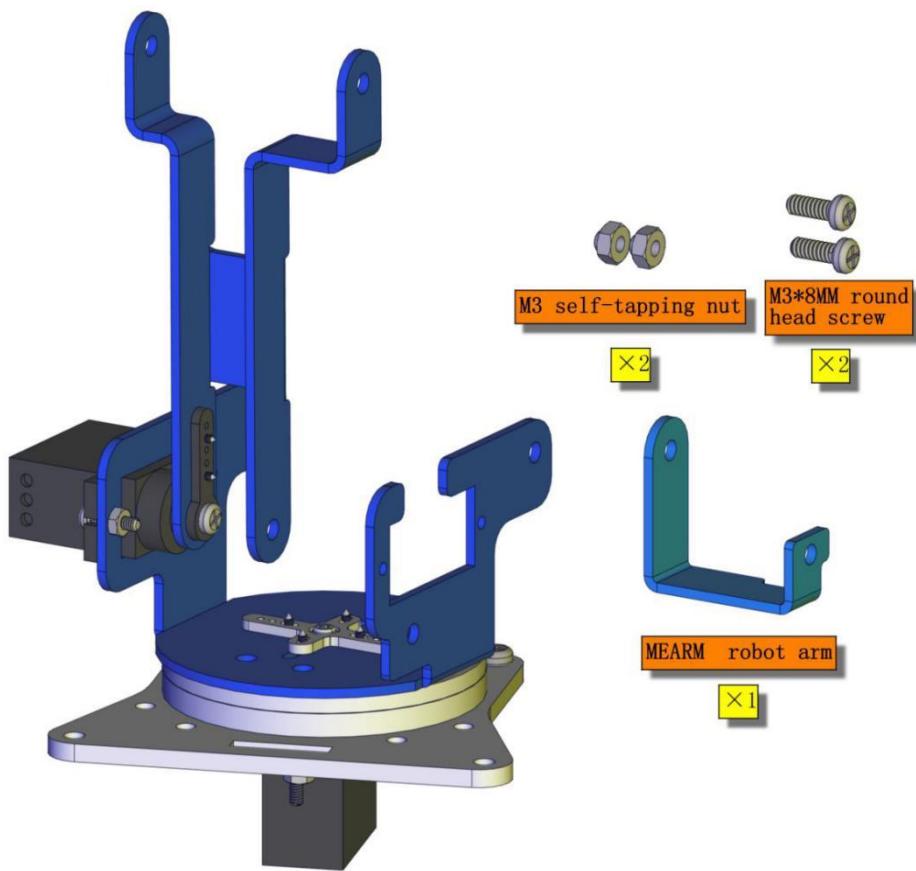
Mount it
according to
diagram

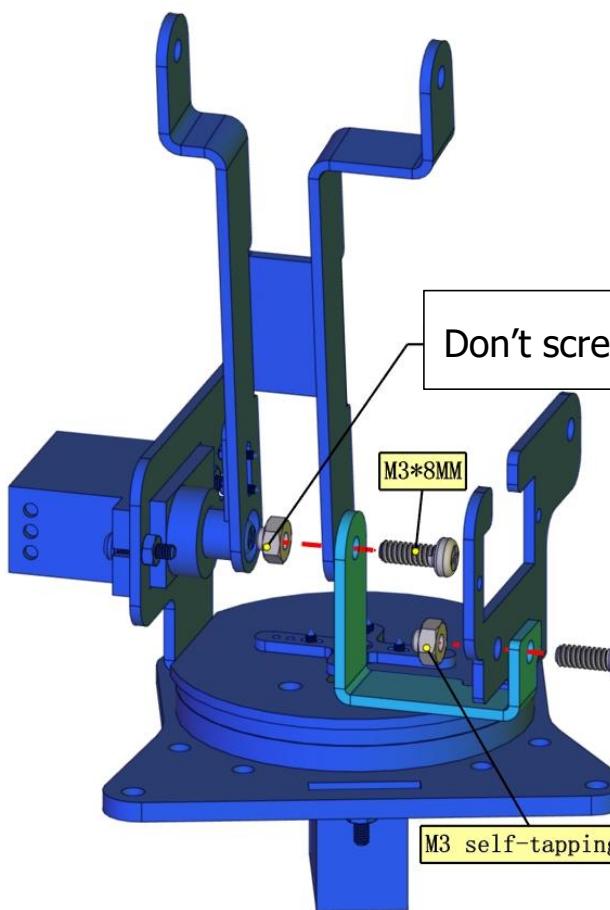


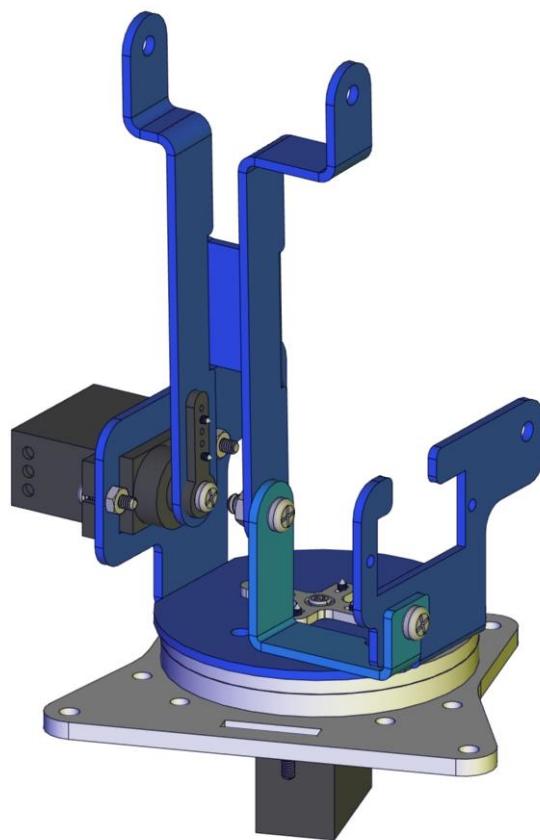




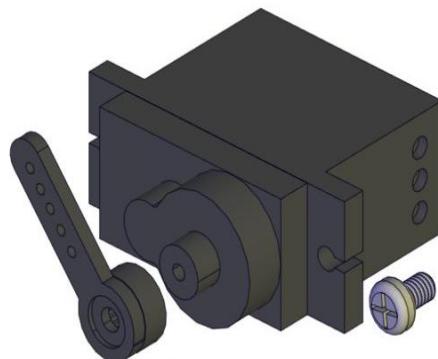








This is servo 2



MG90S 14G servo

X1



MEARM robot arm

X1

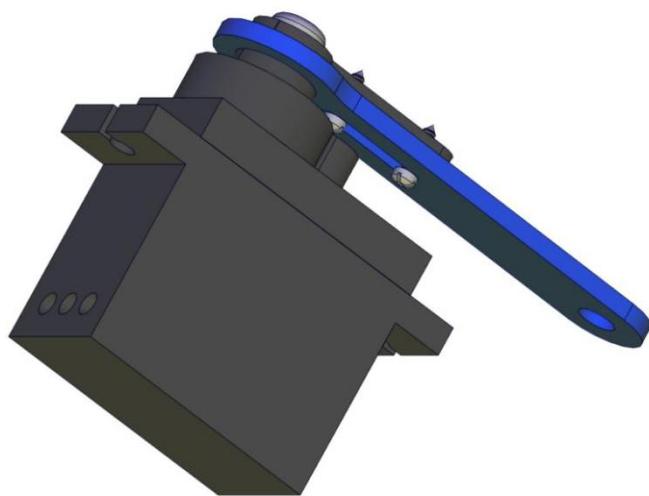
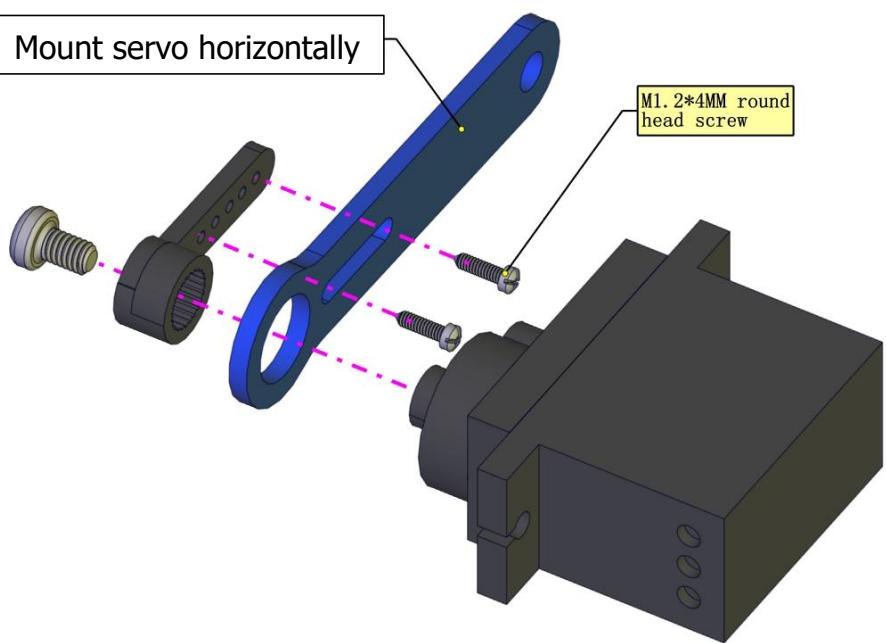


