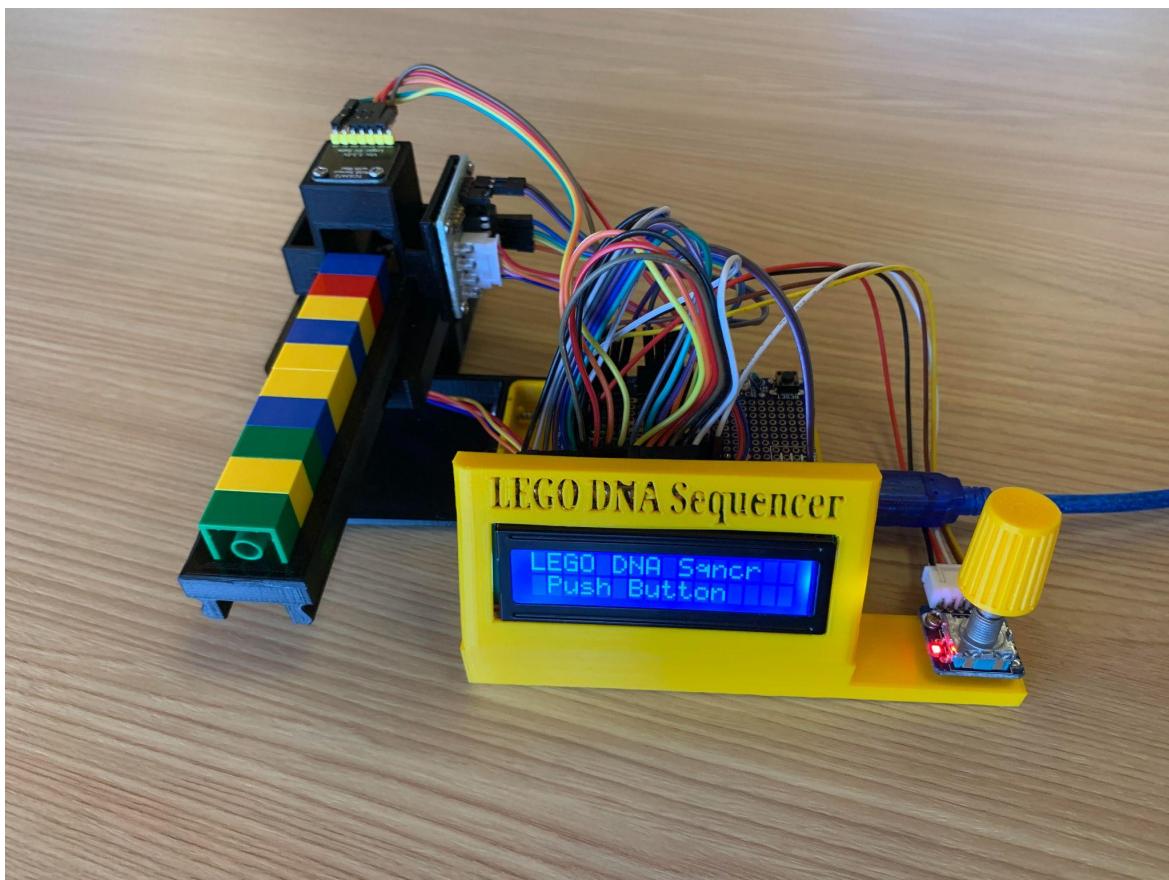


# LEGO DNA Sequencer

## and DIY Construction

2023-04-19 Rev 0.5

The purpose of this LEGO DNA Sequencer and DIY Construction is to provide a complete blueprint for an open source tool that can be used to explain the complex DNA sequencing operation with a colorful easy to understand model.



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# Table of Contents

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<b>Overview</b>	<b>5</b>
<b>Users Manual</b>	<b>6</b>
Starting the System	6
Loading the LEGO Tray	9
Beginning the Sequencing	10
Unloading the LEGO Tray	11
UNKNOWN DNA	14
Updating the Database with a new DNA	15
Troubleshooting	22
Adjustment of the LEGO Tray Position	22
Adjustments to the Color Channel Threshold Levels	24
Additional Operations	25
CANCEL	25
UNLOAD TRAY	25
LOAD TRAY	25
ZERO NEW DNA	25
BUZZER OFF	25
BUZZER ON	26
ADVANCED	26
Advanced Operations	26
CANCEL	26
CLEAR CHANNEL	26
RED CHANNEL	26
BLUE CHANNEL	26
AUTO CHANNEL	27
AUTO POSITION	27
REMOTE LCD ON	27
REMOTE LCD OFF	27
REBOOT	27
Remote LCD	28
RemoteLCD_PySimpleGUI	29
Installation for Remote LCD for PySimpleGUI	35

Windows	35
Mac	35
<b>RemoteLCD_tkinter</b>	<b>35</b>
Installation for Remote LCD for tkinter	42
Windows	42
Mac	42
<b>DIY: Build Your Own LEGO DNA Sequencer</b>	<b>43</b>
The DIY elements include:	43
The LEGO DNA Sequencer License	43
<b>Electronics</b>	<b>44</b>
Breadboard	45
Schematic	46
<b>3D Printed Parts</b>	<b>47</b>
Arduino and LCD Case	49
Color Sensor and Motor Drive Mount	50
Gear	51
LEGO Tray	52
Rotary Encoder Knob	53
Stepper Motor Mount	54
Tray Holder and Gear Mount	55
Buzzer Mount	56
Parts Remixed from Thingiverse.com	57
License	57
<b>Parts List</b>	<b>58</b>
Arduino Advanced Starter Kit	58
TCS34725 – RGB Color Sensor with IR filter and White LED	60
Hardware for the Assembly	61
<b>Assembly and Construction Step Details</b>	<b>62</b>
Assemble the electronics using the LEGO DNA Sequencer Breadboard.	63
Arduino and LCD Case	64
Complete the Assembly	67
<b>Unit and System Testing</b>	<b>79</b>
Buzzer Unit Test	80
LCD and Rotary Encoder Unit Test	82
Stepper Motor Unit Test	85
TCS34725 Color Sensor Unit Test	87