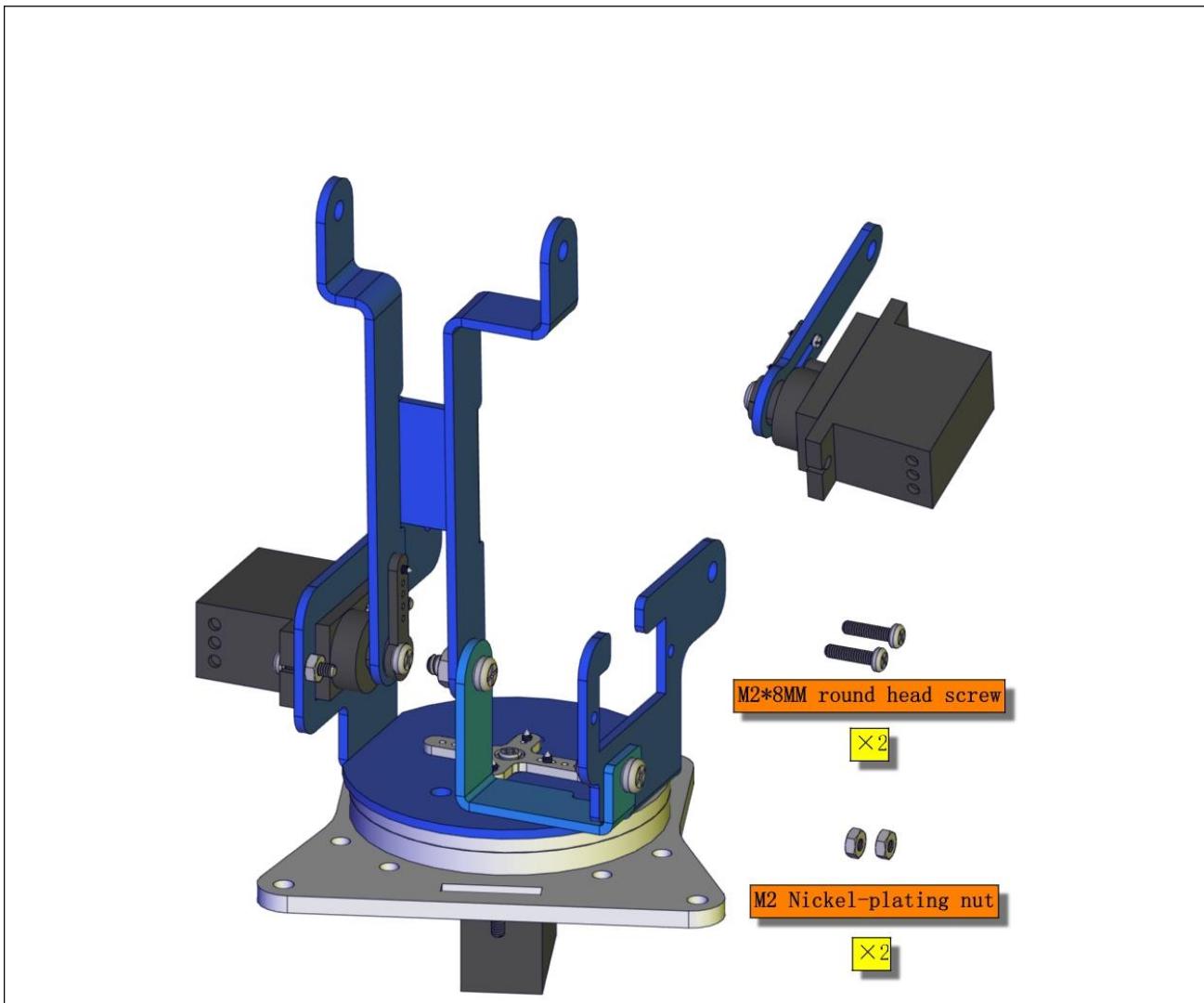
M1.2*4MM round
head screw

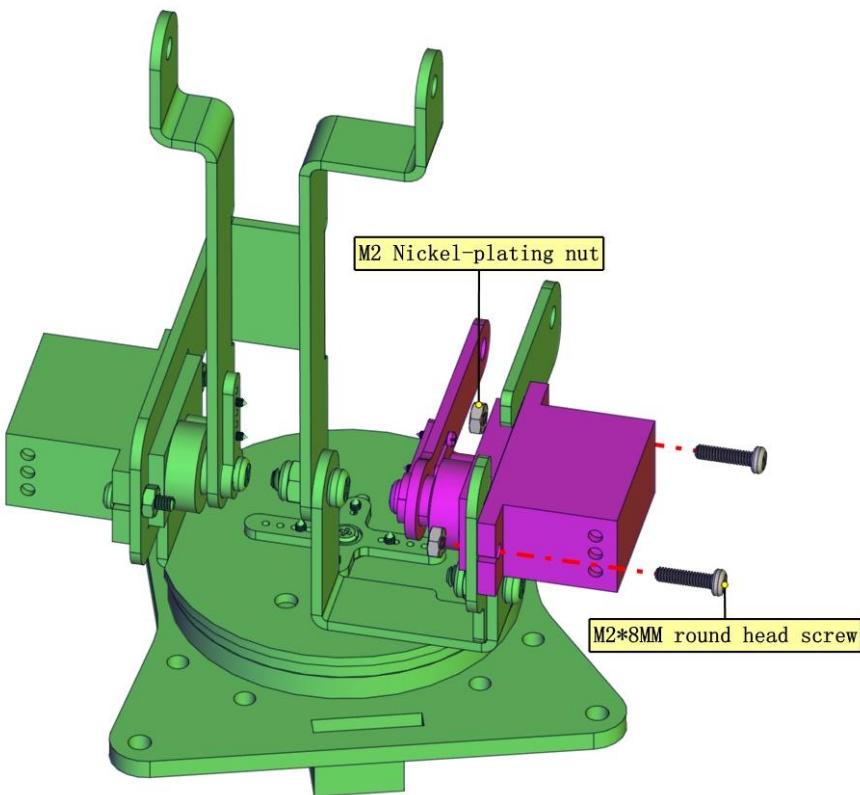
X2

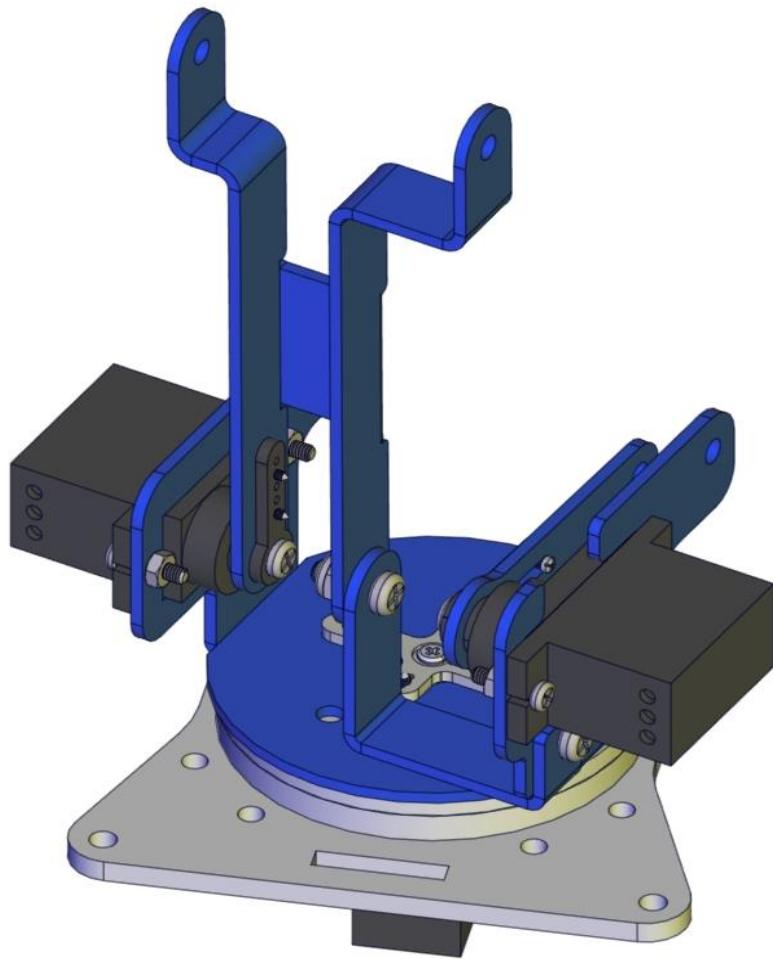


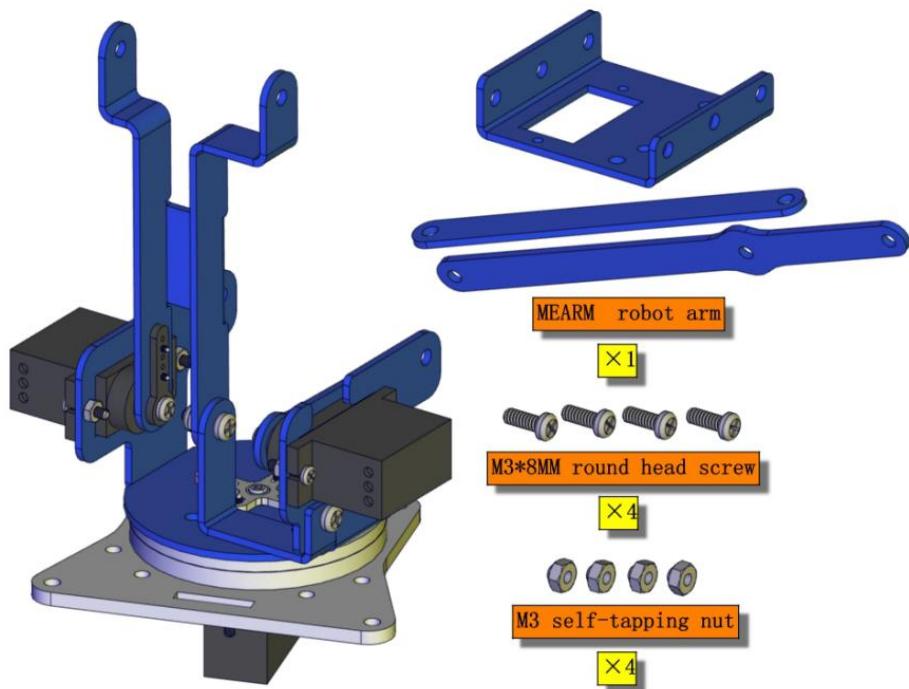
Mount it
according to
diagram



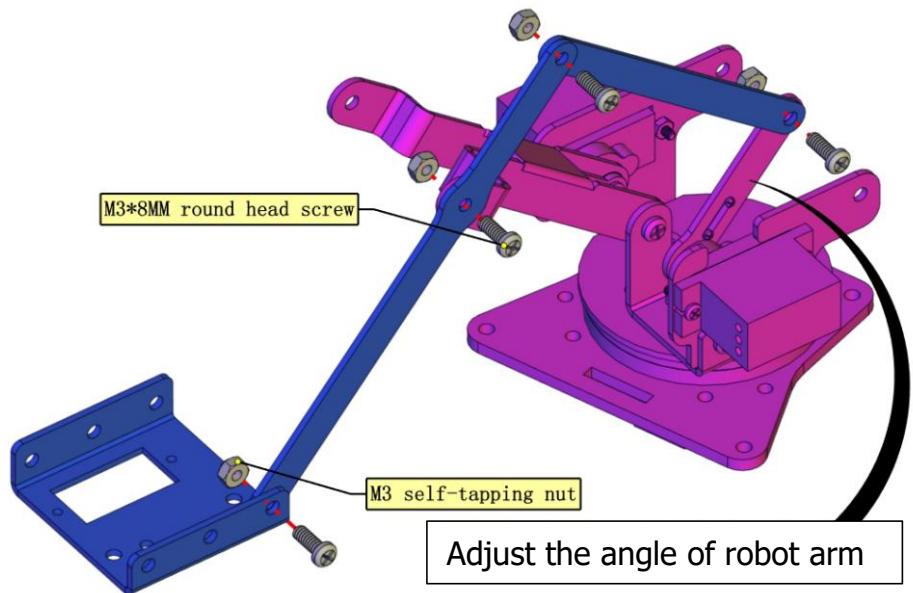


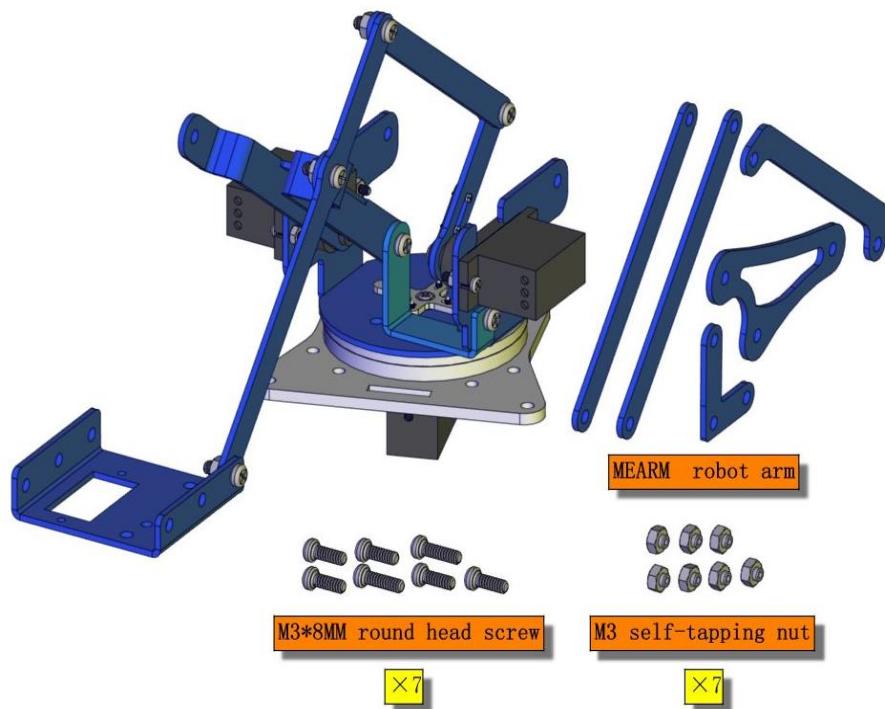
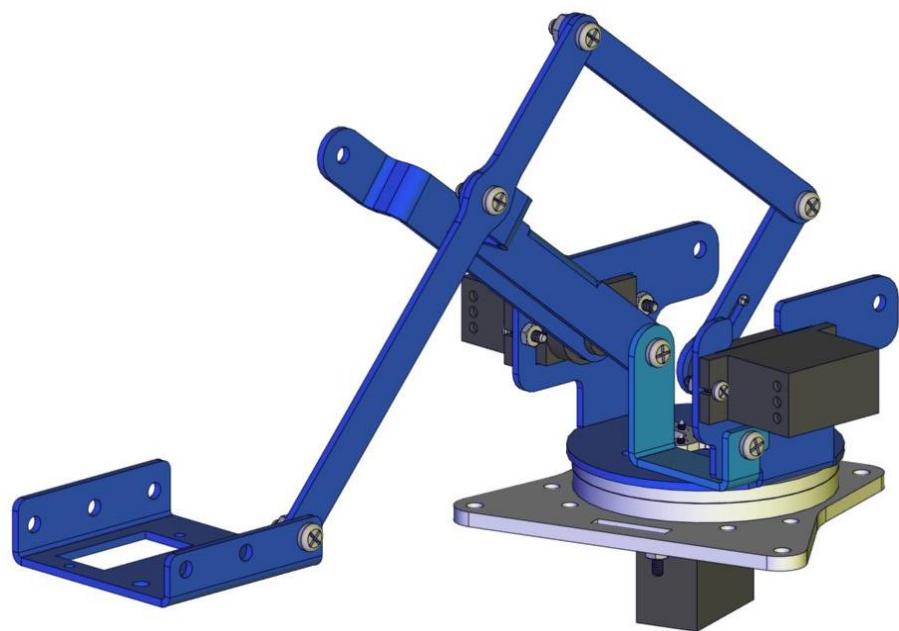






Don't screw nuts too tightly





M3*8MM round head screw

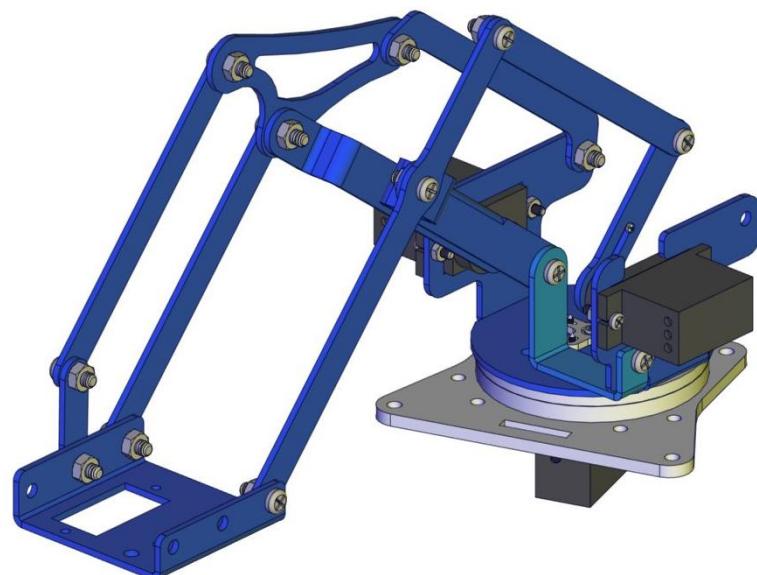
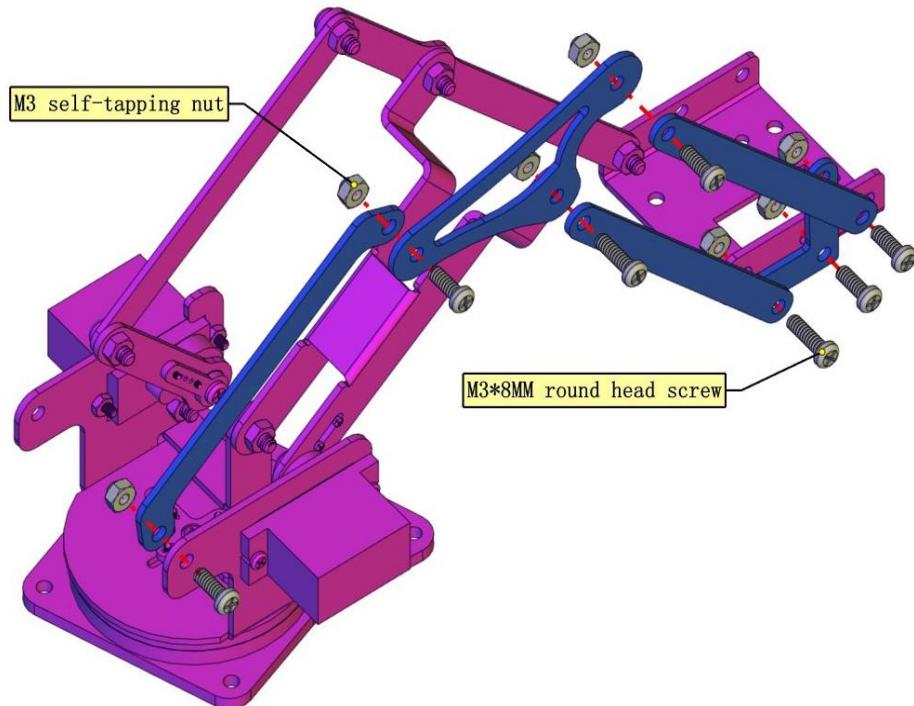
×7

M3 self-tapping nut

×7

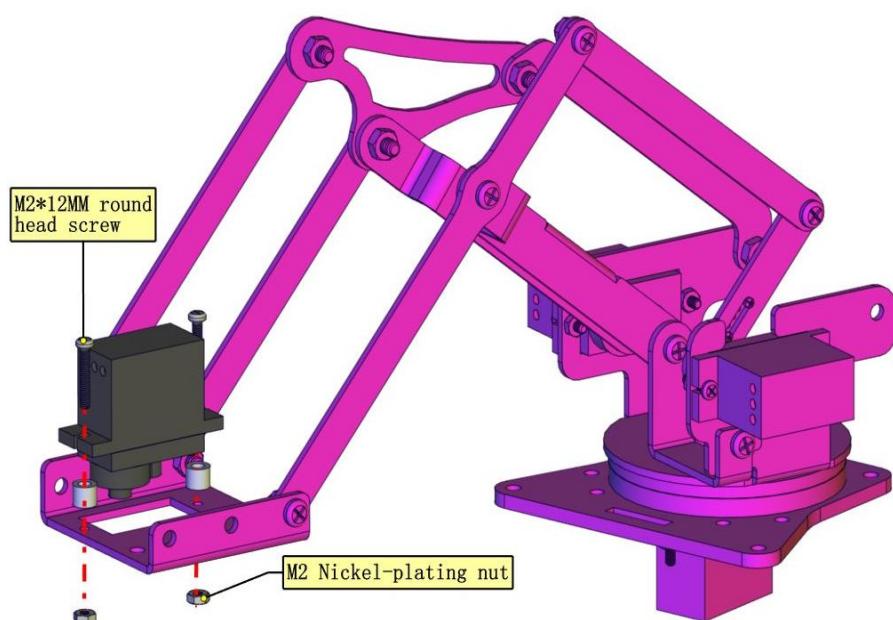
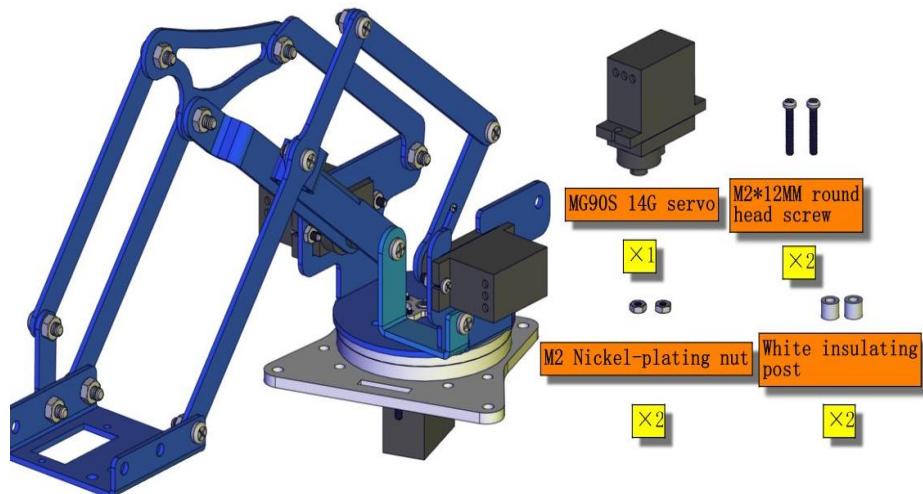


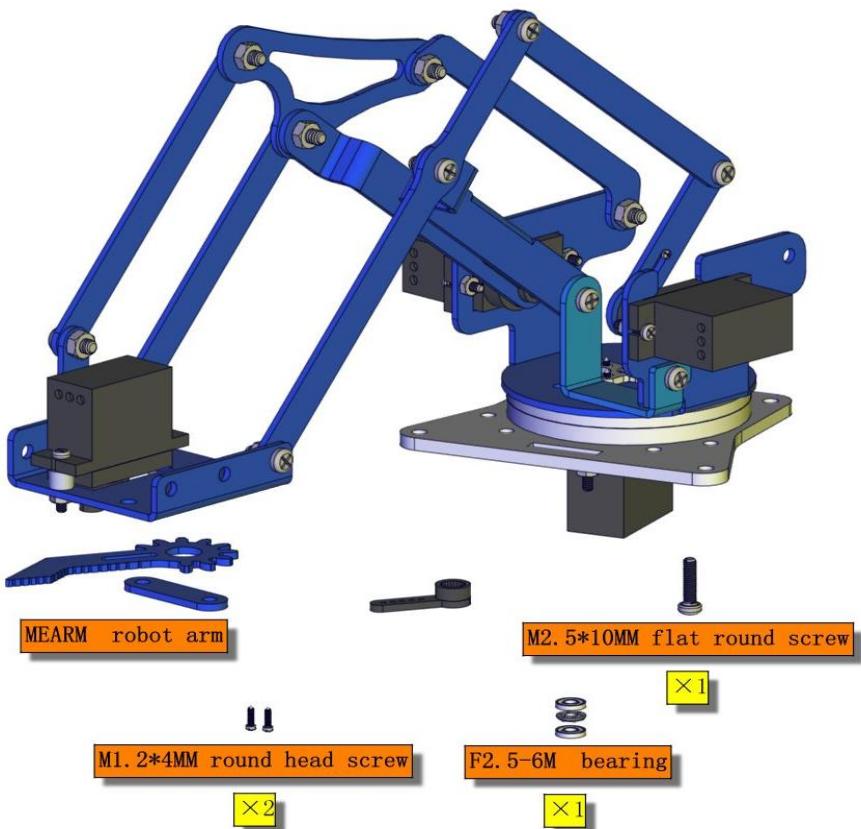
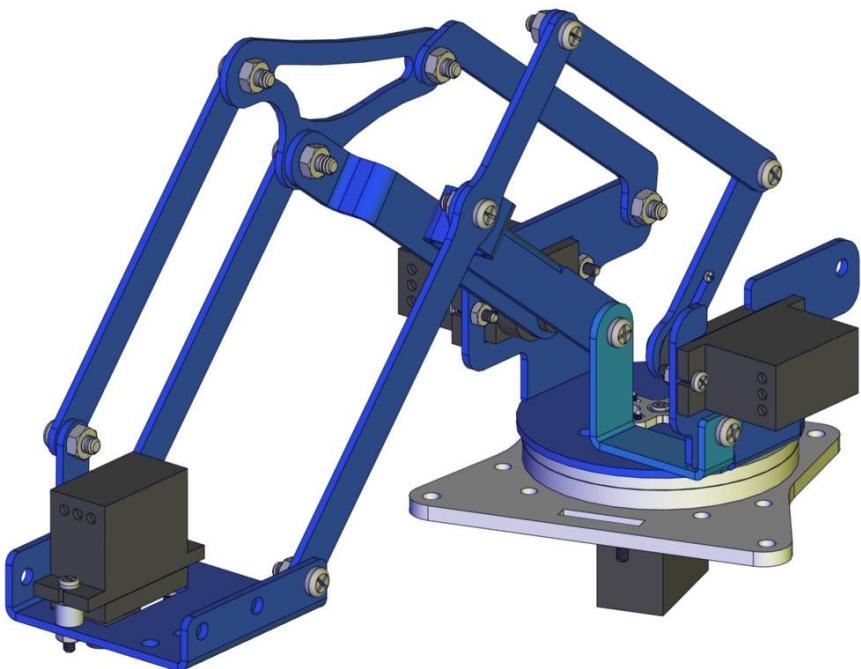
Don't screw nuts too tightly

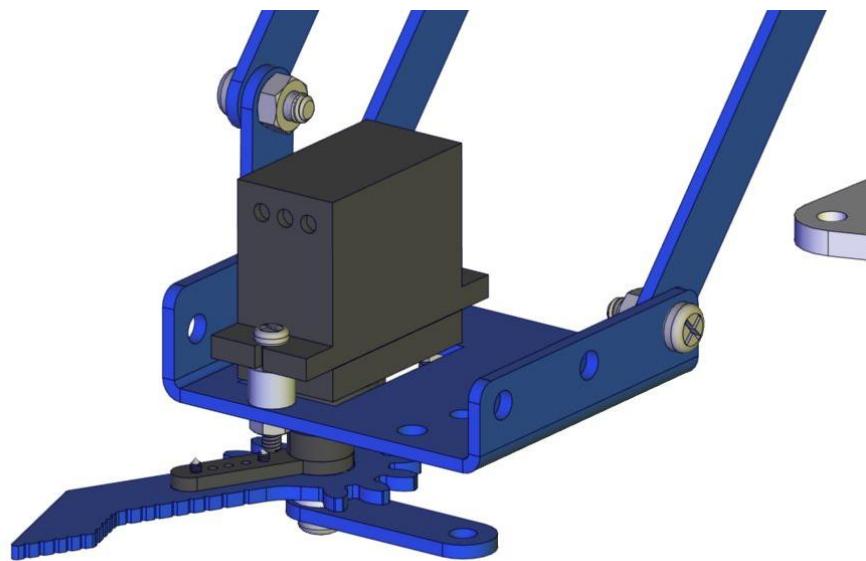
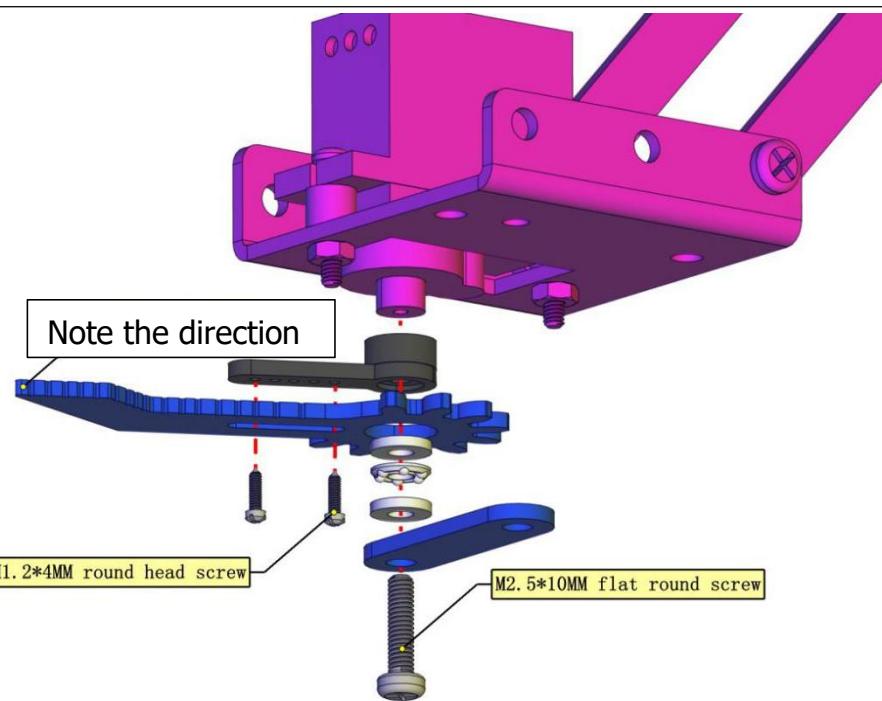


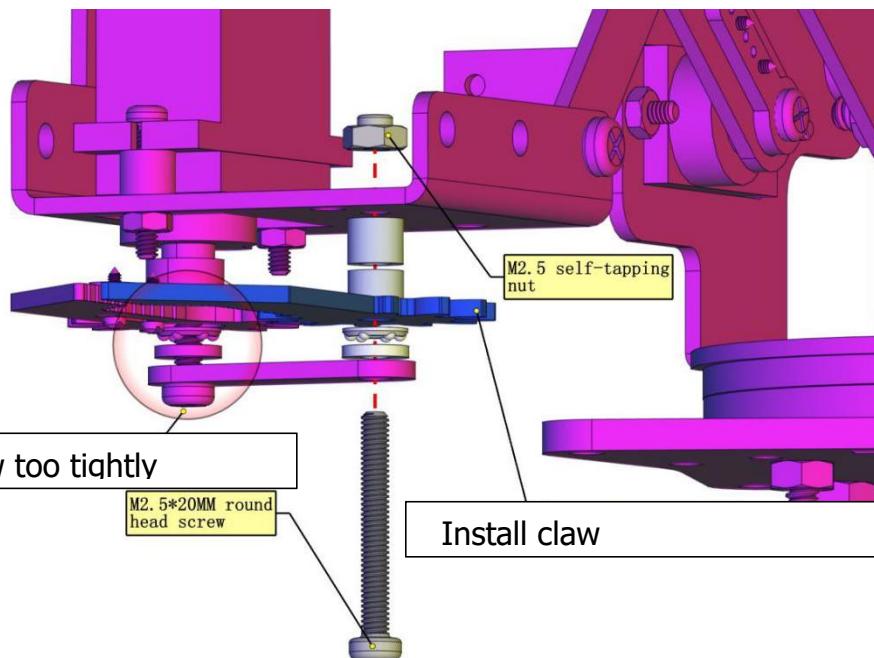
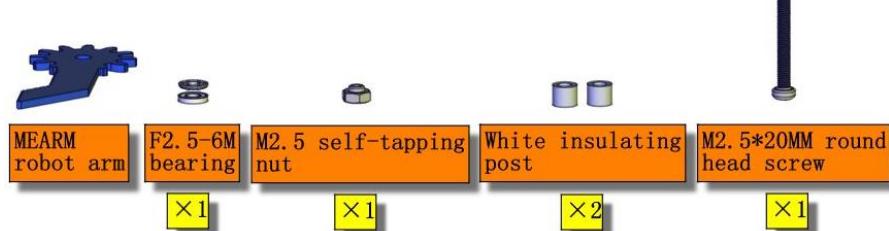
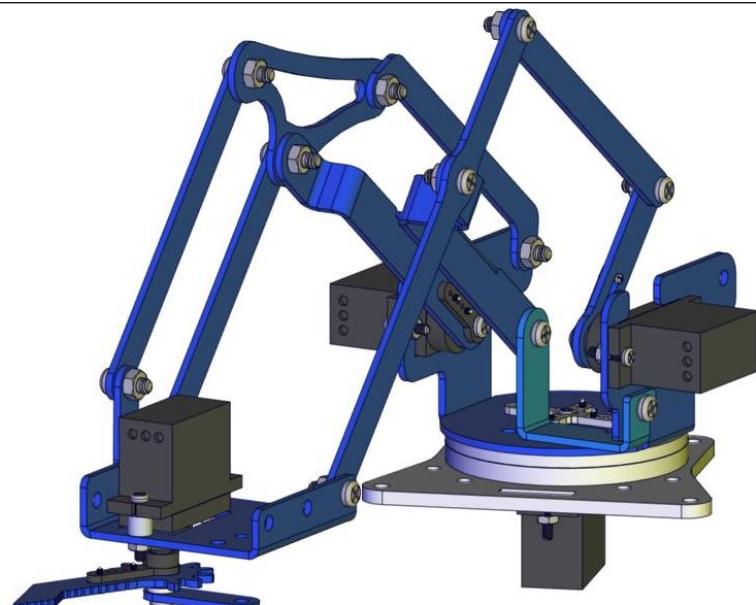


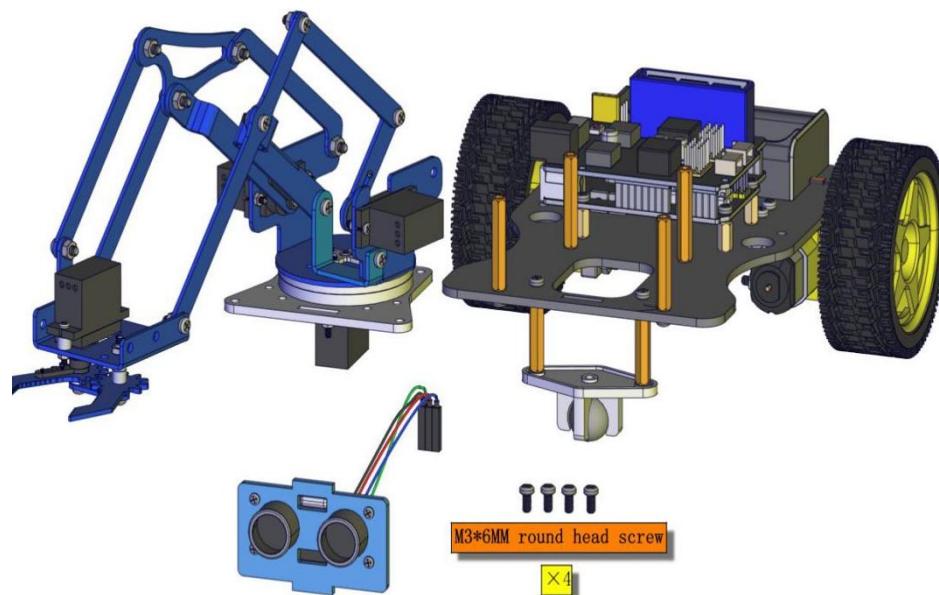
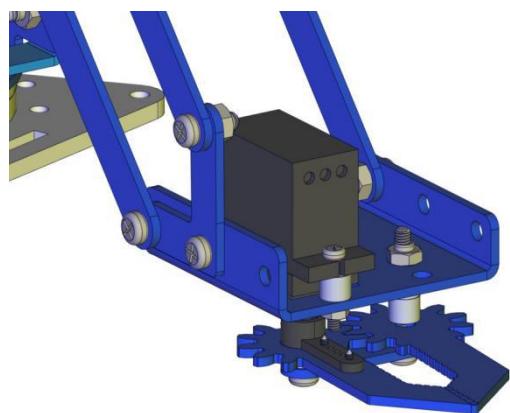
This is servo 4

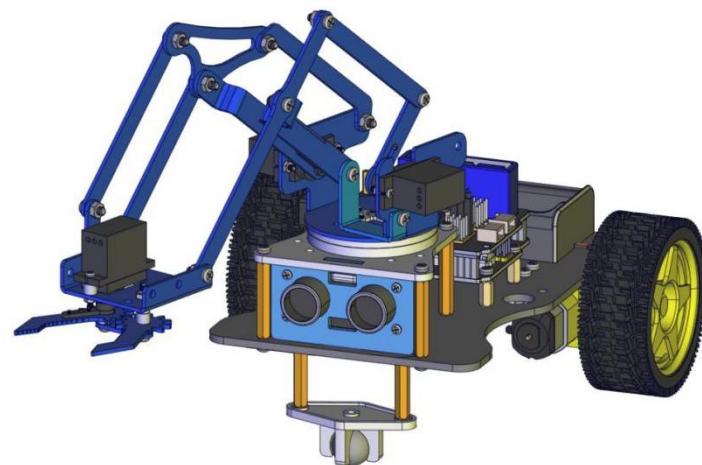
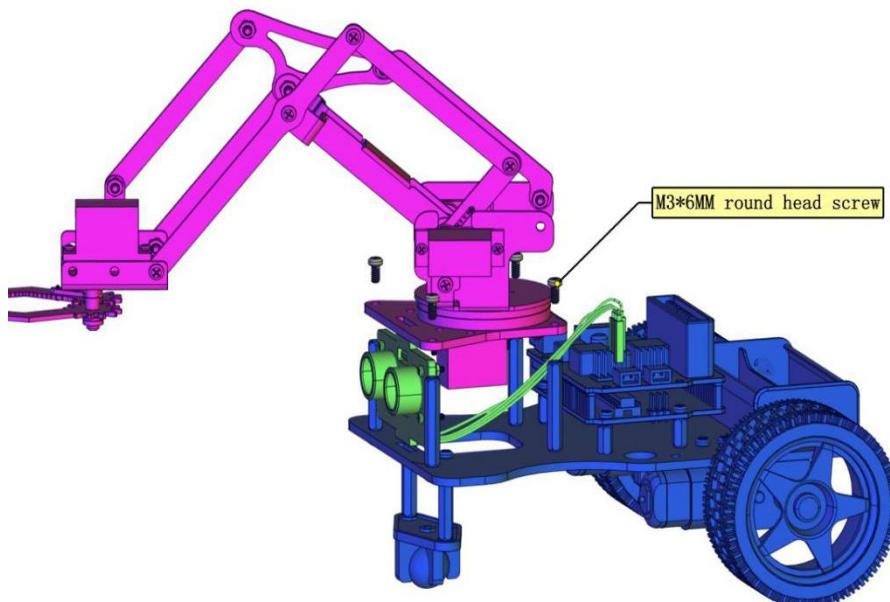




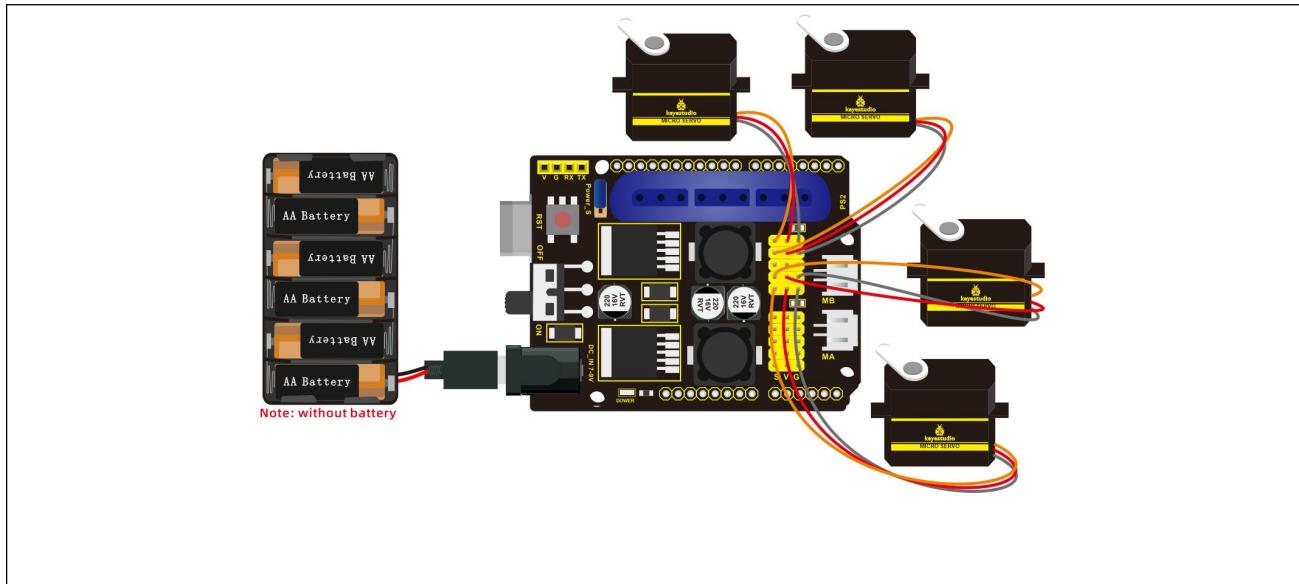








Wire up servos

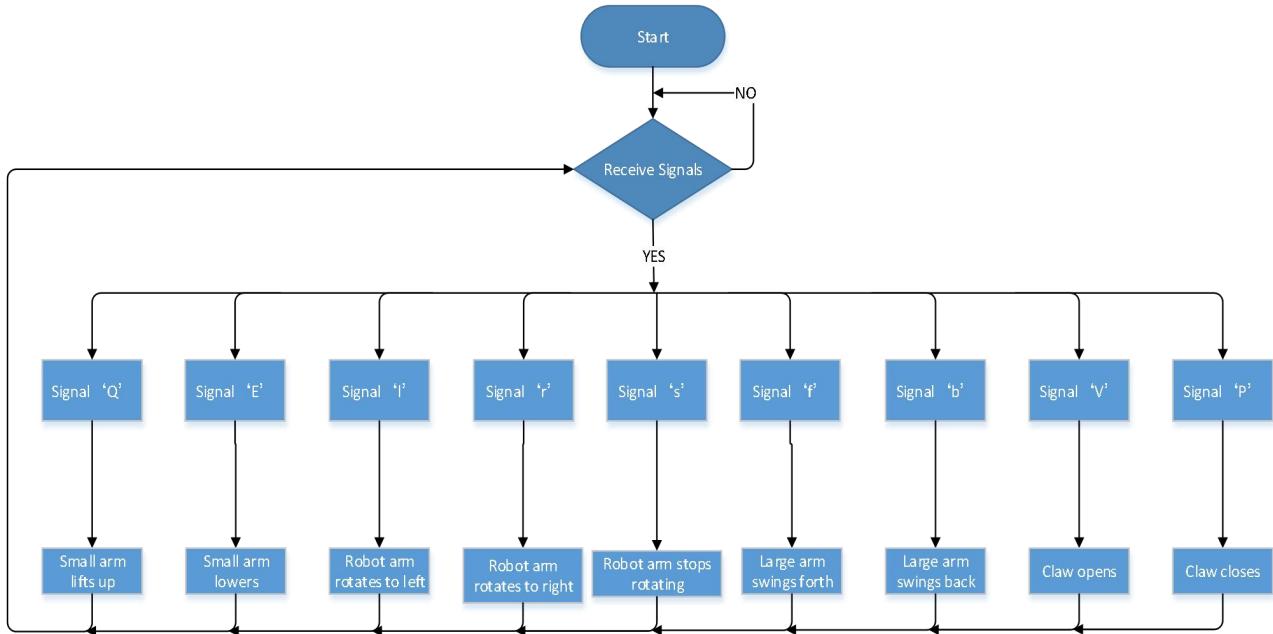


Project 15 App Control Robot

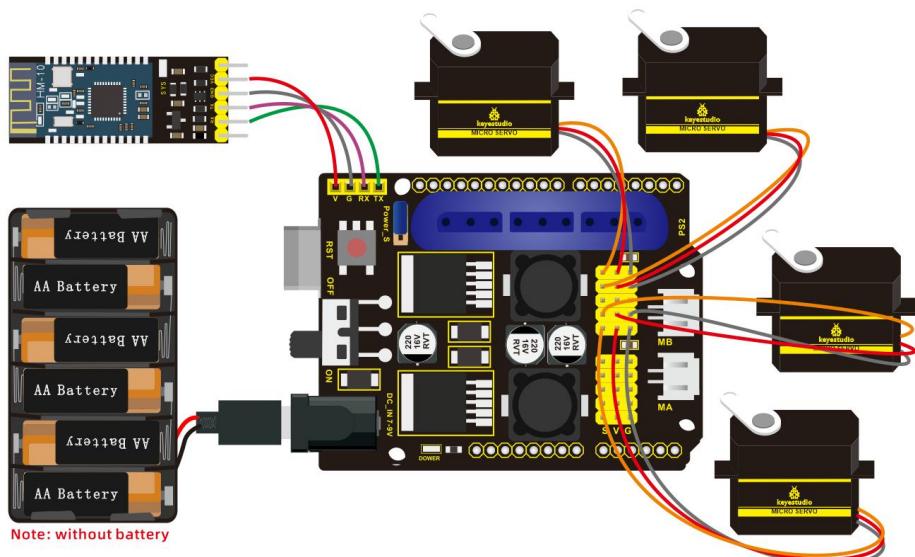
(1) Description:

We've learned basic knowledge of Bluetooth and how to control robot arm. In this chapter, we will operate arm through Bluetooth.

Flow Chart



(2) Connection Diagram:



(3) Test Code:

```
/*
```

keyestudio 4DOF Mechanical Robot Arm Car

lesson 15.1



Bluetooth control robotic arm

<http://www.keyestudio.com>

*/

```
#include <Servo.h> //add the library of servo  
Servo myservo1; //define the name of servo variable  
Servo myservo2; //define the name of servo variable  
Servo myservo3; //define the name of servo variable  
Servo myservo4; //define the name of servo variable  
int pos1=90,pos2=100,pos3=80,pos4=90; // define angle variable of four  
servos(angle value of posture when starting up)  
void T_left(){ //turn left  
    pos1+=1;  
    myservo1.write(pos1);  
    delay(10);  
    if(pos1>=180){ //set the limited angle value of servo  
        pos1=180;  
    }  
}  
void T_right(){ //turn right  
    pos1-=1;  
    myservo1.write(pos1);  
    delay(10);  
    if(pos1<=0){
```



```
pos1=0;  
}  
  
void ZB(){ //claw closes  
pos4-=1;  
myservo4.write(pos4);  
delay(5);  
if(pos4<=95){  
pos4=95;  
}  
  
void ZK(){ //claw opens  
pos4+=1;  
myservo4.write(pos4);  
delay(5);  
if(pos4>=180){  
pos4=180;  
}  
  
void LF(){ //smaller arm lifts up  
pos2+=1;  
myservo2.write(pos2);  
delay(10);  
if(pos2>=100){  
pos2=100;
```



```
}

void LB(){ //smaller arm lifts down
    pos2-=1;
    myservo2.write(pos2);
    delay(10);
    if(pos2<=0){
        pos2=0;
    }
}

void RF(){ // bigger arm swings forward
    pos3+=1;
    myservo3.write(pos3);
    delay(10);
    if(pos3>=180){
        pos3=180;
    }
}

void RB(){ // bigger arm swings back
    pos3-=1;
    myservo3.write(pos3);
    delay(10);
    if(pos3<=80){
        pos3=80;
    }
}
```



```
void setup(){
    Serial.begin(9600);
    myservo1.attach(A1); //set control pin of servo 1 to A1
    myservo2.attach(A0); //set control pin of servo 2 to A0
    myservo3.attach(8); //set control pin of servo 3 to D8
    myservo4.attach(9); //set control pin of servo 4 to D9
    myservo3.write(pos3); //servo 3 rotates to 80°
    delay(500);
    myservo2.write(pos2); //servo 2 rotates to 100°
    delay(500);
    myservo1.write(pos1); //posture to start up, servo 1 rotates to 90°
    delay(500);
    myservo4.write(pos4); //servo 4 rotates to 90°
}

void loop(){
    if(Serial.available()>0){ //determine if Bluetooth receives signals
        switch(Serial.read()){
            case 'Q':while('Q'){
                LF(); //smaller arm lifts up
                if(Serial.read()=='s')break;
            }break;
            case 'E':while('E'){

    
```



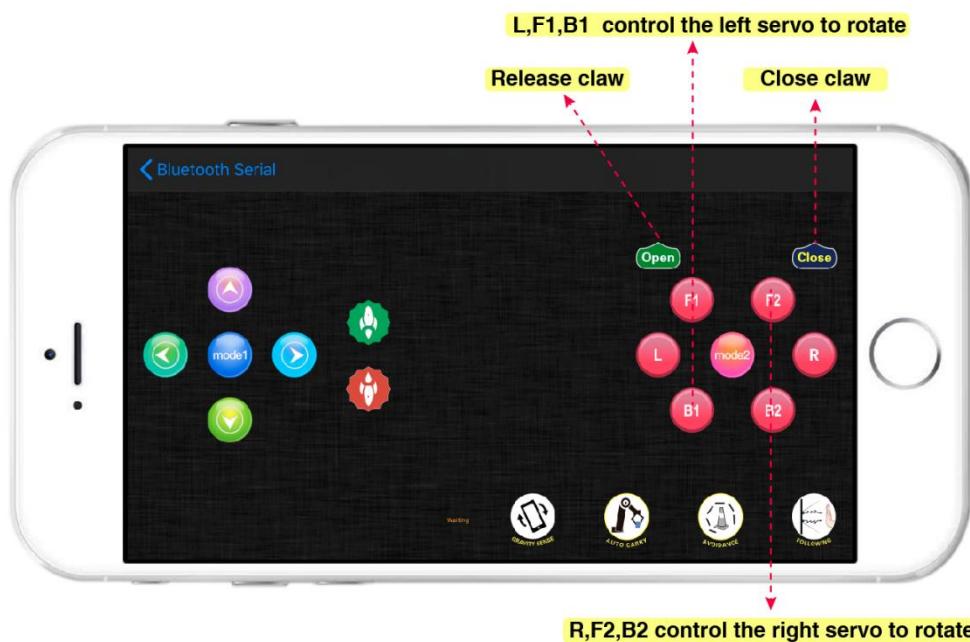
```
LB(); //smaller arm lifts down  
if(Serial.read()=='s')break;  
}  
case 'l':while('l'){  
T_left(); //mechanical arm turns left  
if(Serial.read()=='s')break;  
}  
case 'r':while('r'){  
T_right(); //mechanical arm turn right  
if(Serial.read()=='s')break;  
}  
case 'f':while('f'){  
RF(); //bigger arm swings forward  
if(Serial.read()=='s')break;  
}  
case 'b':while('b'){  
RB(); //bigger arm swings back  
if(Serial.read()=='s')break;  
}  
case 'V':while('V'){  
ZK(); //claw opens  
if(Serial.read()=='s')break;
```

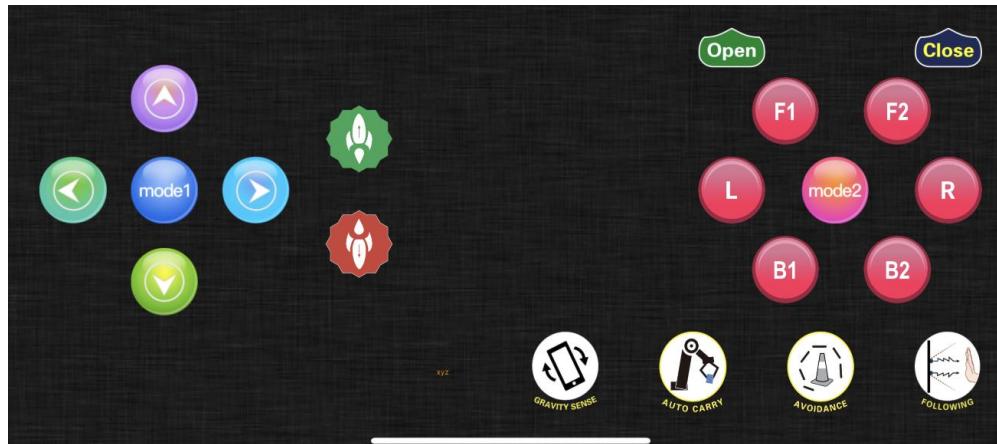


```
}break;  
  
case 'P':while('P'){  
  
    ZB(); //claw closes  
  
    if(Serial.read()=='s')break;  
  
}break;  
  
}  
  
delay(5);  
  
}
```

(4) Test Result:

Upload code and open App, and tick icons on App to control the postures of robot arm.