<b>Arduino Source Code</b>	<b>90</b>
<b>Remote LCD Python Source Code</b>	<b>126</b>
RemoteLCD_PySimpleGUI	126
RemoteLCD_tkinter	130
<b>Credits</b>	<b>133</b>

# Overview

The purpose of this document is to provide all of the necessary information to build your own LEGO DNA Sequencer. The electronics assembly, 3D printed parts, software, and assembly steps are described in detail. Also a complete Users Manual is provided describing the operation of the LEGO DNA Sequencer.

DNA sequencing determines the order of the four chemical building blocks - called "bases" - that make up the DNA molecule. The building blocks are composed of A (adenine), C (cytosine), G (guanine), and T (thymine). These building blocks are represented by LEGO® 2x2 bricks of **Red for G**, **Blue for T**, **Green for A**, and **Yellow for C**. Actual DNA sequencing is greatly simplified in this model by using genomes of only 10 building blocks to identify a species.

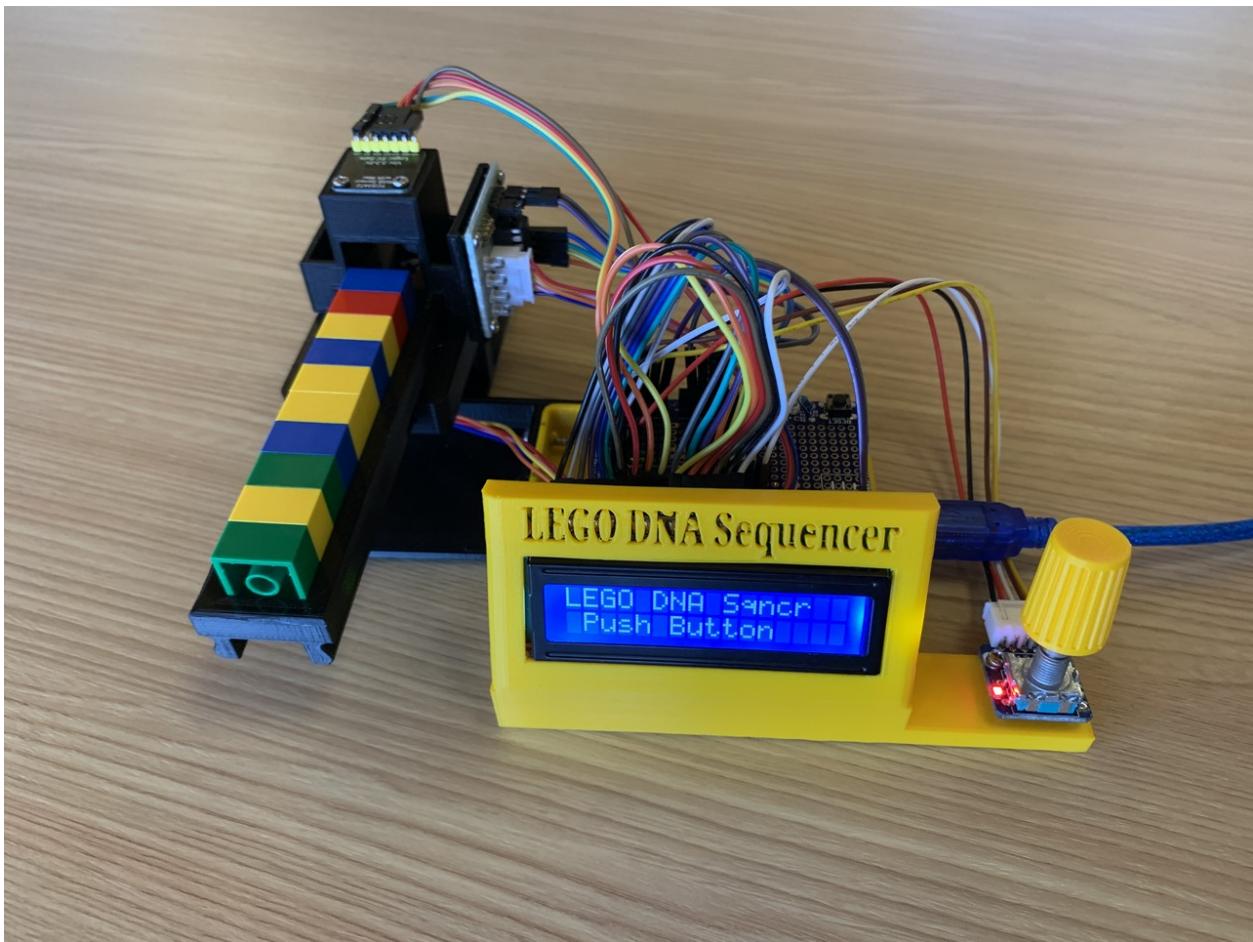
It is beyond the scope of this document to provide more details regarding actual DNA sequencing.

# Users Manual

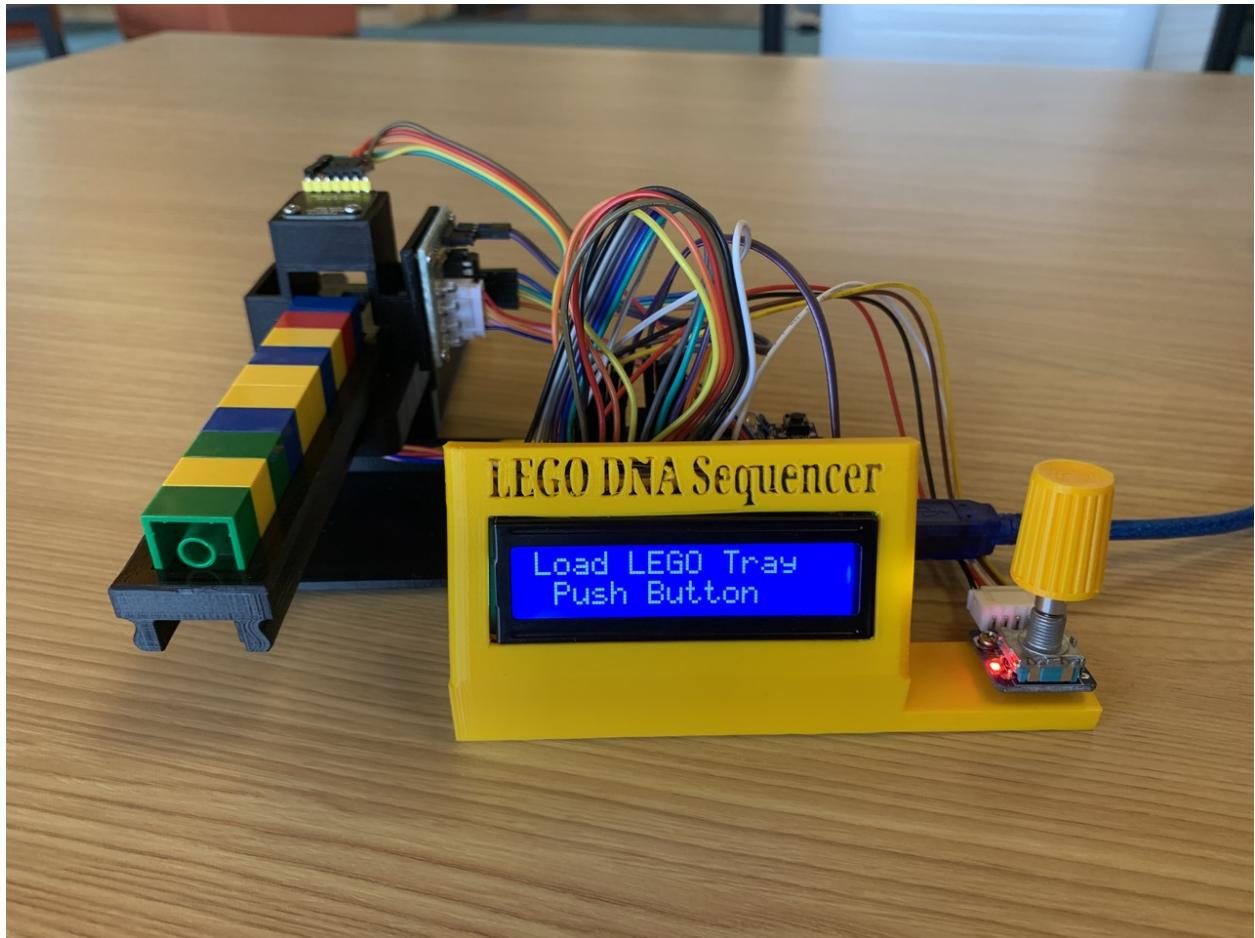
The LEGO DNA Sequencer is operated with a simple user interface. The UI includes an LCD display, a buzzer, and a rotary encoder / button which is much like a car radio knob.

## Starting the System

Power on the system by connecting the USB cable from the Arduino into a USB power adapter. There is no ON/OFF switch. When the system is plugged in it will beep three times and display the following screen.



Push the button and you will be ready to perform DNA sequencing.



To operate the sequencer you will need to assemble 10 of the LEGO 2x2 bricks into a genome for sequencing. The system has 6 built in genomes that it will recognize as shown in the following illustration.