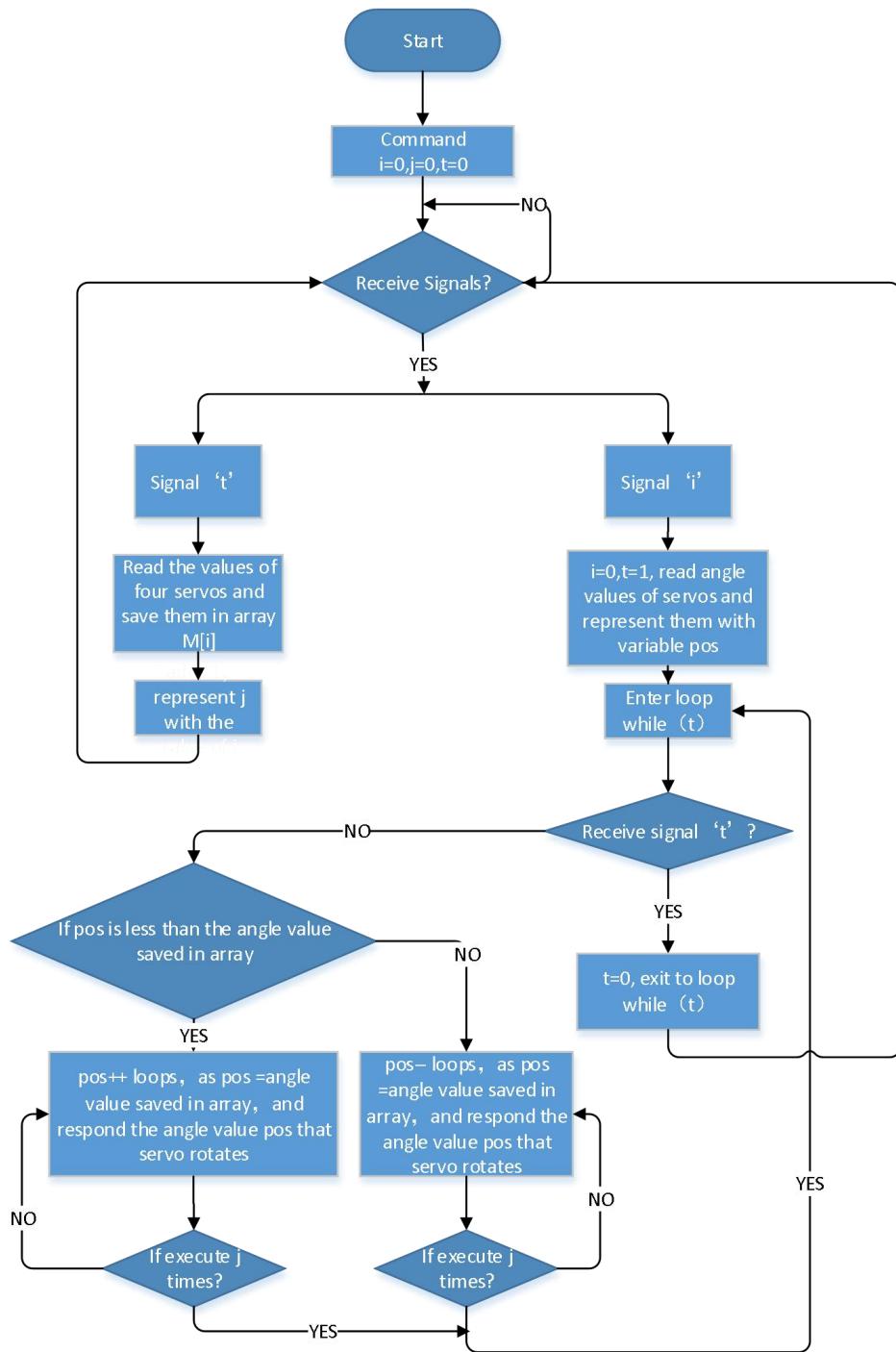


Project 16 Memory Carry Function

(1) Description:

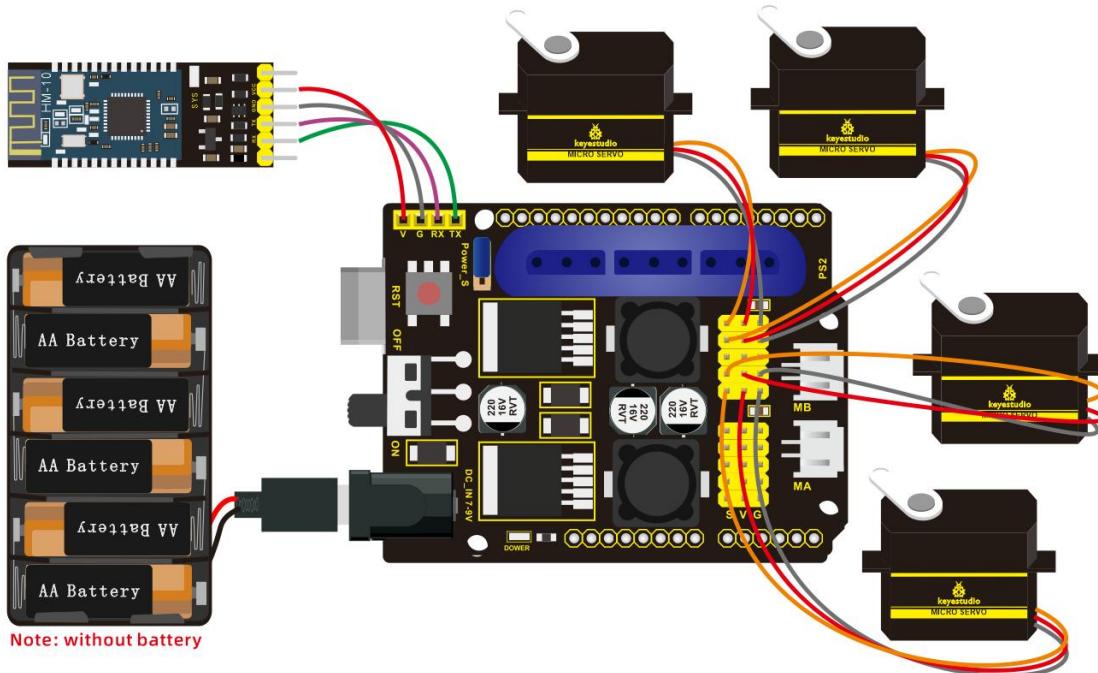
The memory function is a way to control robot arm, which records and programs the frequency, time and amplitude of motion. In this project, we will execute memory function via app.

Flow Chart





(2) Connection Diagram:



(3) Test Code:

```
/*
```

```
keyestudio 4DOF Mechanical Robot Arm Car
```

lesson 16

Bluetooth memory handling

<http://www.keyestudio.com>

```
*/
```

```
#include <Servo.h> //add the library of servo
```

```
Servo myservo1; //define the name of servo variable
```

```
Servo myservo2; //define the name of servo variable
```



```
Servo myservo3; //define the name of servo variable  
Servo myservo4; //define the name of servo variable  
int pos1=90,pos2=100,pos3=80,pos4=90; //define angle variable of four  
servos(angle value of posture when starting up)  
int s1,s2,s3,s4; //read angle value and save in the M[] array  
int M1[20]; //define four arrays  
int M2[20]; //save angle of four servos  
int M3[20]; //the length of array is 20, save 0~20 angle data  
int M4[20];  
int i=0,j=0,t=0; //i is used to save array, j is used to save the maximum  
value of i,t is used to exit while loop  
void T_left(){ //turn left  
    pos1+=1;  
    myservo1.write(pos1);  
    delay(5);  
    if(pos1>=180){ //set the limited angle value of servo  
        pos1=180;  
    }  
}  
  
void T_right(){ //turn right  
    pos1-=1;
```



```
myservo1.write(pos1);
delay(5);
if(pos1<=0){
    pos1=0;
}
}
```

```
void ZB(){ //claw closes
pos4-=2;
myservo4.write(pos4);
delay(5);
if(pos4<=95){
    pos4=95;
}
}
```

```
void ZK(){ //claw opens
pos4+=2;
myservo4.write(pos4);
delay(5);
if(pos4>=180){
    pos4=180;
}
```



}

}

```
void LF(){ //smaller arm lifts up
```

```
    pos2+=1;
```

```
    myservo2.write(pos2);
```

```
    delay(5);
```

```
    if(pos2>=100){
```

```
        pos2=100;
```

```
    }
```

}

```
void LB(){ //smaller arm lifts down
```

```
    pos2-=1;
```

```
    myservo2.write(pos2);
```

```
    delay(5);
```

```
    if(pos2<=1){
```

```
        pos2=0;
```

```
    }
```

}

```
void RF(){ // bigger arm swings forward
```



```
pos3+=1;  
myservo3.write(pos3);  
delay(5);  
if(pos3>=180){  
    pos3=180;  
}  
}  
  
void RB(){ // bigger arm swings back  
    pos3-=1;  
    myservo3.write(pos3);  
    delay(5);  
    if(pos3<=80){  
        pos3=80;  
    }  
}  
  
void setup(){  
    Serial.begin(9600);  
    myservo1.attach(A1); //set control pin of servo 1 to A1  
    myservo2.attach(A0); //set control pin of servo 2 to A0  
    myservo3.attach(8); //set control pin of servo 3 to D8
```



```
myservo4.attach(9); //set control pin of servo 4 to D9
myservo3.write(pos3); //servo 3 rotates to 80°
delay(500);
myservo2.write(pos2); //servo 2 rotates to 100°
delay(500);
myservo1.write(pos1); //posture to start up, servo1 rotates to 90°
delay(500);
myservo4.write(pos4); //servo 4 rotates to 90°

}

void loop(){
    if(Serial.available()>0){ //determine if Bluetooth receives signals
        switch(Serial.read()){
            case 'Q':while('Q'){
                LF(); //smaller arm lifts up
                if(Serial.read()=='s')break;
            }break;
            case 'E':while('E'){
                LB(); //smaller arm lifts down
                if(Serial.read()=='s')break;
            }break;
        }
    }
}
```



```
case 'l':while('l'){
    T_left(); //arm turns left
    if(Serial.read()=='s')break;
}break;

case 'r':while('r'){
    T_right(); //arm turns right
    if(Serial.read()=='s')break;
}break;

case 'f':while('f'){
    RF(); //bigger arm swings forward
    if(Serial.read()=='s')break;
}break;

case 'b':while('b'){
    RB(); //arm swings back
    if(Serial.read()=='s')break;
}break;

case 'V':while('V'){
    ZK(); //claw opens
    if(Serial.read()=='s')break;
}break;

case 'P':while('P'){
    ZB(); //claw closes
```



```
if(Serial.read()=='s')break;  
}  
case 't': { //receive 't' , remember  
    M1[i]=myservo1.read(); //save the current angle of each servo to  
array  
    delay(100); //delay time to save angle value  
    M2[i]=myservo2.read();  
    delay(100);  
    M3[i]=myservo3.read();  
    delay(100);  
    M4[i]=myservo4.read();  
    delay(100);  
    i++; //i increases 1 when save each time  
    j=i; //set the value of i to j  
    Serial.print("j:");  
    Serial.println(j);  
    if(i>20)i=19; //set the previous array to 20  
    delay(200);  
}  
case 'i': { //receive 'i' , execute  
    i=0; //i clears  
    t=1; //used for while loop
```



```
pos1=myservo1.read(); //set the current angle value to pos  
pos2=myservo2.read();  
pos3=myservo3.read();  
pos4=myservo4.read();  
  
while(t){  
    for(int k=0;k<j;k++){      //repeat j times, execute all saved  
motions  
  
        if(pos1<M1[k]){ //when the angle value of servo 1 is less than  
the value saved in array 1  
  
            while(pos1<M1[k]){ //while loop, make servo rotate where  
value is saved in array  
  
                myservo1.write(pos1); //servo 1 executes posture  
                pos1++; //pos1 increases 1  
                delay(8); //delay in 8ms to control rotation speed of servo  
            }  
        }  
  
        else{ //when the angle of servo 1 is more than the value  
saved in array 1  
  
            while(pos1>M1[k]){ //while loop, make servo rotate where  
value is saved in array  
  
                myservo1.write(pos1); //servo 1 executes posture  
                pos1--; //pos1 reduces 1
```



```
delay(8); //delay in 8ms to control rotation speed of servo
}

}

//the same below

if(pos2<M2[k]){

    while(pos2<M2[k]){

        myservo2.write(pos2);

        pos2++;

        delay(8);

    }

}

else{

    while(pos2>M2[k]){

        myservo2.write(pos2);

        pos2--;

        delay(8);

    }

}

if(pos3<M3[k]){

    while(pos3<M3[k]){

        myservo3.write(pos3);

    }

}
```



```
    pos3++;
    delay(8);
}

}

else{
    while(pos3>M3[k]){
        myservo3.write(pos3);
        pos3--;
        delay(8);
    }
}

if(pos4<M4[k]){
    while(pos4<M4[k]){
        myservo4.write(pos4);
        pos4++;
        delay(8);
    }
}

else{
    while(pos4>M4[k]){
        myservo4.write(pos4);
    }
}
```



```
pos4--;
delay(8);

}

}

if(Serial.available()>0){ //in order to exit loop

    if(Serial.read()=='t'){ //receive 'i' and 't'

        t=0; //set t to 0, exit while loop

        break; //exit

    }

}

if(Serial.read()=='s')break;

}break;

}

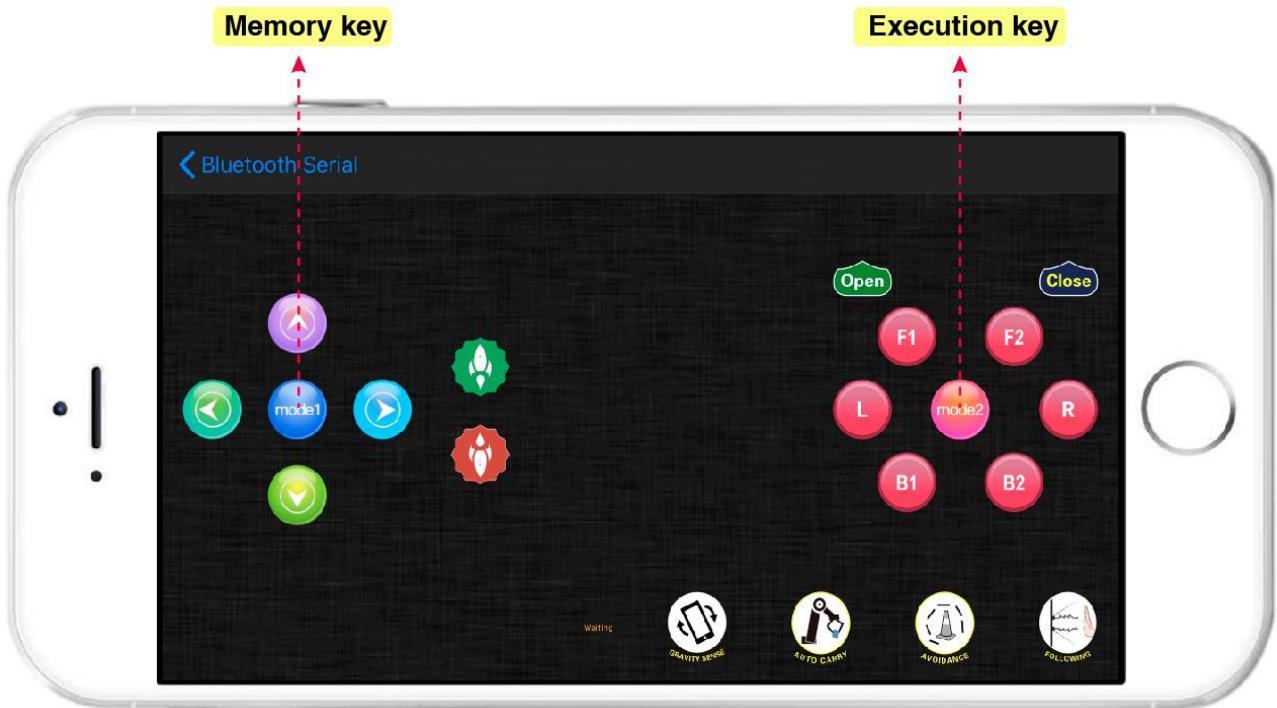
delay(5);

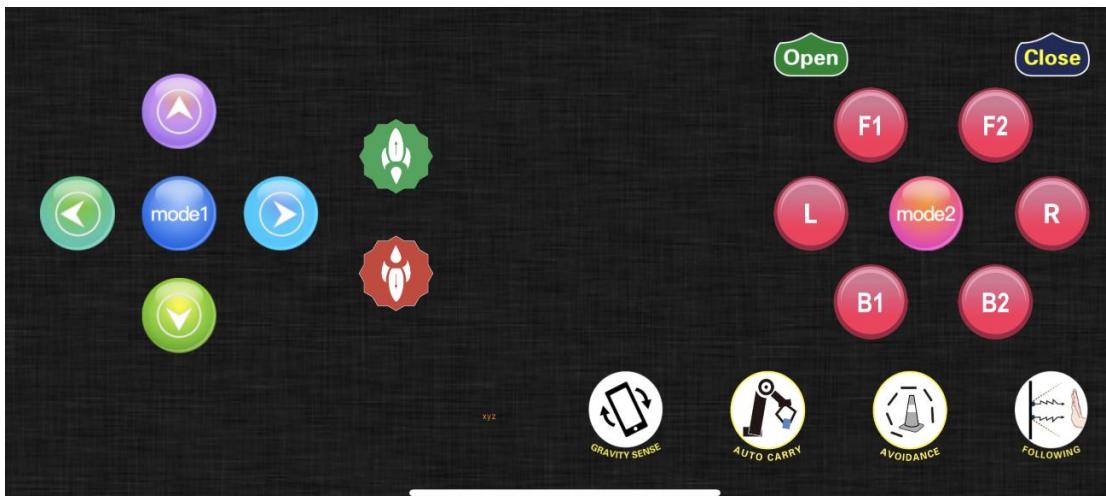
}
```



(4) Test Result:

Upload code and connect App. As the robot arm demonstrates some postures, we press memory key to save them. For more actions to be saved, we just need to press execution key so that robot arm can memorize and show them ceaselessly. And it won't stop presenting actions until we press memory key.



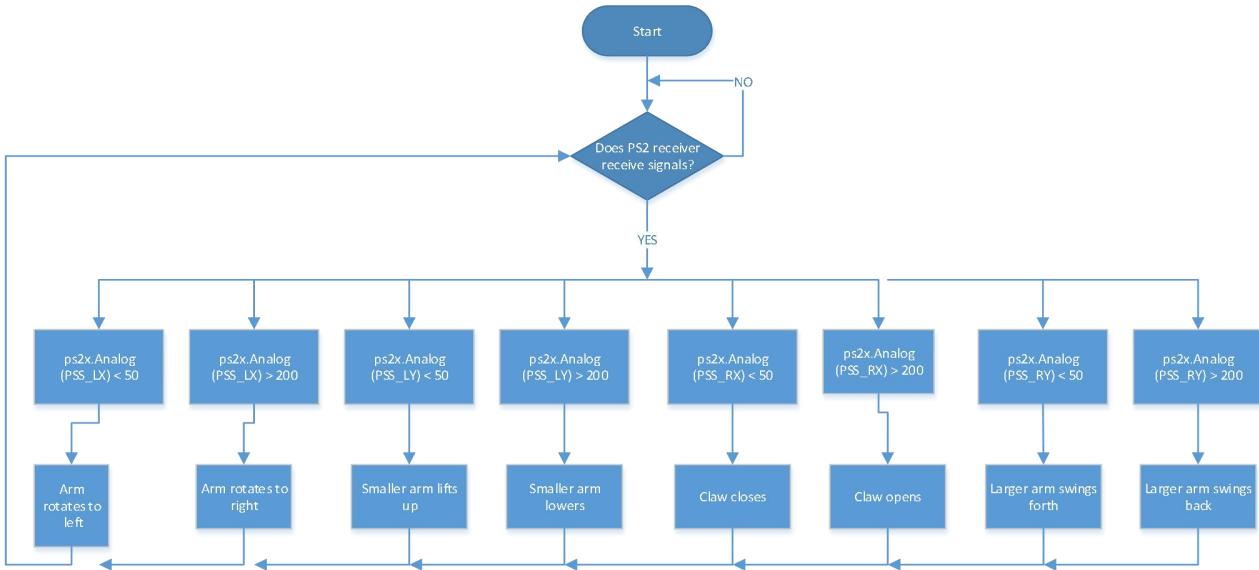


Project 17 PS2 Joypad Control

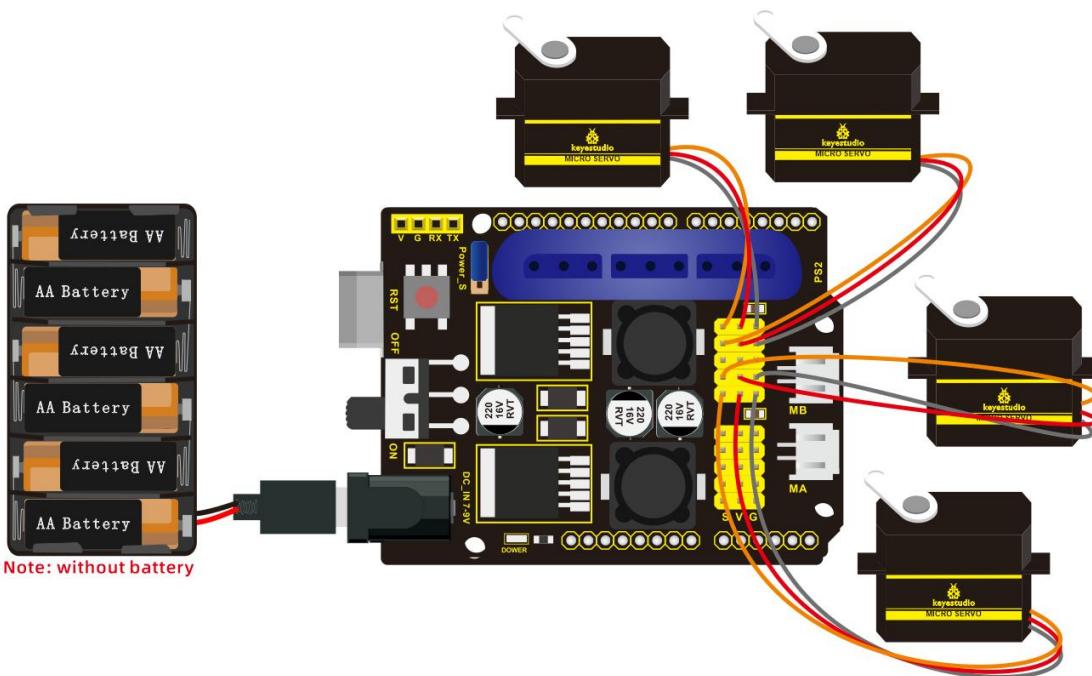
(1) Description:

In the previous section, we have showed how to use PS2 Joypad to control the robot arm. It is almost the same for you to control the 4DOF robot arm using the PS2 Joypad.