# LEGO DNA Sequencer

**Sea Urchin**

CGATGACTAG



**White Shark**

TACGCTAGCT



**Sea Star**

GATCCGATGC



**Anchovy**

ACTGATCGAT



**Giant Kelp**

TAGCTAGCTA



**Pelican**

CAGTACCGATC



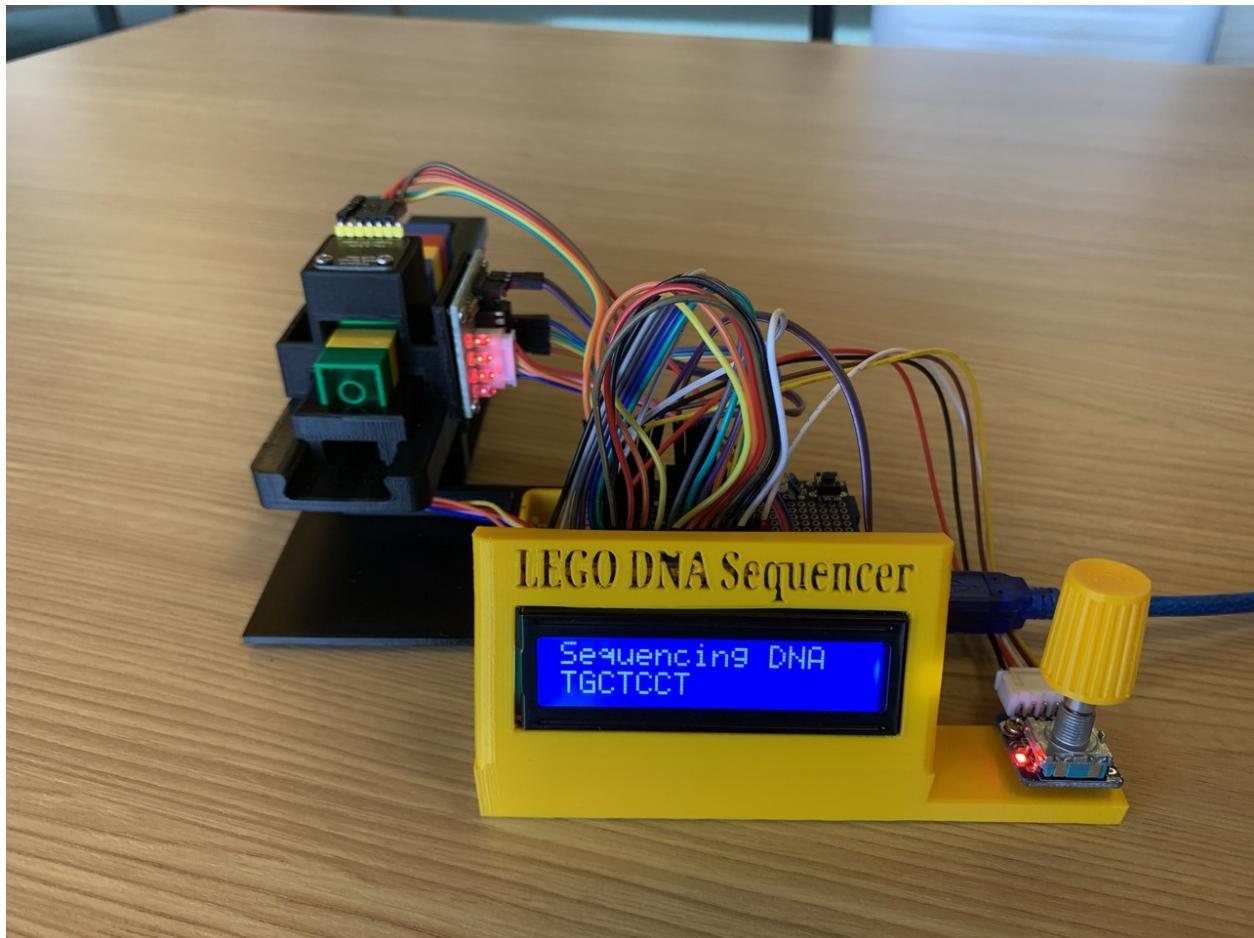
## Loading the LEGO Tray

When you have assembled a genome of 10 LEGO bricks, place them in the slot in the tray with the first brick in the sequence at the forward end of the tray. Note that the first brick will be inside the color sensor detection unit. The beginning of the second brick should align with the face of the color sensor.