Flow Chart



(2) Connection Diagram:



(3) Test Code:

```
/*
```

```
keyestudio 4DOF Mechanical Robot Arm Car
```



lesson 16.1

PS2 control robotic arm

<http://www.keyestudio.com>

*/

```
#include <PS2X_lib.h> //add library of ps2 handle
```

```
#include <Servo.h> //add the library of servo
```

```
PS2X ps2x; // create PS2 Controller Class
```

```
#define PS2_DAT 12 //ps2 receiver
```

```
#define PS2_CMD 11
```

```
#define PS2_SEL 10
```

```
#define PS2_CLK 13
```

```
Servo myservo1; //define the name of servo variable
```

```
Servo myservo2; //define the name of servo variable
```

```
Servo myservo3; //define the name of servo variable
```

```
Servo myservo4; //define the name of servo variable
```

```
int error=0;
```

```
byte vibrate=0;
```

```
int pos1=90,pos2=100,pos3=60,pos4=90; // define angle variable of four  
servos and set initial value(posture angle value when setting up)
```

```
void setup(){
```

```
  Serial.begin(9600); //set to baud rate to 57600 when printing ps2,
```



however, Bluetooth can't be used

```
myservo1.attach(A1); //set control pin of servo 1 to A1
myservo2.attach(A0); //set control pin of servo 2 to A0
myservo3.attach(8); //set control pin of servo 3 to D8
myservo4.attach(9); //set control pin of servo 4 to D9
myservo3.write(pos3); //servo 3 rotates to 80°
delay(500);
myservo2.write(pos2); //servo 2 rotates to 100°
delay(500);
myservo1.write(pos1); //posture to start up, servo rotates to 90°
delay(500);
myservo4.write(pos4); //servo 4 rotates to 90°
error=ps2x.config_gamepad(PS2_CLK,PS2_CMD,PS2_SEL,PS2_DAT);
//setup pins check for error
if(error==0){
    Serial.println("Found Controller, configured successful");
    Serial.println("Try out all the buttons, X will vibrate the controller,
faster as you press harder;");
    Serial.println("holding L1 or R1 will print out the analog stick values.");
    Serial.println("Go to www.billporter.info for updates and to report
bugs.");
}
```

```
else if(error==1) Serial.println("No controller found, check wiring, see  
readme.txt to enable debug. visit www.billporter.info for troubleshooting  
tips");
```

```
else if(error==2) Serial.println("Controller found but not accepting  
commands. see readme.txt to enable debug. Visit www.billporter.info for  
troubleshooting tips");
```

```
ps2x.enableRumble(); //enable rumble vibration motors  
ps2x.enablePressures(); //enable reading the pressure values from the  
buttons.
```

```
}
```

```
void loop(){  
    if(error!=0) return;  
    ps2x.read_gamepad(false, vibrate);  
    down_ser(); //call function of servo of base  
    left_ser(); //call left servo function  
    right_ser(); //call right servo function  
    zhuazi(); //call claw function
```

```
    delay(5);  
}
```



```
void down_ser(){ //servo on base
    if(ps2x.Analog (PSS_LX) < 50) //put left joystick leftward
    {
        pos1=pos1+1;
        myservo1.write(pos1); //arm swings to left
        //delay(2); //add delayed time to control rotation speed
        if(pos1>180) //limit the angle of left swinging
        {
            pos1=180;
        }
    }

    if(ps2x.Analog (PSS_LX) > 200) //put left joystick rightward
    {
        pos1=pos1-1;
        myservo1.write(pos1); //arm swings to right
        //delay(2);
        if(pos1<1) //limit the angle of right swinging
        {
            pos1=0;
        }
    }
}
```



{

```
void left_ser(){ //left servo
    if(ps2x.Analog(PSS_LY)<50) //put left joystick forward
    {
        pos2=pos2+1;
        myservo2.write(pos2); //arm swings forward
        //delay(2);
        if(pos2>100) //limit the angle of forward swinging
        {
            pos2=100;
        }
    }
    if(ps2x.Analog(PSS_LY)>200) //put left joystick backward
    {
        pos2=pos2-1;
        myservo2.write(pos2); //arm swings back
        //delay(2);
        if(pos2<1) //limit the angle of back swinging
        {
            pos2=0;
        }
    }
}
```



```
    }  
}  
  
void right_ser(){ //right servo  
    if(ps2x.Analog(PSS_RY)<50) //put right joystick forward  
    {  
        pos3=pos3+1;  
        myservo3.write(pos3); //bigger arm swings forward  
        //delay(2);  
        if(pos3>180) //limit the angle of forward swinging  
        {  
            pos3=180;  
        }  
    }  
    if(ps2x.Analog(PSS_RY)>200) //put right joystick backward  
    {  
        pos3=pos3-1;  
        myservo3.write(pos3); //bigger arm swings back  
        //delay(2);  
        if(pos3<80) //limit the angle of back swinging  
        {  
            pos3=80;
```



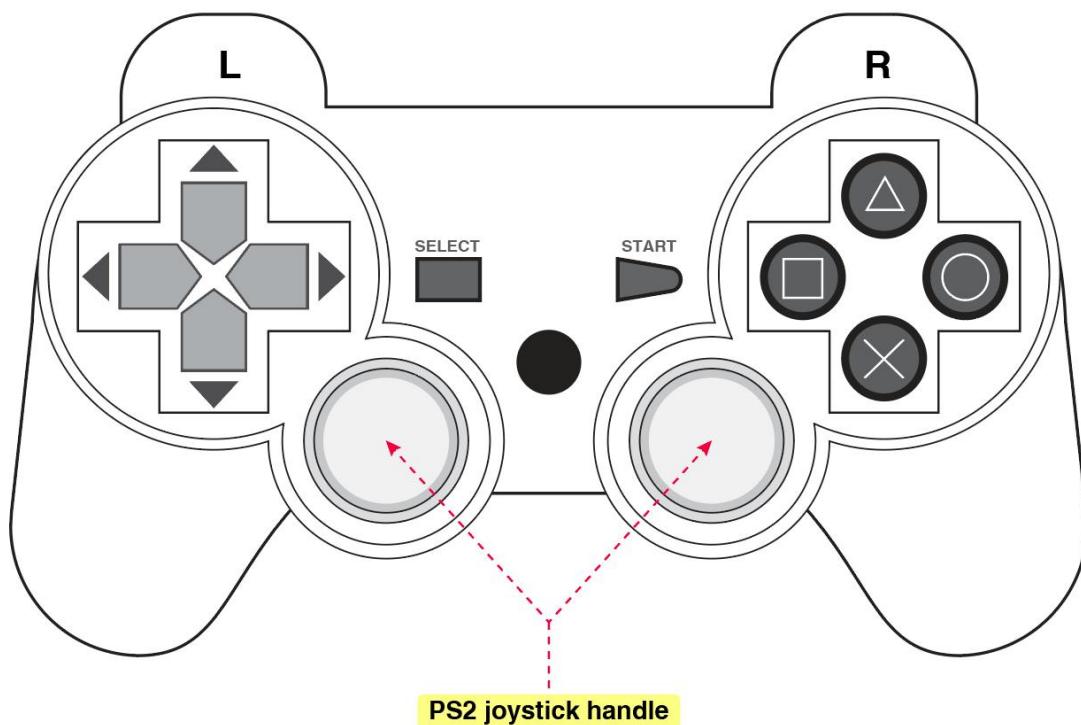
```
    }  
}  
  
}  
  
void zhuazi(){ //servo of claw  
    if(ps2x.Analog(PSS_RX)>200) //put right joystick rightward  
    {  
        myservo4.write(pos4); //servo 4 moves, claw gradually opens  
        pos4+=3;  
        delay(2);  
        if(pos4>180) //limit angle  
        {  
            pos4=180;  
        }  
    }  
  
    if(ps2x.Analog(PSS_RX)<50) ///put right joystick leftward  
    {  
        myservo4.write(pos4); //servo 4 executes pose, claw gradually closes  
        pos4-=3;  
        delay(2);  
        if(pos4<95) //limit to open the maximum angle  
        {
```



```
    pos4=95;  
}  
}  
}
```

(4) Test Result:

Upload code and connect PS2 joypad so that you could control robot arm with it.





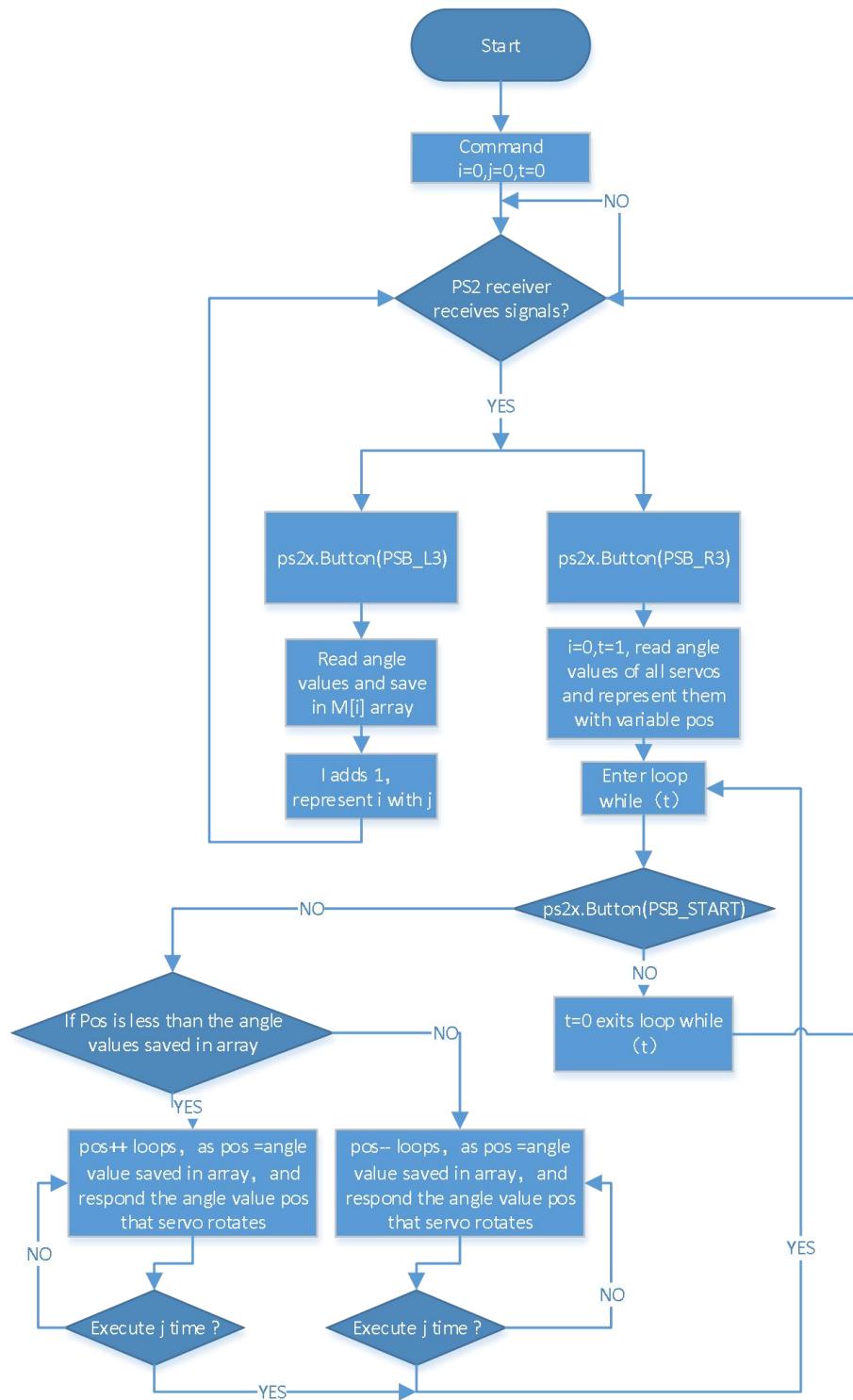
Project 18 Memory Function

(1) Description:

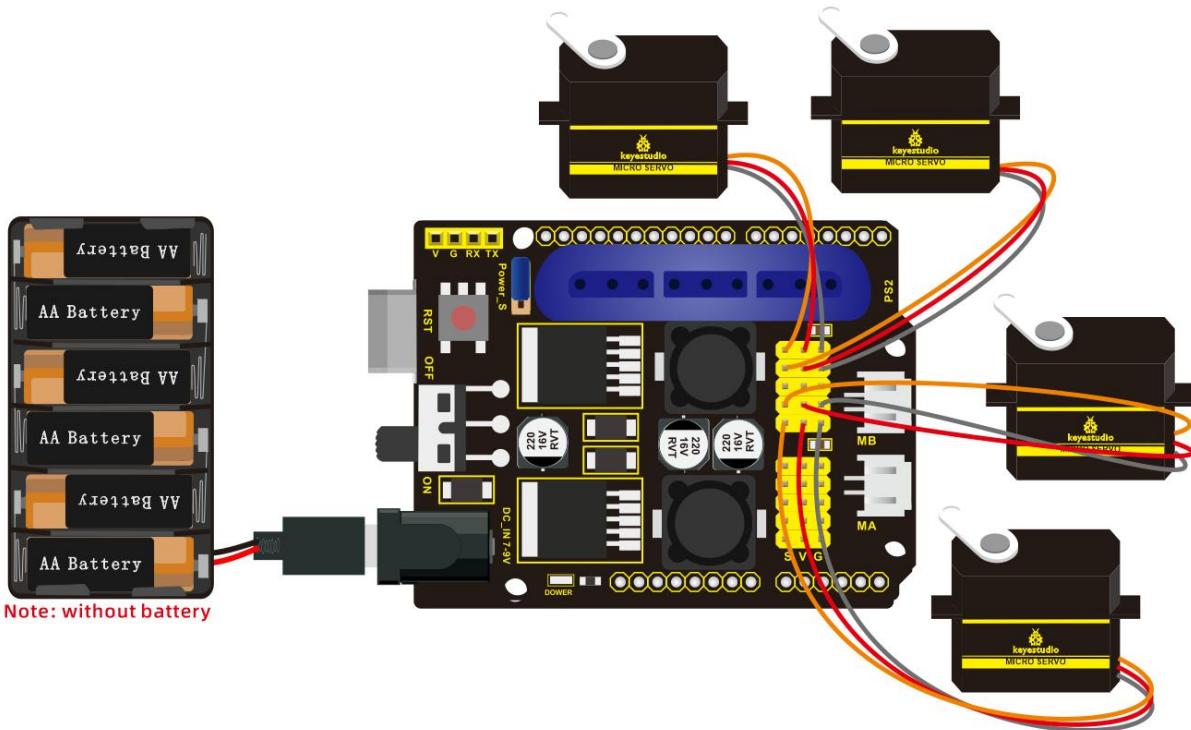
The memory function could be cooperated through memory key on APP.

In this part, we will perform the memory function with the key on PS2 joypad.

Flow Chart



(2) Connection Diagram:



(3) Test Code:

```
/*
```

keyestudio 4DOF Mechanical Robot Arm Car

lesson 18.1

PS2 memory handling

<http://www.keyestudio.com>

```
*/
```

```
#include <PS2X_lib.h> //add a library of ps2 handle
```

```
#include <Servo.h> //add the library of servo
```

```
PS2X ps2x; // create PS2 Controller Class
```

```
#define PS2_DAT 12 //ps2 receiver
```

```
#define PS2_CMD 11
```



```
#define PS2_SEL      10
#define PS2_CLK       13

Servo myservo1; //define the name of servo variable
Servo myservo2; //define the name of servo variable
Servo myservo3; //define the name of servo variable
Servo myservo4; //define the name of servo variable
int error = 0;
byte vibrate = 0;

int pos1 = 90, pos2 = 100, pos3 = 80, pos4 = 90; // define angle variable of
four servos and set initial value(posture angle value when setting up)
int s1, s2, s3, s4; //used to read angle value and save in M[] array

int M1[20];          //define four arrays
int M2[20];          //respectively use to save angle of 4 servos
int M3[20];          //array length is 20, can save 0~20 angle data
int M4[20];

int i = 0, j = 0, t = 0; //i is used to save array, j is used to save the maximum
value of i,t is used to exit while loop

void setup() {
    Serial.begin(9600);      //set to baud rate to 57600 when printing ps2,
however, Bluetooth can't be used
    myservo1.attach(A1);   //set control pin of servo 1 to A1
```

```
myservo2.attach(A0); //set control pin of servo 2 to A0
myservo3.attach(8); //set control pin of servo 3 to D8
myservo4.attach(9); //set control pin of servo 4 to D9
myservo3.write(pos3); //servo 3 rotates to 80°
delay(500);
myservo2.write(pos2); //servo 2 rotates to 100°
delay(500);
myservo1.write(pos1); //posture to start up, servo 1 rotates to 90°
delay(500);
myservo4.write(pos4); //servo 4 rotates to 90°
error = ps2x.config_gamepad(PS2_CLK, PS2_CMD, PS2_SEL, PS2_DAT);
//setup pins check for error
if (error == 0) {
    Serial.println("Found Controller, configured successful");
    Serial.println("Try out all the buttons, X will vibrate the controller,
faster as you press harder;");
    Serial.println("holding L1 or R1 will print out the analog stick values.");
    Serial.println("Go to www.billporter.info for updates and to report
bugs.");
}
else if (error == 1) Serial.println("No controller found, check wiring, see
readme.txt to enable debug. visit www.billporter.info for troubleshooting")
```

```
tips");  
else if (error == 2) Serial.println("Controller found but not accepting  
commands. see readme.txt to enable debug. Visit www.billporter.info for  
troubleshooting tips");
```

```
ps2x.enableRumble(); //enable rumble vibration motors  
ps2x.enablePressures(); //enable reading the pressure values from the  
buttons.  
}
```

```
void loop() {  
if (error != 0) return;  
memory(); //call memory function  
down_ser(); //call function of servo of base  
left_ser(); //call left servo function  
right_ser(); //call right servo function  
zhuazi(); //call claw function  
delay(10);  
}
```

```
void down_ser() { //servo on base  
if (ps2x.Analog (PSS_LX) < 50) //put left joystick leftward
```



```
{  
    pos1 = pos1 + 1;  
  
    myservo1.write(pos1); //arm swings to left  
  
//    delay(2); //delay time to control rotation speed of servo  
  
    if (pos1 > 180) //limit the angle of left swinging  
  
    {  
        pos1 = 180;  
  
    }  
  
}  
  
if (ps2x.Analog (PSS_LX) > 200) //put left joystick rightward  
  
{  
    pos1 = pos1 - 1;  
  
    myservo1.write(pos1); //arm swings to right  
  
//    delay(2); //delay time to control rotation speed of servo  
  
    if (pos1 < 0) //limit the angle of right swinging  
  
    {  
        pos1 = 0;  
  
    }  
  
}  
  
}  
  
void left_ser() { //left servo
```



```
if (ps2x.Analog(PSS_LY) < 50) //put left joystick forward
{
    pos2 = pos2 + 1;
    myservo2.write(pos2); //arm swings forward
//    delay(2);

    if (pos2 > 100) //limit the angle of forward swinging
    {
        pos2 = 100;
    }
}

if (ps2x.Analog(PSS_LY) > 200) //put left joystick backward
{
    pos2 = pos2 - 1;
    myservo2.write(pos2); //arm swings back
//    delay(2);

    if (pos2 < 1) //limit the angle of back swinging
    {
        pos2 = 0;
    }
}
```



```
void right_ser() { //right servo
    if (ps2x.Analog(PSS_RY) < 50) //put right joystick forward
    {
        pos3 = pos3 + 1;
        myservo3.write(pos3); //bigger arm swings forward
        // delay(2);
        if (pos3 > 180) //limit the angle of forward swinging
        {
            pos3 = 180;
        }
    }

    if (ps2x.Analog(PSS_RY) > 200) //put right joystick backward
    {
        pos3 = pos3 - 1;
        myservo3.write(pos3); //大arm swings back
        // delay(2);
        if (pos3 < 80) //limit the angle of back swinging
        {
            pos3 = 80;
        }
    }
}
```



```
void zhuazi() { //servo of claw
    if (ps2x.Analog(PSS_RX) > 200) //put right joystick rightward
    {
        myservo4.write(pos4); //servo 4 moves, claw gradually opens
        pos4 += 3;
        delay(2);
        if (pos4 > 180) //limit angles
        {
            pos4 = 180;
        }
    }
    if (ps2x.Analog(PSS_RX) < 50) ////put right joystick leftward
    {
        myservo4.write(pos4); //servo 4 executes pose, claw gradually closes
        pos4 -= 3;
        delay(2);
        if (pos4 < 95) //limit to open the maximum angle
        {
            pos4 = 95;
        }
    }
}
```