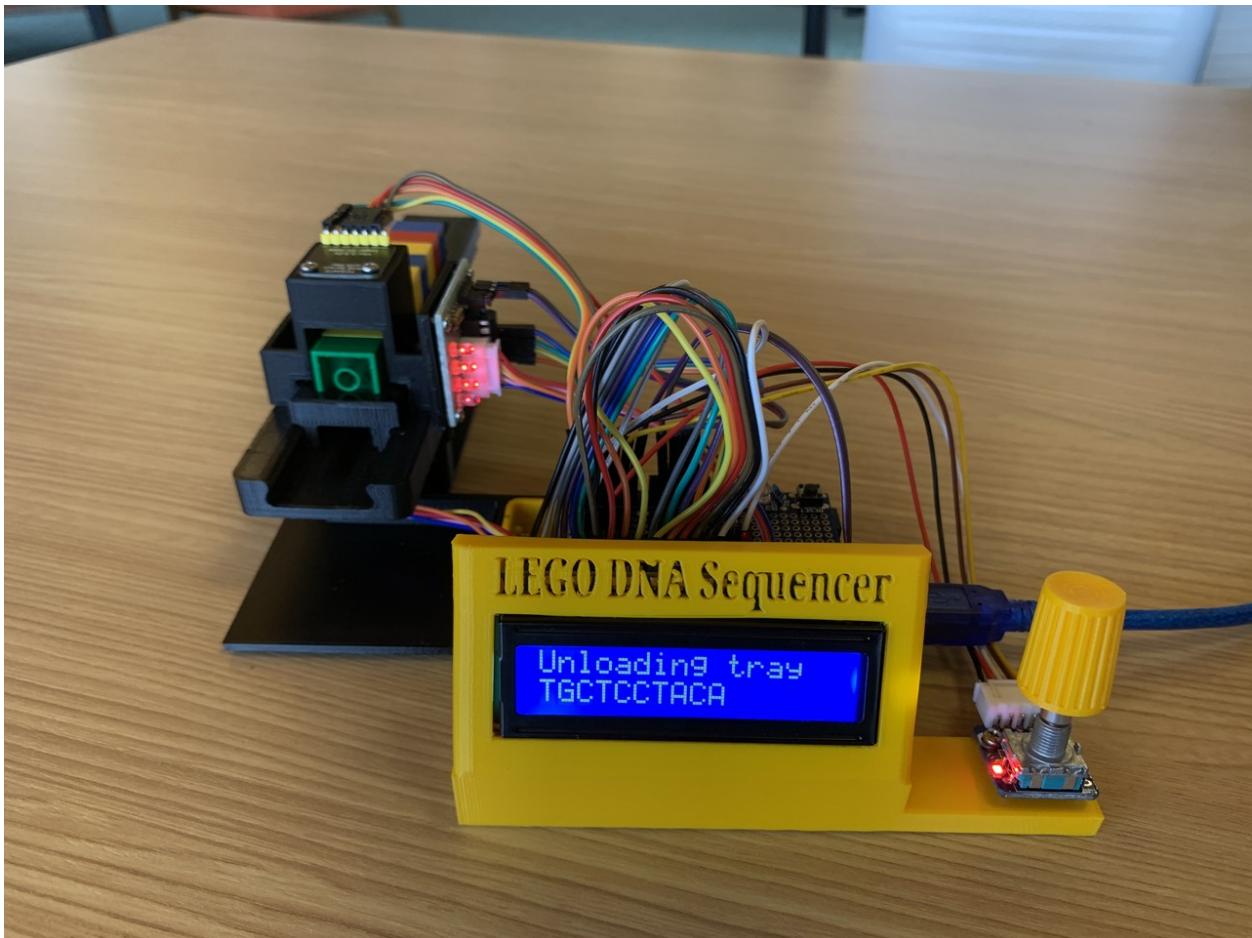
## Beginning the Sequencing

Push the button to begin sequencing. You will hear a buzzer click with each brick that is sequenced and the appropriate A, C, G, or T will be displayed.