{

```
void memory() { //ps2memory function
    ps2x.read_gamepad(false, vibrate); //read controller
    if (ps2x.NewButtonState()) {
        delay(20);
        ps2x.read_gamepad(false, vibrate);
    }
    if (ps2x.Button(PSB_L3)) { //if press L3 is true
        Serial.println("L3 pressed");
        s1 = myservo1.read(); //read the angle value of each servo
        delay(100);
        Serial.println(s1); //print the current angle value of servo 1 in serial
        monitor
        s2 = myservo2.read();
        delay(100);
        Serial.println(s2);
        s3 = myservo3.read();
        delay(100);
        Serial.println(s3);
        s4 = myservo4.read();
        delay(100);
        Serial.println(s4);
```





```
if (pos1 < M1[k]) {      //when the angle value of servo 1 is more
than the value saved in array 1

    while (pos1 < M1[k]) {      //while loop, make servo rotate to
value where the array is saved

        myservo1.write(pos1);      //servo 1 executes posture
        pos1++;                      //pos1 increases 1
        delay(10);                  //delay 10ms to control
rotation speed of servo

    }

}

else {                      //when the angle of servo 1 is
more than the value saved in array 1

    while (pos1 > M1[k]) {      //while loop, make servo rotate to
value where the array is saved

        myservo1.write(pos1);      //servo 1 executes posture
        pos1--;                      //pose reduces 1
        delay(10);                  //delay 10ms to control rotation speed of
servo

    }

}
```



```
if (pos2 < M2[k]) {  
    while (pos2 < M2[k]) {  
        myservo2.write(pos2);  
        pos2++;  
        delay(10);  
    }  
}  
  
else {  
    while (pos2 > M2[k]) {  
        myservo2.write(pos2);  
        pos2--;  
        delay(10);  
    }  
}  
  
  
if (pos3 < M3[k]) {  
    while (pos3 < M3[k]) {  
        myservo3.write(pos3);  
        pos3++;  
        delay(10);  
    }  
}
```



```
else {  
    while (pos3 > M3[k]) {  
        myservo3.write(pos3);  
        pos3--;  
        delay(10);  
    }  
}  
  
if (pos4 < M4[k]) {  
    while (pos4 < M4[k]) {  
        myservo4.write(pos4);  
        pos4++;  
        delay(10);  
    }  
}  
else {  
    while (pos4 > M4[k]) {  
        myservo4.write(pos4);  
        pos4--;  
        delay(10);  
    }  
}
```



```
    delay(100);

}

//exit loop

ps2x.enableRumble(); //enable rumble vibration

motors

ps2x.enablePressures();

ps2x.read_gamepad(false, vibrate);

vibrate = ps2x.Analog(PSAB_BLUE);

if (ps2x.Button(PSB_START)) { //press R3 and hold down START to
exit mode of motion memory

    Serial.println("break");

    t = 0;

    break;

}

}

}

}

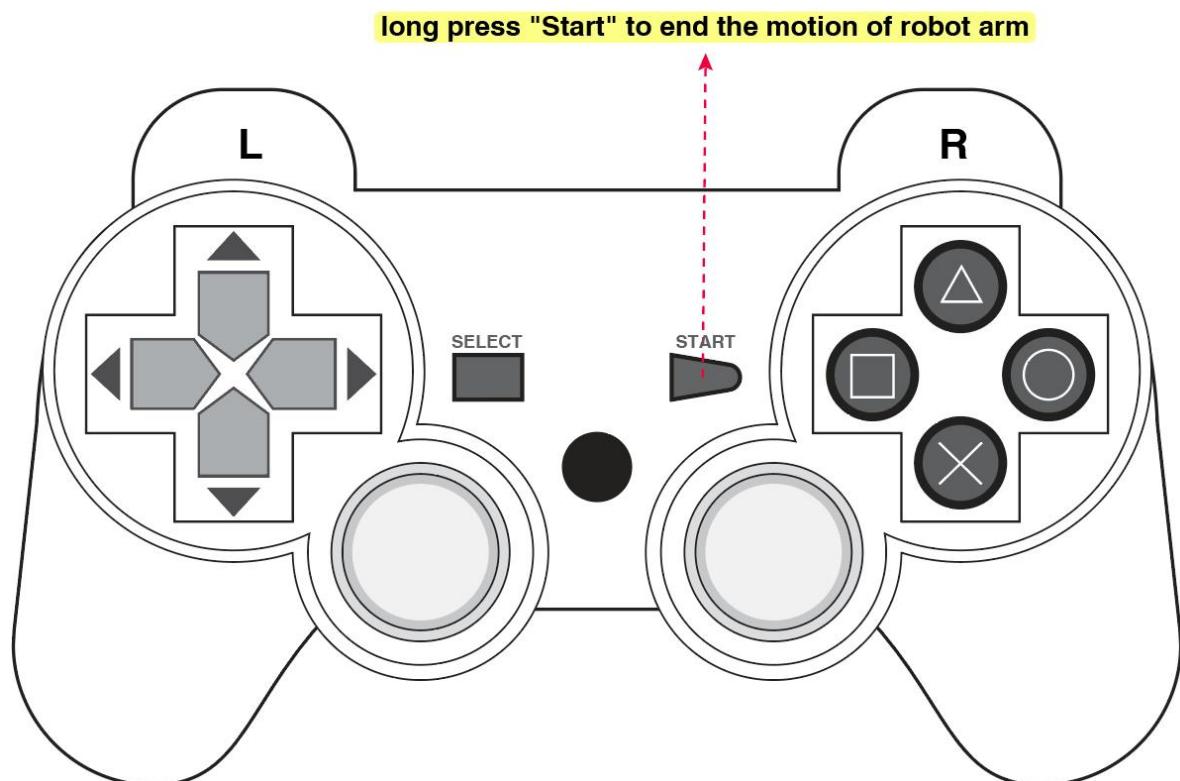
}
```

(4) Test Result:

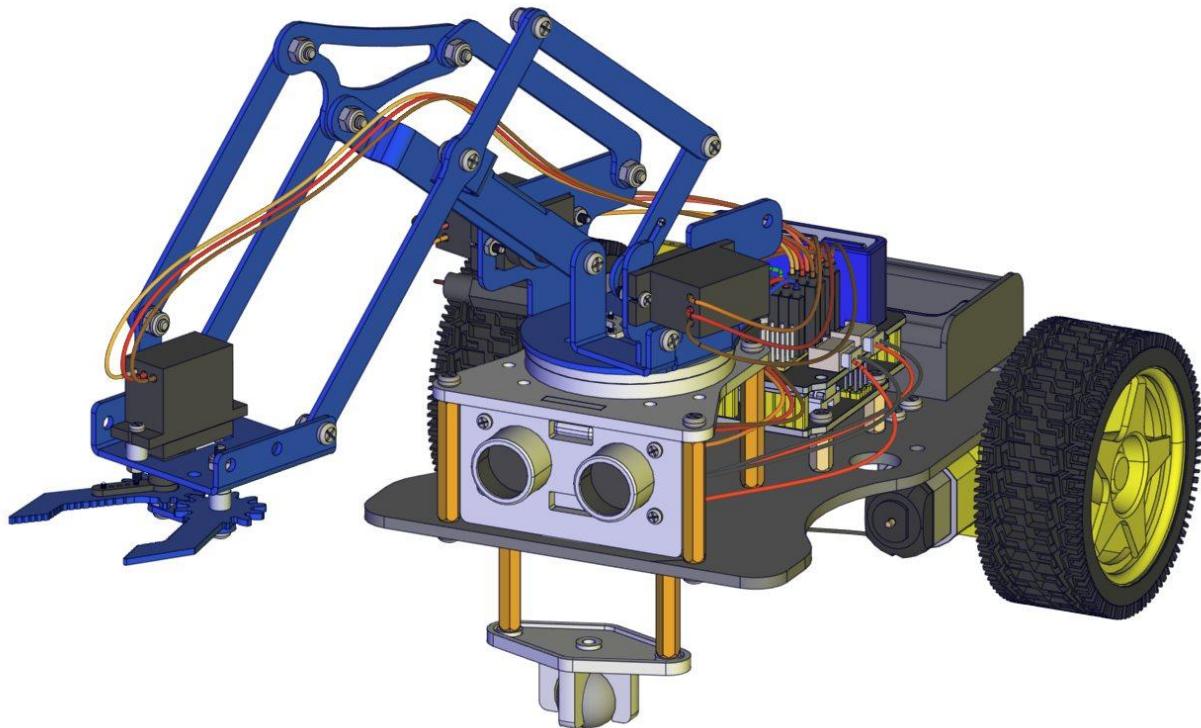
Upload code to PS2 joypad, and press memory key(left joystick handle) to save the posture.



As the robot arm demonstrates some postures, we press memory key to save them. For more actions to be saved, we just need to press execution key so that robot arm can memorize and show them ceaselessly. And it won't stop presenting actions until we press START key.



Combine Robot Arm and Smart Car

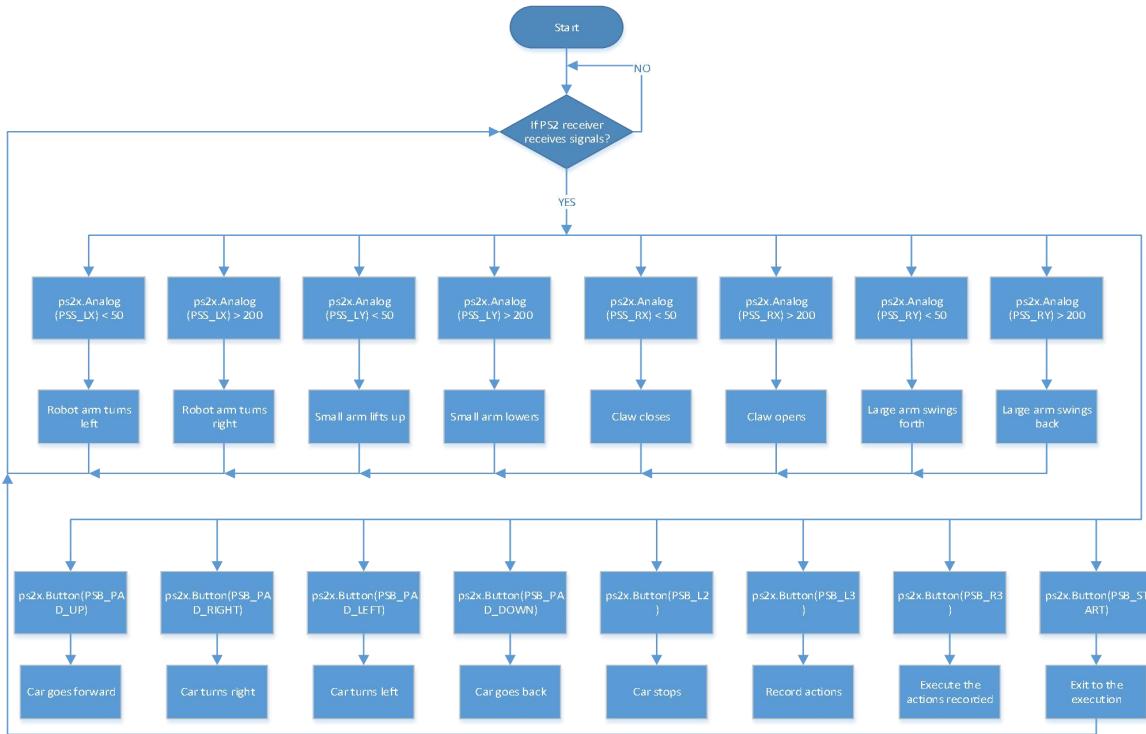


Project 19 PS2 Joypad Control Car

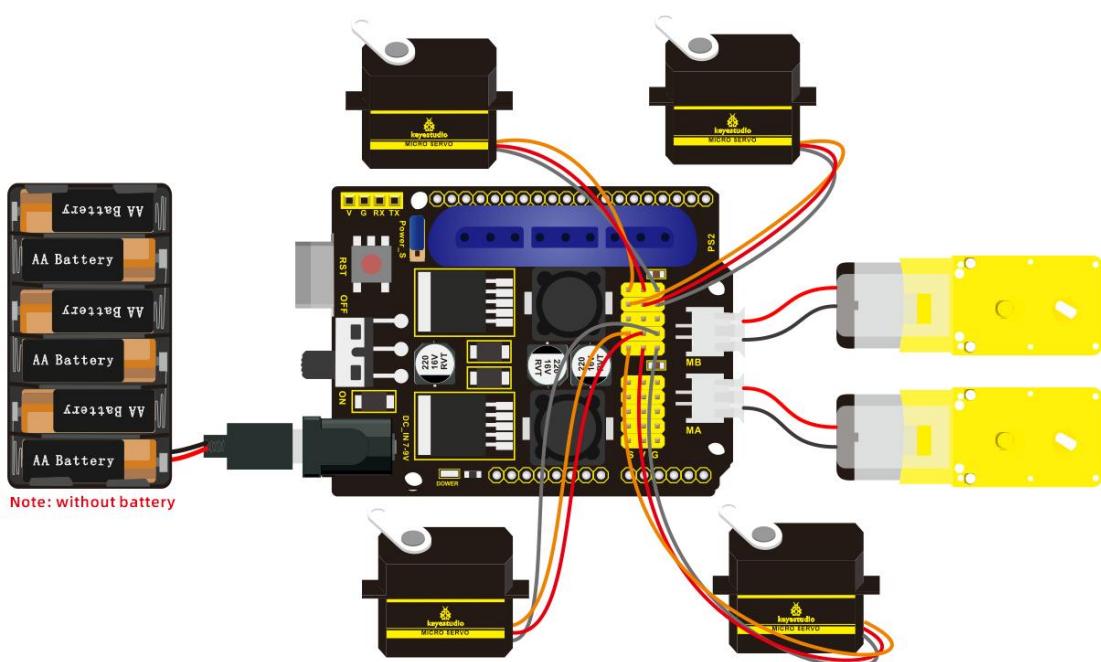
(1) Description:

In previous programs, we make PS2 joypad to control robot arm and smart car respectively. How about controlling them in unison? You could upload the following code to control smart car.

Flow Chart



(2) Connection Diagram:



Note: without battery



(3) Test Code:

```
/*
keyestudio 4DOF Mechanical Robot Arm Car
lesson 19
PS2 control car
http://www.keyestudio.com
*/
#include <PS2X_lib.h> //add library of ps2 handle
#include <Servo.h> //add the library of servo
PS2X ps2x; // create PS2 Controller Class
#define PS2_DAT 12 //ps2receiver
#define PS2_CMD 11
#define PS2_SEL 10
#define PS2_CLK 13
Servo myservo1; //define the name of servo variable
Servo myservo2; //define the name of servo variable
Servo myservo3; //define the name of servo variable
Servo myservo4; //define the name of servo variable
int error=0;
byte vibrate=0;
```



```
int pos1=90,pos2=100,pos3=80,pos4=90; // define angle variable of four servos  
and set initial value(posture angle value when setting up)
```

```
int M1[20];           //define four arrays  
int M2[20];           //Respectively save the angle of four servos  
int M3[20];           //array length is 20, can save 0~20 angle data  
int M4[20];  
  
int i=0,j=0,t=0;      //i is used to save array, j is used to save the maximum value  
of i,t is used to exit while loop  
  
const int AIN2=2;    //define the driving pins of motor  
  
const int PWMA=3;  
  
const int BIN2=4; //when AIN2 is low and AIN1 is high, BIN2 is high and BIN1 is  
low  
  
const int PWMB=5;  
  
void setup(){  
  Serial.begin(9600);  
  
  myservo1.attach(A1); //set control pin of servo 1 to A1  
  myservo2.attach(A0); //set control pin of servo 2 to A0  
  myservo3.attach(8);  //set control pin of servo 3 to D8  
  myservo4.attach(9);  //set control pin of servo 4 to D9  
  
  myservo3.write(pos3); //servo 3 rotates to 80°  
  
  delay(500);
```



```
myservo2.write(pos2); //servo 2 rotates 100°  
delay(500);  
myservo1.write(pos1); //posture to start up, servo rotates 90°  
delay(500);  
myservo4.write(pos4); //servo 4 rotates 90°  
pinMode(2,OUTPUT); //set ports of motor to output  
pinMode(3,OUTPUT);  
pinMode(4,OUTPUT);  
pinMode(5,OUTPUT);  
error=ps2x.config_gamepad(PS2_CLK,PS2_CMD,PS2_SEL,PS2_DAT); //setup  
pins check for error  
  
if(error==0){  
    Serial.println("Found Controller, configured successful");  
    Serial.println("Try out all the buttons, X will vibrate the controller, faster as  
you press harder");  
    Serial.println("holding L1 or R1 will print out the analog stick values.");  
    Serial.println("Go to www.billporter.info for updates and to report bugs.");  
}  
  
else if(error==1) Serial.println("No controller found, check wiring, see  
readme.txt to enable debug. visit www.billporter.info for troubleshooting tips");  
else if(error==2) Serial.println("Controller found but not accepting commands.  
see readme.txt to enable debug. Visit www.billporter.info for troubleshooting
```