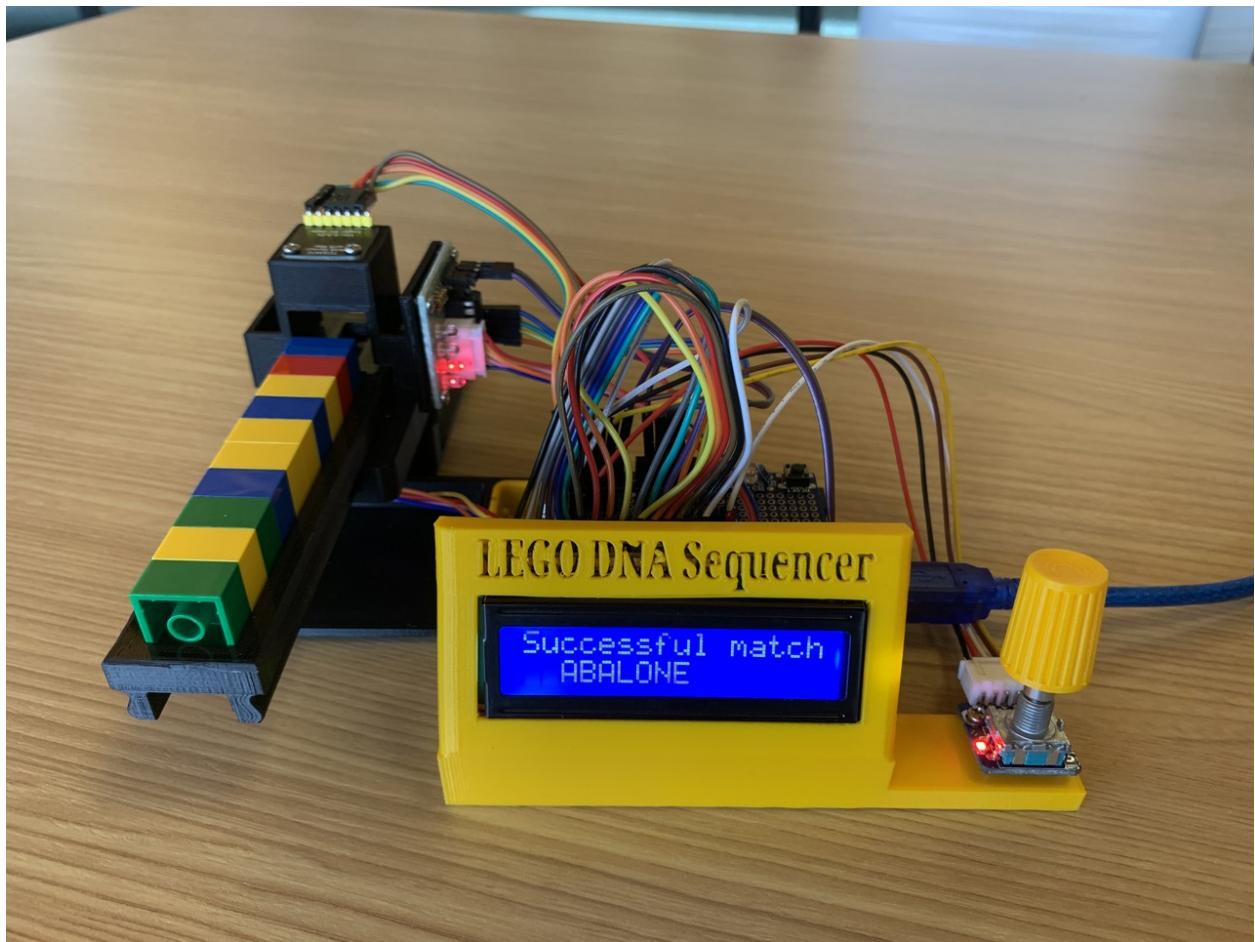


## Unloading the LEGO Tray

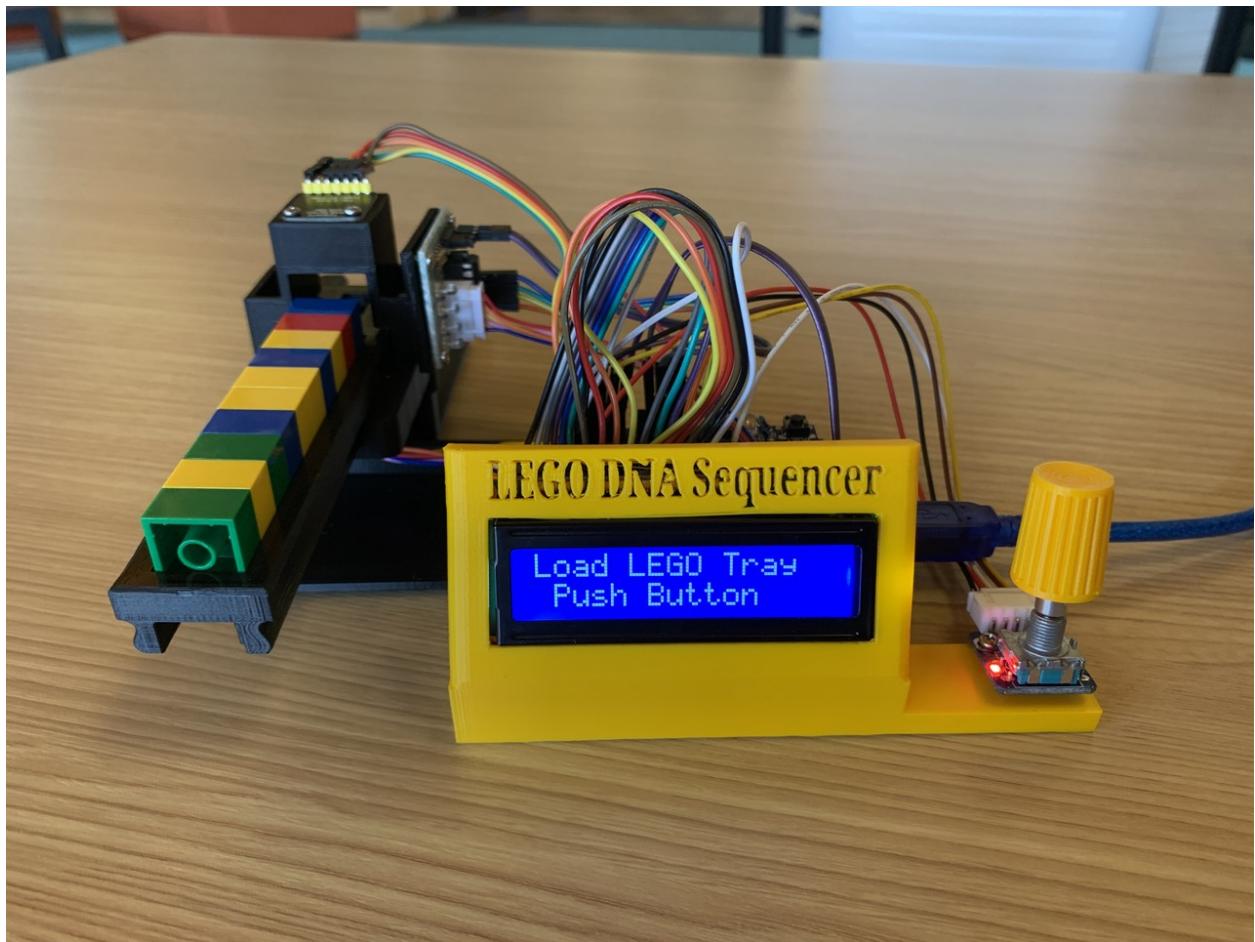
When all 10 of the bricks have been sequenced the LEGO tray will be unloaded, returning the tray to the initial position.



At that point you should see a “Successful match” and the name of the species that has been sequenced.

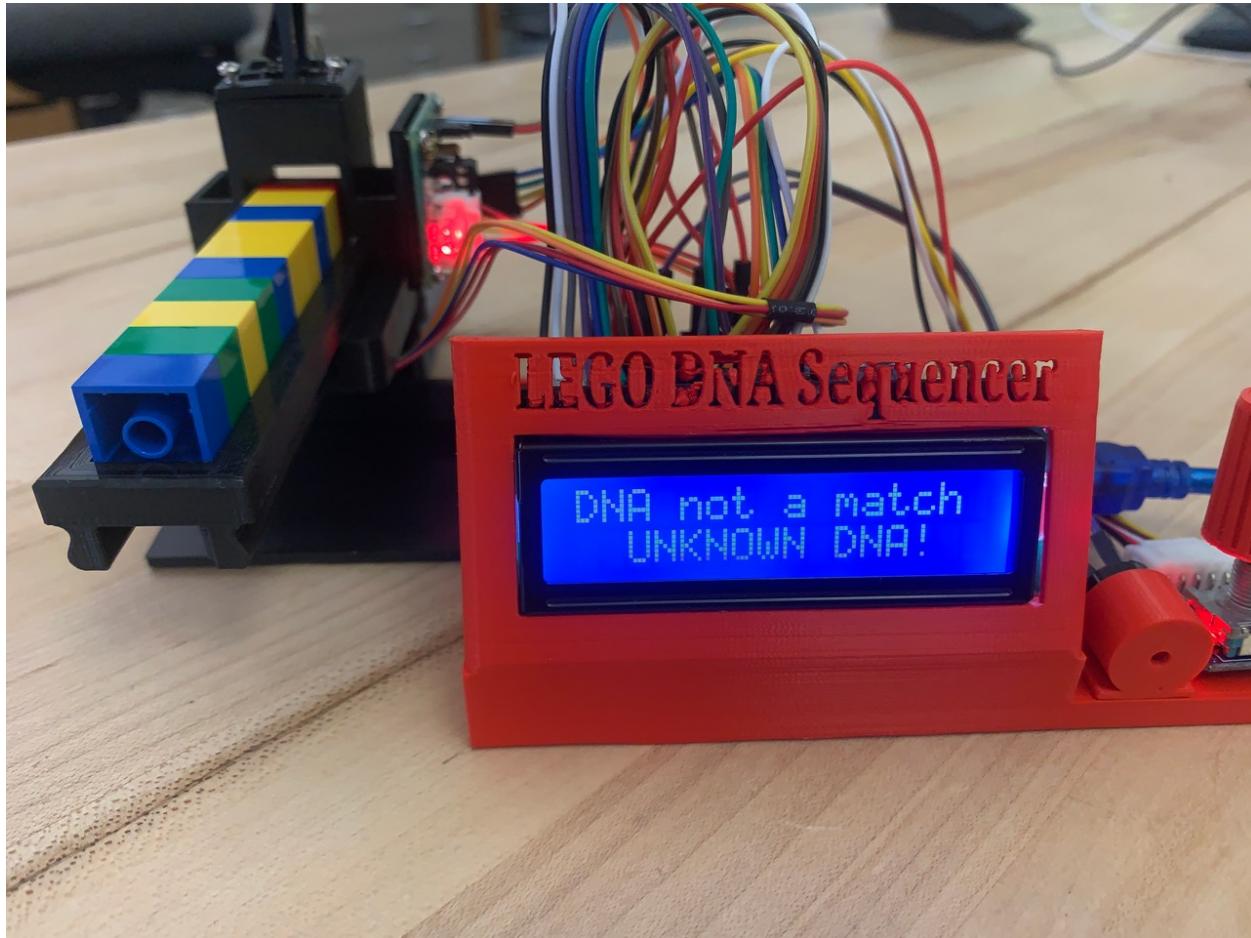


Pushing the button will ready the system to perform another sequencing operation.