tips");

```
ps2x.enableRumble(); //enable rumble vibration motors  
ps2x.enablePressures(); //enable reading the pressure values from the  
buttons.  
}
```

```
void loop(){
```

```
    if(error!=0) return;  
  
    memory(); //call memory function  
    if(ps2x.Button(PSB_PAD_UP)) { //will be TRUE as long as button is  
        pressed  
        Serial.print("Up held this hard: ");  
        advance();  
    }  
    if(ps2x.Button(PSB_PAD_RIGHT)){  
        Serial.print("Right held this hard: ");  
        turnR();  
    }  
    if(ps2x.Button(PSB_PAD_LEFT)){  
        Serial.print("LEFT held this hard: ");  
        turnL();
```



```
    }

    if(ps2x.Button(PSB_PAD_DOWN)){
        Serial.print("DOWN held this hard: ");
        back();
    }

    if(ps2x.Button(PSB_L2))
    {
        Serial.println("L2 pressed");
        stopp();
    }

down_ser(); //call function of servo on base
left_ser(); //call left servo function
right_ser(); //call right servo function
zhuazi(); //all claw function
delay(10);

}

void down_ser(){ //servo on base
    if(ps2x.Analog (PSS_LX) < 50) //put left joystick rightward
    {
        pos1=pos1+2;
    }
}
```



```
myservo1.write(pos1); //limit the angle of left swinging  
delay(2); //delay time to control rotation speed of servo  
if(pos1>179) //limit the angle of left swinging  
{  
    pos1=180;  
}  
}  
  
if(ps2x.Analog (PSS_LX) > 200) //put left joystick rightward  
{  
    pos1=pos1-2;  
    myservo1.write(pos1); //arm swings to right  
    delay(2); //delay time to control rotation speed of servo  
    if(pos1<1) //limit the angle of right swinging  
{  
        pos1=0;  
    }  
}  
}  
  
void left_ser(){ //left servo  
    if(ps2x.Analog(PSS_LY)<50) //put left joystick forward  
    {
```



```
pos2=pos2+2;  
  
myservo2.write(pos2); //swing forward  
  
delay(2);  
  
if(pos2>100) //limit the angle of forward swinging  
  
{  
  
    pos2=100;  
  
}  
  
}  
  
if(ps2x.Analog(PSS_LY)>200) //put left joystick backward  
  
{  
  
    pos2=pos2-2;  
  
    myservo2.write(pos2); //swing back  
  
    delay(2);  
  
    if(pos2<1) //limit the angle of back swinging  
  
    {  
  
        pos2=0;  
  
    }  
  
}  
  
}  
  
void right_ser(){ //right servo  
  
if(ps2x.Analog(PSS_RY)<50) //put right joystick forward
```



```
{  
    pos3=pos3+2;  
    myservo3.write(pos3); //bigger arm swings forward  
    delay(2);  
    if(pos3>180) //limit the angle of forward swinging  
    {  
        pos3=180;  
    }  
}  
  
if(ps2x.Analog(PSS_RY)>200) //put right joystick backward  
{  
    pos3=pos3-2;  
    myservo3.write(pos3); //bigger arm swings back  
    delay(2);  
    if(pos3<80) //limit the angle of back swinging  
    {  
        pos3=80;  
    }  
}  
}  
  
void zhuazi(){ //servo of claw
```



```
if(ps2x.Analog(PSS_RX)>200) //put right joystick rightward
{
    myservo4.write(pos4); //servo 4 moves, claw gradually opens
    pos4+=3;
    delay(1);
    if(pos4>180) //limit angle
    {
        pos4=180;
    }
}

if(ps2x.Analog(PSS_RX)<50) ///put right joystick leftward
{
    myservo4.write(pos4); //servo 4 executes pose, claw gradually closes
    pos4-=3;
    delay(1);
    if(pos4<95) //limit the closed angle
    {
        pos4=95;
    }
}
```



```
void memory(){ //ps2 memory function
    ps2x.read_gamepad(false, vibrate); //read controller
    if (ps2x.NewButtonState()){
        // delay(20);

        ps2x.read_gamepad(false, vibrate);
        if(ps2x.Button(PSEN_L3)){ //press L3, true
            Serial.println("L3 pressed");

            M1[i]=myservo1.read(); //read the angle value of each servo
            delay(100);

            Serial.println(M1[i]); //print the current angle value of servo 1 in serial
monitor

            M2[i]=myservo2.read();
            delay(100);
            Serial.println(M2[i]);
            M3[i]=myservo3.read();
            delay(100);
            Serial.println(M3[i]);
            M4[i]=myservo4.read();
            delay(100);
            Serial.println(M4[i]);
            i++; //i increases when save each time
            if(i>20)i=19;
        }
    }
}
```



```
j=i; //set the last value of i to j  
delay(200);  
Serial.print("j=");  
Serial.println(j); //print j value in serial monitor  
}  
  
  
if(ps2x.Button(PB_R3)){ //If R3 is pressed, if it is, it's true  
Serial.println("R3 pressed");  
i=0; //i clears  
t=1; //used for while loop  
pos1 = myservo1.read(); //read the current angle value of servo  
pos2 = myservo2.read();  
pos3 = myservo3.read();  
pos4 = myservo4.read();  
while(t){  
for(int k=0;k<j;k++){ //loop j times, execute all saved motions  
if(pos1<M1[k]){ //when the angle value of servo 1 is more than the  
value saved in array 1  
while(pos1<M1[k]){ //while loop , make servo rotate to value  
where array is saved  
myservo1.write(pos1); //servo 1 executes posture  
pos1++; //pose increases 1
```



```
    delay(10);          //delay 10ms to control rotation  
    speed of servo  
}  
  
}  
  
else{      //when the angle of servo 1 is more than the value saved in  
array 1  
    while(pos1>M1[k]){    //while loop ,  make servo rotate to value  
where the array is saved  
        myservo1.write(pos1);    //servo 1 executes posture  
        pos1--;                //pose reduces 1  
        delay(10);            //delay 10ms to control rotation  
speed of servo  
    }  
}  
  
if(pos2<M2[k]){

    while(pos2<M2[k]){
        myservo2.write(pos2);
        pos2++;
        delay(10);

    }
}
```



```
else{

    while(pos2>M2[k]){

        myservo2.write(pos2);

        pos2--;

        delay(10);

    }

}

if(pos3<M3[k]){

    while(pos3<M3[k]){

        myservo3.write(pos3);

        pos3++;

        delay(10);

    }

}

else{

    while(pos3>M3[k]){

        myservo3.write(pos3);

        pos3--;

        delay(10);

    }

}
```



```
if(pos4<M4[k]){
    while(pos4<M4[k]){
        myservo4.write(pos4);
        pos4++;
        delay(10);
    }
}
else{
    while(pos4>M4[k]){
        myservo4.write(pos4);
        pos4--;
        delay(10);
    }
}
//exit loop
ps2x.enableRumble(); //enable rumble vibration motors
ps2x.enablePressures();
ps2x.read_gamepad(false, vibrate);
vibrate = ps2x.Analog(PSAB_BLUE);
if(ps2x.Button(PB_START)){ //press R3 and hold down START to exit
```



mode of motion memory

```
    Serial.println("break");

    t=0;

    break;

}

delay(50);

}

}

}

void advance() { //go forward

    digitalWrite(AIN2, LOW); //when AIN2 is low and AIN1 is high, motor MA turns
clockwise

    analogWrite(PWMA, 100); //rotation speed of motor MA is 100

    digitalWrite(BIN2, HIGH); //When BIN2 is high and BIN1 is low, motor MB turns
clockwise

    analogWrite(PWMB, 100); //rotation speed of motor MB is 100

}

void turnL() { //turn left

    digitalWrite(AIN2, HIGH); //when AIN2 is high and AIN1 is low, motor MA turns
anticlockwise

    analogWrite(PWMA, 100); //rotation speed of motor MA is 100
```



```
digitalWrite(BIN2, HIGH); //When BIN2 is high and BIN1 is low, motor MB turns
clockwise

analogWrite(PWMB, 100); //rotation speed of motor MB is 100

}

void turnR() { //turn right

    digitalWrite(AIN2, LOW); //when AIN2 is low and AIN1 is high, motor MA turns
clockwise

    analogWrite(PWMA, 100); //rotation speed of motor MA is 100

    digitalWrite(BIN2, LOW); //When BIN2 is low and BIN1 is high, motor MB turns
clockwise

    analogWrite(PWMB, 100); //rotation speed of motor MB is 100

}

void back() { //go back

    digitalWrite(BIN2, LOW); //When BIN2 is low and BIN1 is high motor MB turns
anticlockwise

    analogWrite(PWMB, 100); //rotation speed of motor MB is 100

    digitalWrite(AIN2, HIGH); //when AIN2 is high and AIN1 is low, motor MA turns
anticlockwise

    analogWrite(PWMA, 100); //rotation speed of motor MA is 100

}

void stopp() { //stop

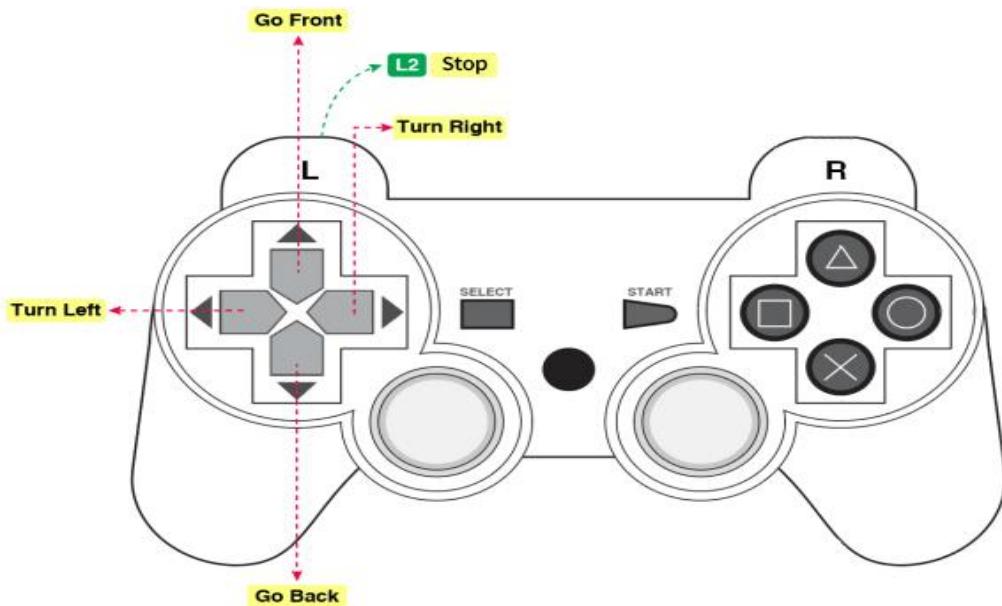
    analogWrite(PWMA, 0); //rotation speed of motor MA is 0
```



```
analogWrite(PWMB, 0); //rotation speed of motor MB is 0  
}
```

(4) Test Result:

Burn the above code to control car and robot arm simultaneously through PS2 joypad. The button keys are used to drive the robot car, and PS2 joystick is used to control robot arm



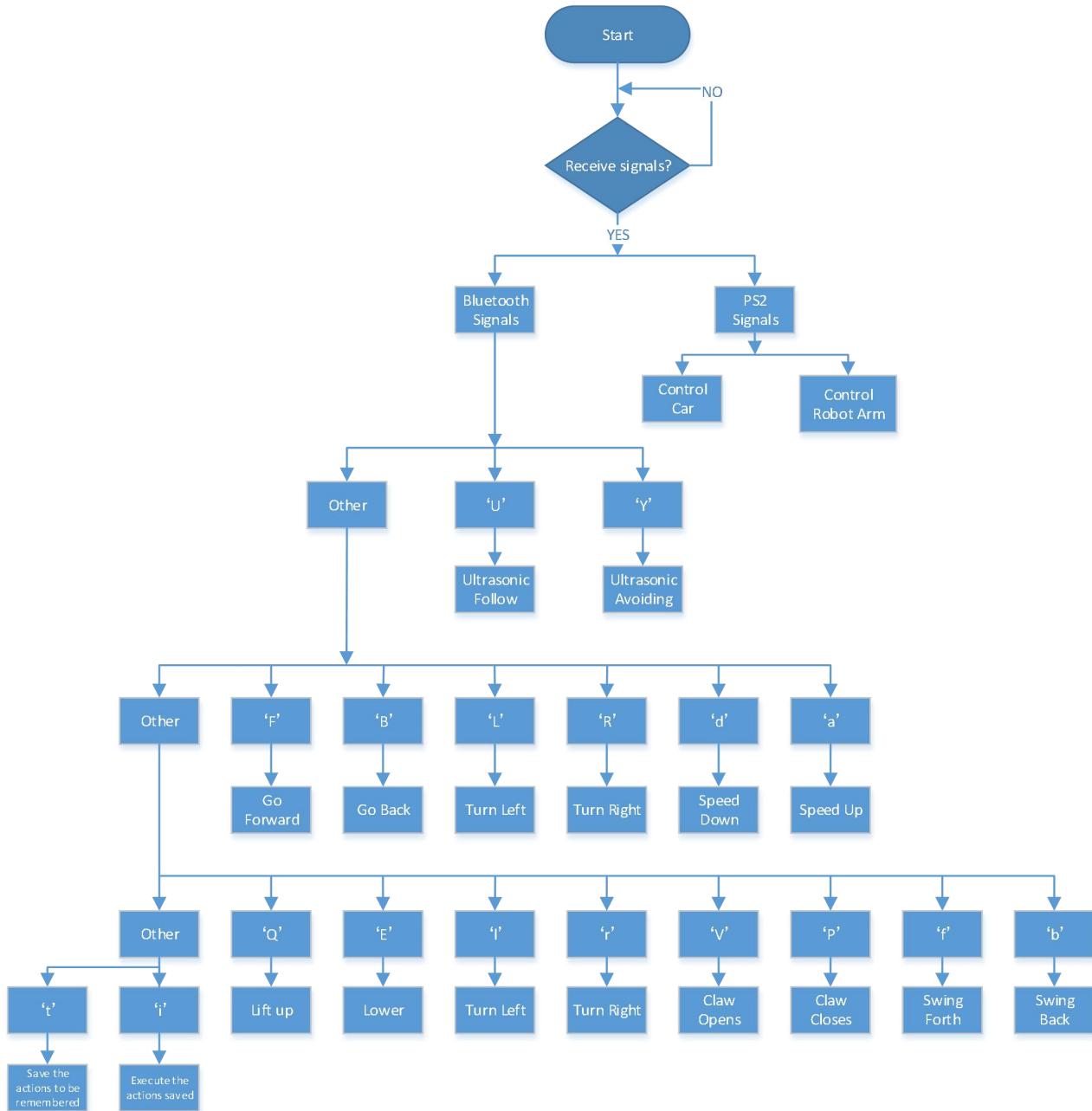


Project 20 Mechanical Arm Smart Car

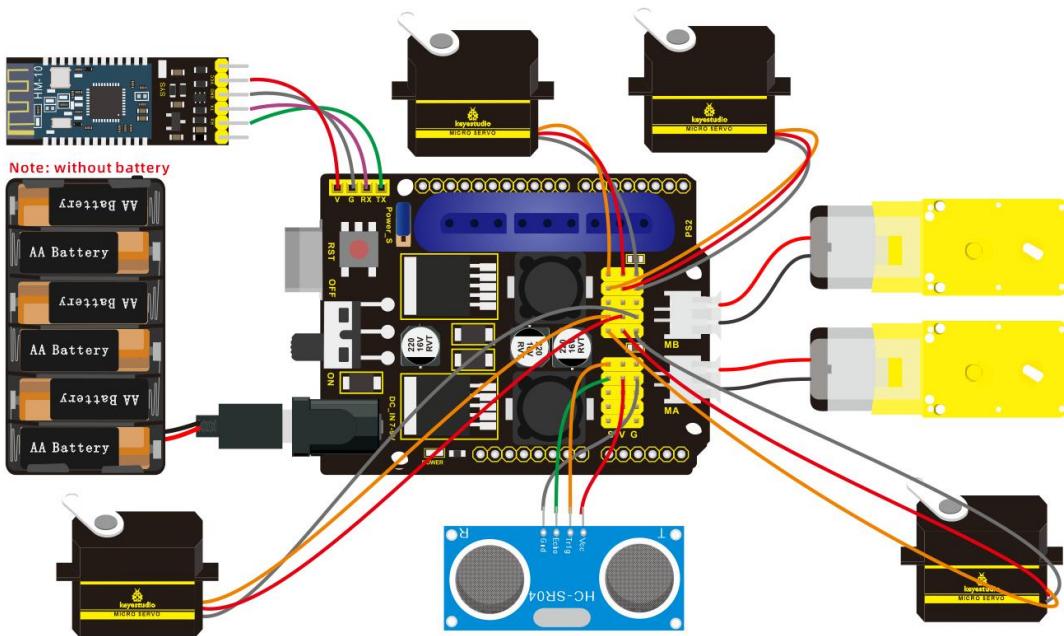
(1) Description:

From now, we've known multiple functions of smart car and mechanical arm. In fact, we could combine them together. Apply the following code, we could make robot arm car demonstrate all functions.

Flow Chart



(2) Connection Diagram:



(3) Test Code:

```
/*
```

keyestudio 4DOF Mechanical Robot Car

lesson 20

Multifunctional robotic arm robot

<http://www.keyestudio.com>

```
*/
```

```
#include <PS2X_lib.h> //add the library of ps2 handle
```

```
#include <Servo.h> //add the library of servo
```

```
PS2X ps2x; // create PS2 Controller Class
```

```
#define PS2_DAT 12 //ps2receiver
```

```
#define PS2_CMD 11
```



```
#define PS2_SEL      10
#define PS2_CLK       13

Servo myservo1; //define the name of servo variable
Servo myservo2; //define the name of servo variable
Servo myservo3; //define the name of servo variable
Servo myservo4; //define the name of servo variable

int error = 0;

byte vibrate = 0;

int pos1 = 90, pos2 = 100, pos3 = 80, pos4 = 90; // define angle variable of four
servos and set initial value(posture angle value when setting up)

char blue_val;

int M1[20];           //define four arrays
int M2[20];           //respectively save the angle of four servos
int M3[20];           //the array length is 20, can save 0~20 angle data
int M4[20];

int i = 0, j = 0, t = 0; //i is used to save array, j is used to save the maximum value
of i,t is used to exit while loop

const int AIN2 = 2; //define the driving pins of motor
const int PWMA = 3;
const int BIN2 = 4; //when AIN2 is low and AIN1 is high, BIN2 is high and BIN1 is
low
const int PWMB = 5;
```



```
int echoPin = A3; // ultrasonic module    ECHO to A3
int trigPin = A4; // ultrasonic module    TRIG to A4
int speeds = 100; // set the initial value of rotation speed of motor
int Ultrasonic_Ranging() { //ultrasonic ranging function
    digitalWrite(trigPin, LOW);
    delayMicroseconds(2);
    digitalWrite(trigPin, HIGH);
    delayMicroseconds(10); //send least 10us high level to trig pin to trigger
    ultrasonic waves
    digitalWrite(trigPin, LOW);
    int distance = pulseIn(echoPin, HIGH); // reading the duration of high level
    distance = distance / 58; // Transform pulse time to distance
    delay(30);
    return distance; //return distance to this function
}
void setup() {
    Serial.begin(9600); //set to baud rate to 57600 when printing ps2, however,
    Bluetooth can't be used
    myservo1.attach(A1); //set control pin of servo 1 to A1
    myservo2.attach(A0); //set control pin of servo 2 to A0
    myservo3.attach(8); //set control pin of servo 3 to D8
    myservo4.attach(9); //set control pin of servo 4 to D9
```



```
myservo3.write(pos3); //servo 3 rotates to 80°  
delay(500);  
myservo2.write(pos2); //servo 2 rotates to 100°  
delay(500);  
myservo1.write(pos1); //servo 1 rotates to 90°  
delay(500);  
myservo4.write(pos4); //servo 4 rotates to 90°  
pinMode(2, OUTPUT); //set ports of motor to output  
pinMode(3, OUTPUT);  
pinMode(4, OUTPUT);  
pinMode(5, OUTPUT);  
pinMode(echoPin, INPUT); //set echoPin to input  
pinMode(trigPin, OUTPUT); //set trigPin to output  
error = ps2x.config_gamepad(PS2_CLK, PS2_CMD, PS2_SEL, PS2_DAT);  
//setup pins check for error  
if (error == 0) {  
    Serial.println("Found Controller, configured successful");  
    Serial.println("Try out all the buttons, X will vibrate the controller, faster as  
you press harder.");  
    Serial.println("holding L1 or R1 will print out the analog stick values.");  
    Serial.println("Go to www.billporter.info for updates and to report bugs.");  
}
```

```
else if (error == 1) Serial.println("No controller found, check wiring, see  
readme.txt to enable debug. visit www.billporter.info for troubleshooting tips");  
  
else if (error == 2) Serial.println("Controller found but not accepting  
commands. see readme.txt to enable debug. Visit www.billporter.info for  
troubleshooting tips");  
  
  
ps2x.enableRumble(); //enable rumble vibration motors  
ps2x.enablePressures(); //enable reading the pressure values from the  
buttons.  
}
```

```
void loop() {  
  
if (error != 0) return;  
  
if (Serial.available() > 0) { //determine if Bluetooth receives signals  
blue_val = Serial.read();  
Serial.println(blue_val);  
switch (blue_val) {  
  
case 'F': advance(); break; //receive 'F' to go forward  
case 'B': back(); break; //receive 'B' to go back  
  
case 'L': turnL(); break; //receive 'L' to turn left
```



```
case 'R': turnR(); break; //receive 'R' to turn right
```

```
case 'S': stopp(); break; //receive 'S' to stop
```

```
case 'a': speeds_a(); break; //receive 'a' , car speeds up
```

```
case 'd': speeds_d(); break; //receive 'd' , car speeds down
```

```
case 'Q': LF(); break; //smaller arm lifts up
```

```
case 'E': LB(); break; //smaller arm lifts down
```

```
case 'l': T_left(); break; //arm turns left
```

```
case 'r': T_right(); break; //arm turns right
```

```
case 'f': RF(); break; //bigger swings forward
```

```
case 'b': RB(); break; //bigger arm swings back
```

```
case 'V': ZK(); break; //claw opens
```

```
case 'P': ZB(); break; //claw closes
```



```
case 't': read_servo(); break; //receive 't' , remember the motion

case 'i': do_servo(); break;

case 'Y': avoid(); break; //receive 'Y' to enable obstacle avoidance mode
case 'U': follow(); break; //receive 'U' to enable ultrasonic follow mode
default: break;

}

}

if (ps2x.Button(PSB_PAD_UP)) {           //will be TRUE as long as button is
pressed

    Serial.print("Up held this hard: ");
    advance();
}

if (ps2x.Button(PSB_PAD_RIGHT)) {
    Serial.print("Right held this hard: ");
    turnR();
}

if (ps2x.Button(PSB_PAD_LEFT)) {
    Serial.print("LEFT held this hard: ");
    turnL();
}
```



```
}

if (ps2x.Button(PSB_PAD_DOWN)) {

    Serial.print("DOWN held this hard: ");

    back();

}

if (ps2x.Button(PSB_L2))

{

    Serial.println("L2 pressed");

    stopp();

}

memory(); //call the memory function

down_ser(); //call the servo on base function

left_ser(); //call the left servo function

right_ser(); // call the right servo function

zhuazi(); //call claw function

delay(10);

}
```

```
void speeds_a() {

    int a_flag = 1;

    while (a_flag) {

        Serial.println(speeds);

    }

}
```



```
if (speeds <= 254) { //maximize to add 255
    speeds++;
    delay(10); //change delayed time to alter the acceleration of car
}
blue_val = Serial.read();
if (blue_val == 'S') a_flag = 0; //receive 'S' to stop speeding up
}
}

void speeds_d() {
int d_flag = 1;
while (d_flag) {
    Serial.println(speeds);
    if (speeds >= 1) { //minimize to 0
        speeds--;
        delay(10); //change delayed time to alter the deacceleration of car
    }
    blue_val = Serial.read();
    if (blue_val == 'S') d_flag = 0; //receive 'S' to stop speeding down
}
}
```



```
void T_left() { //turn left  
    int left_flag = 1;  
    while (left_flag) {  
        pos1 += 1;  
        myservo1.write(pos1);  
        delay(8);  
        if (pos1 > 180) { // set the limited angle value of servo  
            pos1 = 180;  
        }  
        blue_val = Serial.read();  
        if (blue_val == 's')left_flag = 0;  
    }  
}
```

```
void T_right() { //turn right  
    int right_flag = 1;  
    while (right_flag) {  
        pos1 -= 1;  
        myservo1.write(pos1);  
        delay(8);  
        if (pos1 < 0) {  
            pos1 = 0;
```



```
}

blue_val = Serial.read();

if (blue_val == 's')right_flag = 0;

}

}

void ZB() { //claw closes

int ZB_flag = 1;

while (ZB_flag) {

pos4 -= 2;

myservo4.write(pos4);

delay(8);

if (pos4 <= 95) {

pos4 = 95;

}

blue_val = Serial.read();

if (blue_val == 's')ZB_flag = 0;

}

}

void ZK() { //claw opens

int ZK_flag = 1;
```



```
while (ZK_flag) {  
    pos4 += 2;  
    myservo4.write(pos4);  
    delay(8);  
    if (pos4 >= 180) {  
        pos4 = 180;  
    }  
    blue_val = Serial.read();  
    if (blue_val == 's') ZK_flag = 0;  
}  
  
}  
  
void LF() { //smaller arm lifts up  
    int LF_flag = 1;  
    while (LF_flag) {  
        pos2 += 1;  
        myservo2.write(pos2);  
        delay(8);  
        if (pos2 >= 100) {  
            pos2 = 100;  
        }  
        blue_val = Serial.read();
```



```
if (blue_val == 's')LF_flag = 0;  
}  
}
```

```
void LB() { //smaller arm lifts down
```

```
int LB_flag = 1;  
while (LB_flag) {  
    pos2 -= 1;  
    myservo2.write(pos2);  
    delay(8);  
    if (pos2 <= 1) {  
        pos2 = 0;  
    }  
    blue_val = Serial.read();  
    if (blue_val == 's')LB_flag = 0;  
}
```

```
void RF() { // bigger arm swings forward
```

```
int RF_flag = 1;  
while (RF_flag) {  
    pos3 += 1;  
    myservo3.write(pos3);
```



```
delay(8);

if (pos3 >= 180) {

    pos3 = 180;

}

blue_val = Serial.read();

if (blue_val == 's')RF_flag = 0;

}

void RB() { // bigger arm swings back

    int RB_flag = 1;

    while (RB_flag) {

        pos3 -= 1;

        myservo3.write(pos3);

        delay(8);

        if (pos3 <= 80) {

            pos3 = 80;

        }

        blue_val = Serial.read();

        if (blue_val == 's')RB_flag = 0;

    }

}

void read_servo() {
```



```
M1[i] = myservo1.read(); //save the current servo angles in array  
delay(100); //delay time to save angle value  
  
M2[i] = myservo2.read();  
delay(100);  
  
M3[i] = myservo3.read();  
delay(100);  
  
M4[i] = myservo4.read();  
delay(100);  
  
i++; //i increases 1 when save each time  
  
j = i; // set the value of i to j  
  
// if(i>20)i=19;  
delay(200);  
  
}  
  
void do_servo() {  
  
    i = 0; //i clears  
  
    t = 1; //used for while loop  
  
    pos1 = myservo1.read(); //read the current vale and set to pos  
  
    pos2 = myservo2.read();  
  
    pos3 = myservo3.read();  
  
    pos4 = myservo4.read();  
  
    while (t) {  
  
        for (int k = 0; k < j; k++) { //loop j times, execute all saved motions
```



```
if (pos1 < M1[k]) { //when the angle value of servo 1 is more than the  
value saved in array 1
```

```
    while (pos1 < M1[k]) { //while loop, make servo rotate to value where  
the array is saved
```

```
        myservo1.write(pos1); //servo 1 executes posture
```

```
        pos1++; //pos1 increases 1
```

```
        delay(8); //delay in 8ms to control rotation speed of servo
```

```
}
```

```
}
```

```
else { //when the angle of servo 1 is more than the value saved in array 1
```

```
    while (pos1 > M1[k]) { //while loop, make servo rotate to value where  
the array is saved
```

```
        myservo1.write(pos1); //servo 1 executes posture
```

```
        pos1--; //pos1 reduces 1
```

```
        delay(8); //delay in 8ms to control rotation speed of servo
```

```
}
```

```
}
```

```
if (pos2 < M2[k]) {
```

```
    while (pos2 < M2[k]) {
```

```
        myservo2.write(pos2);
```

```
        pos2++;
```



```
    delay(8);

}

}

else {

    while (pos2 > M2[k]) {

        myservo2.write(pos2);

        pos2--;

        delay(8);

    }

}

if (pos3 < M3[k]) {

    while (pos3 < M3[k]) {

        myservo3.write(pos3);

        pos3++;

        delay(8);

    }

}

else {

    while (pos3 > M3[k]) {

        myservo3.write(pos3);

        pos3--;

    }

}
```



```
delay(8);

}

}

if (pos4 < M4[k]) {

    while (pos4 < M4[k]) {

        myservo4.write(pos4);

        pos4++;

        delay(8);

    }

}

else {

    while (pos4 > M4[k]) {

        myservo4.write(pos4);

        pos4--;

        delay(8);

    }

}

if (Serial.available() > 0) { //exit loop

    if (Serial.read() == 't') { //receive 'i' and 't'

        t = 0; //set t to 0, exit while loop
    }
}
```



```
break; //exit

}

}

}

void avoid() { //ultrasonic obstacle avoidance

int avoid_flag = 1;

while (avoid_flag) {

    int distance = Ultrasonic_Ranging();

    Serial.print("distance=");

    Serial.println(distance);

    if (distance < 30 && distance > 2) { //when distance is less than 30cm

        if (distance < 18) { //when distance is less than 18, go back

            back();

            delay(300);

        }

        else { //when the distance is more than 18 and less than 30, turn right

            turnR();

            delay(300);

        }

    }

}
```



```
else { //when distance is more than 30, go forward  
    advance();  
}  
  
blue_val = Serial.read();  
  
if (blue_val == 'S') {  
    stopp();  
    avoid_flag = 0;  
}  
  
}  
  
}
```

```
void follow() { //ultrasonic follow  
    int follow_flag = 1;  
  
    while (follow_flag) {  
        int distance = Ultrasonic_Ranging();  
        Serial.print("distance=");  
        Serial.println(distance);  
        if (distance < 40 && distance > 2) { //if 2<distance <40  
            if (distance < 20) { //if distance < 20, go back  
                if (distance < 15) {  
                    back();  
                }  
            }  
        }  
    }  
}
```



```
else {  
    stopp();  
}  
  
}  
  
else { //if 20<distance<35, go forward  
    advance();  
}  
  
}  
  
else { //if distance>35 or distance<2, stop  
    stopp();  
}  
  
blue_val = Serial.read();  
  
if (blue_val == 'S') {  
    stopp();  
    follow_flag = 0;  
}  
  
}  
  
}  
  
void down_ser() { //servo on base  
    if (ps2x.Analog (PSS_LX) < 50) //move the left joystick to left  
    {
```



```
pos1 = pos1 + 2;  
  
myservo1.write(pos1); //arm swings to left  
  
delay(2); //delay time to control rotation speed of servo  
  
if (pos1 > 179) //limit the angle of left swinging  
  
{  
  
    pos1 = 180;  
  
}  
  
}  
  
if (ps2x.Analog (PSS_LX) > 200) //move the left joystick to right  
  
{  
  
    pos1 = pos1 - 2;  
  
    myservo1.write(pos1); //arm swings to right  
  
    delay(2); //delay time to control rotation speed of servo  
  
    if (pos1 < 1) //limit the angle of right swinging  
  
    {  
  
        pos1 = 0;  
  
    }  
  
}  
  
}  
  
void left_ser() { //left servo  
  
    if (ps2x.Analog(PSS LY) < 50) //move the left joystick forward  
  
    {
```



```
pos2 = pos2 + 2;  
  
myservo2.write(pos2); //arm swings forward  
  
delay(2);  
  
if (pos2 > 100) //limit the angle of forward swinging  
  
{  
  
    pos2 = 100;  
  
}  
  
}  
  
if (ps2x.Analog(PSS_LY) > 200) //move the left joystick backward  
  
{  
  
    pos2 = pos2 - 2;  
  
    myservo2.write(pos2); //arm swings back  
  
    delay(2);  
  
    if (pos2 < 0) //limit the angle of back swinging  
  
    {  
  
        pos2 = 0;  
  
    }  
  
}  
  
}  
  
void right_ser() { //right servo
```



```
if (ps2x.Analog(PSS_RY) < 50) //move the right joystick forward
{
    pos3 = pos3 + 2;
    myservo3.write(pos3); //bigger arm swings forward
    delay(2);
    if (pos3 > 180) //limit the angle of forward swinging
    {
        pos3 = 180;
    }
}

if (ps2x.Analog(PSS_RY) > 200)//move the right joystick backward
{
    pos3 = pos3 - 2;
    myservo3.write(pos3); //arm swings back
    delay(2);
    if (pos3 < 80) //limit the angle of back swinging
    {
        pos3 = 80;
    }
}
```



```
void zhuazi() { //servo of claw
    if (ps2x.Analog(PSS_RX) > 200) //move the right joystick to right
    {
        myservo4.write(pos4); //servo 4 moves, claw gradually opens
        pos4 += 3;
        delay(1);
        if (pos4 > 180) //limit angle
        {
            pos4 = 180;
        }
    }
    if (ps2x.Analog(PSS_RX) < 50) ///move the right joystick to left
    {
        myservo4.write(pos4); //servo 4 executes pose, claw gradually closes
        pos4 -= 3;
        delay(1);
        if (pos4 < 95) //limit to open the maximum angle
        {
            pos4 = 95;
        }
    }
}
```



```
void memory() { //ps2memory function
    ps2x.read_gamepad(false, vibrate); //read controller
    if (ps2x.NewButtonState()) {
        //      delay(20);
        ps2x.read_gamepad(false, vibrate);
    }
    if (ps2x.Button(PSP_L3)) { //press L3, true
        Serial.println("L3 pressed");
        M1[i] = myservo1.read(); //read the angle value of each servo
        delay(100);
        Serial.println(M1[i]); //print the current angle value of servo 1 in serial
        monitor
        M2[i] = myservo2.read();
        delay(100);
        Serial.println(M2[i]);
        M3[i] = myservo3.read();
        delay(100);
        Serial.println(M3[i]);
        M4[i] = myservo4.read();
        delay(100);
        Serial.println(M4[i]);
        i++; // i increases when save each time
    }
}
```



```
if (i > 20)i = 19; // the define array length is 20  
j = i; //set the last value of i to j  
delay(200);  
Serial.print("j=");  
Serial.println(j); //print j value in serial monitor  
}  
  
if (ps2x.Button(PSB_R3)) { //if R3 is pressed, true  
Serial.println("R3 pressed");  
i = 0; //i clears  
t = 1; //used for while loop  
pos1 = myservo1.read(); //read the current angle value of servo  
pos2 = myservo2.read();  
pos3 = myservo3.read();  
pos4 = myservo4.read();  
while (t) {  
for (int k = 0; k < j; k++) { //loop j times, execute all saved motions  
  
if (pos1 < M1[k]) { //when the angle value of servo 1 is more than  
the value saved in array 1  
while (pos1 < M1[k]) { //while loop, make servo rotate to value  
where the array is saved  
myservo1.write(pos1); //servo 1 executes posture
```



```
    pos1++;           //pos1 increases 1
    delay(10);        //delay 10ms to control rotation
speed of servo

}
}

else { //when the angle of servo 1 is more than the value saved in
array 1

    while (pos1 > M1[k]) { //while loop, make servo rotate to value
where the array is saved

        myservo1.write(pos1);      //servo 1 executes posture
        pos1--;                  //pose reduces 1
        delay(10);                //delay 10ms to control rotation
speed of servo

}
}

if (pos2 < M2[k]) {

    while (pos2 < M2[k]) {

        myservo2.write(pos2);
        pos2++;
        delay(10);

}
}
```



```
}

else {

    while (pos2 > M2[k]) {

        myservo2.write(pos2);

        pos2--;

        delay(10);

    }

}

if (pos3 < M3[k]) {

    while (pos3 < M3[k]) {

        myservo3.write(pos3);

        pos3++;

        delay(10);

    }

}

else {

    while (pos3 > M3[k]) {

        myservo3.write(pos3);

        pos3--;

        delay(10);

    }

}
```



```
}

if (pos4 < M4[k]) {

    while (pos4 < M4[k]) {

        myservo4.write(pos4);

        pos4++;

        delay(10);

    }

}

else {

    while (pos4 > M4[k]) {

        myservo4.write(pos4);

        pos4--;

        delay(10);

    }

}

delay(50);

}

//exit loop

ps2x.enableRumble();           //enable rumble vibration motors

ps2x.enablePressures();

ps2x.read_gamepad(false, vibrate);
```



```
vibrate = ps2x.Analog(PSAB_BLUE);

if (ps2x.Button(PSB_START)) { //press R3 and hold down START to exit
mode of motion memory

    Serial.println("break");

    t = 0;

    break;

}

}

}

}

void advance() { //go forward

    digitalWrite(AIN2, LOW); //when AIN2 is low and AIN1 is high, motor MA turns
clockwise

    analogWrite(PWMA, speeds); //rotation speed of motor MA is speeds

    digitalWrite(BIN2, HIGH); //When BIN2 is high and BIN1 is low, motor MB turns
clockwise

    analogWrite(PWMB, speeds); //rotation speed of motor MB is speeds

}

void turnL() { //turn left
```



```
digitalWrite(AIN2, HIGH); //when AIN2 is high and AIN1 is low, motor MA turns  
anticlockwise  
  
analogWrite(PWMA, speeds); //rotation speed of motor MA is speeds  
  
digitalWrite(BIN2, HIGH); //When BIN2 is high and BIN1 is low, motor MB turns  
clockwise  
  
analogWrite(PWMB, speeds); //rotation speed of motor MB is speeds  
  
}  
  
void turnR() { //turn right  
  
    digitalWrite(AIN2, LOW); //when AIN2 is low and AIN1 is high, motor MA turns  
clockwise  
  
    analogWrite(PWMA, speeds); //rotation speed of motor MA is speeds  
  
    digitalWrite(BIN2, LOW); //When BIN2 is low and BIN1 is high, motor MB turns  
clockwise  
  
    analogWrite(PWMB, speeds); //rotation speed of motor MB is speeds, the same  
below  
  
}  
  
void back() { //go back  
  
    digitalWrite(BIN2, LOW); //When BIN2 is low and BIN1 is high motor MB turns  
anticlockwise  
  
    analogWrite(PWMB, speeds); //rotation speed of motor MB is speeds, the  
same below  
  
    digitalWrite(AIN2, HIGH); //when AIN2 is high and AIN1 is low, motor MA turns
```

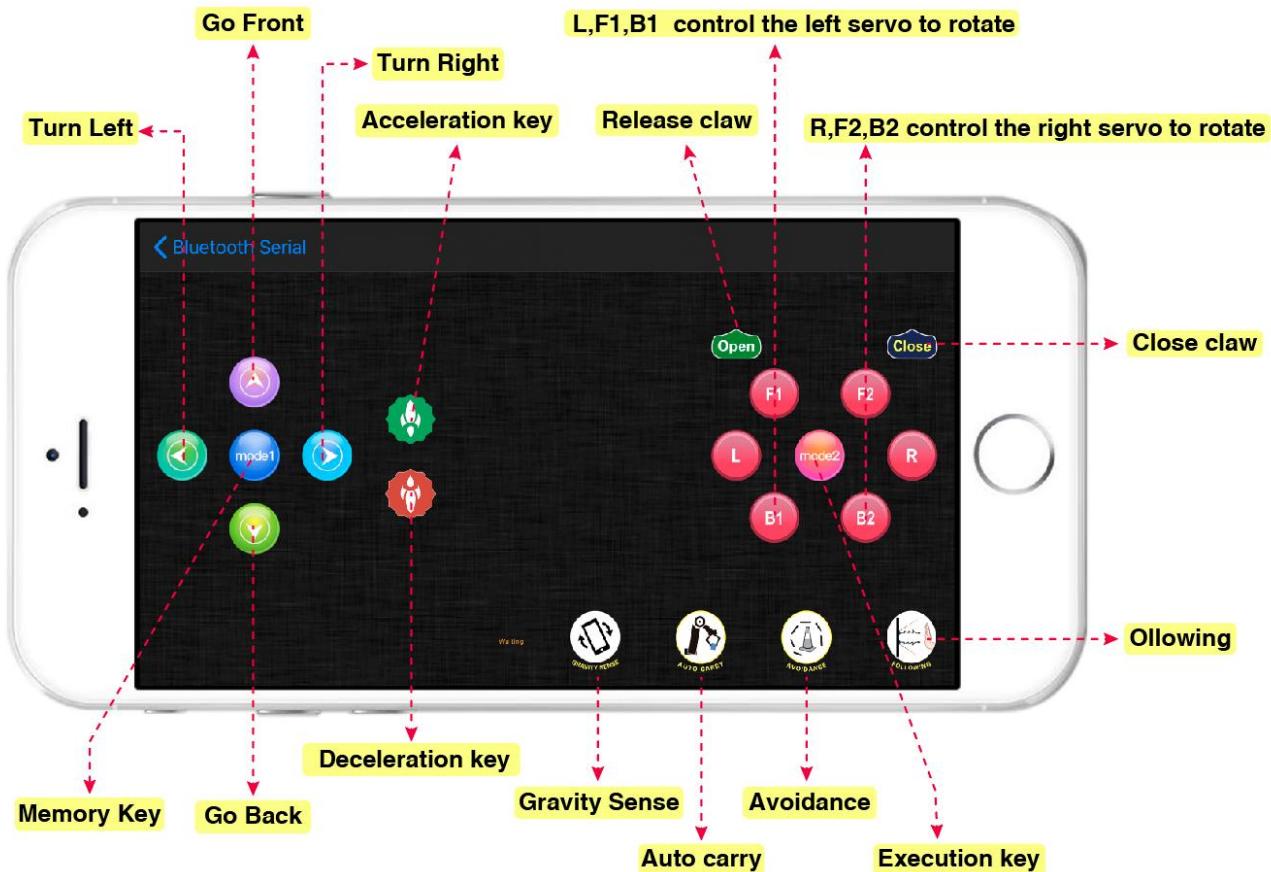


anticlockwise

```
analogWrite(PWMA, speeds); //rotation speed of motor MA is speeds  
}  
  
void stopp() { //stop  
  
analogWrite(PWMA, 0); //rotation speed of motor MA is 0  
  
analogWrite(PWMB, 0); //rotation speed of motor MB is 0  
  
}
```

(4) Test Result:

Upload code, plug in PS2 receiver, you could control robot arm car to execute different movements, as well as transforming into obstacle avoidance mode. What's more, you can combine app and PS2 joypad to make robot arm to carry and grip something.



Q&A

(1) No response on smart car

- A: 1. If battery works normally.
5. Make sure you wire up correctly

(2) Q: Computer can't identify USB port

- A: Must follow the instruction to install the drive of CP2012 chip(seen in the Project 5)

B. Check if USB cable is good

(3) Unable to upload code

1. Try to burn code with V4.0 board(Plug off external sensors)
2. Don't insert Bluetooth module into expansion board when uploading code; otherwise, the code fails to be uploaded.

(4) Abnormal movements on robotic arm

A: make sure that you've initialized the servo

10. Resource

<https://fs.keyestudiocom/KS0520>