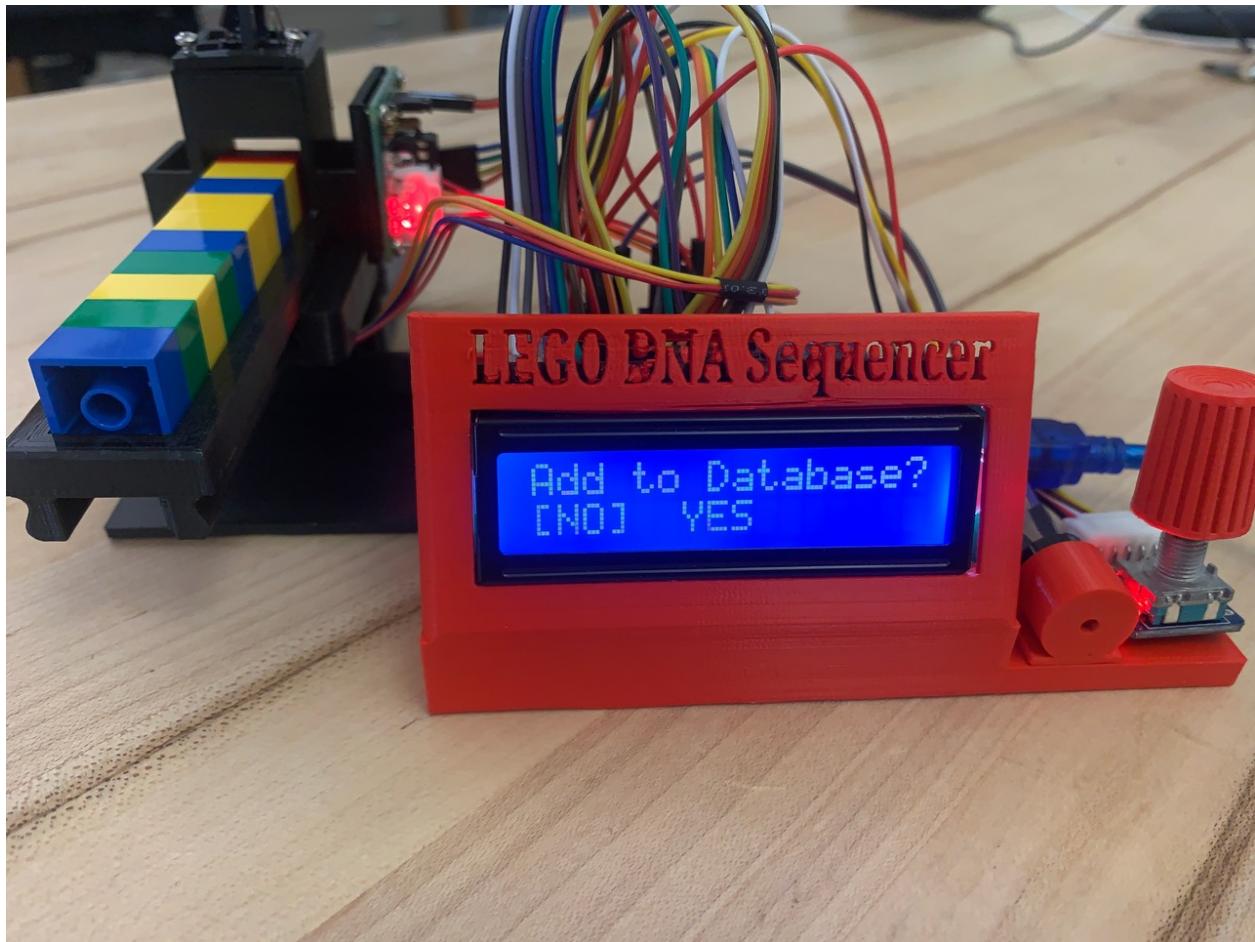
## UNKNOWN DNA

In the event that the bricks you have assembled do not match those of a known genome the system will display the following message.

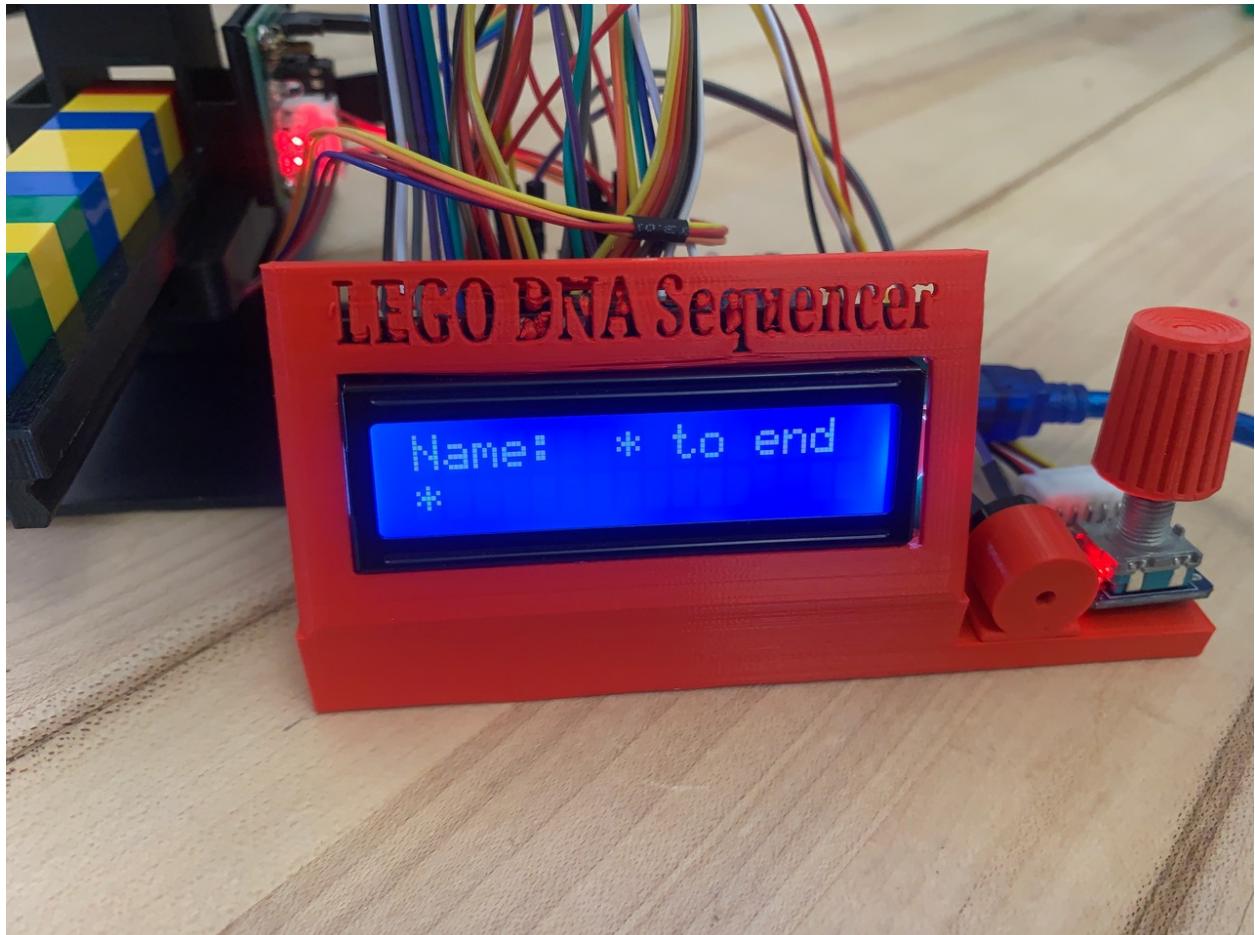


## Updating the Database with a new DNA

Push the button and you will be asked if you want to add the sequence to the database of known species genomes. Rotating the knob will move the selection back and forth between the choices of NO and YES. If you select NO, which is the default selection, the system will return to the state where it is ready to start another sequence operation.



If you selected YES to add the new sequence to the database, you will be prompted to enter a Name for the new genome. Rotating the knob will show you the characters that you can choose for the next letter of the name: A-Z, 0-9, and ‘‘.



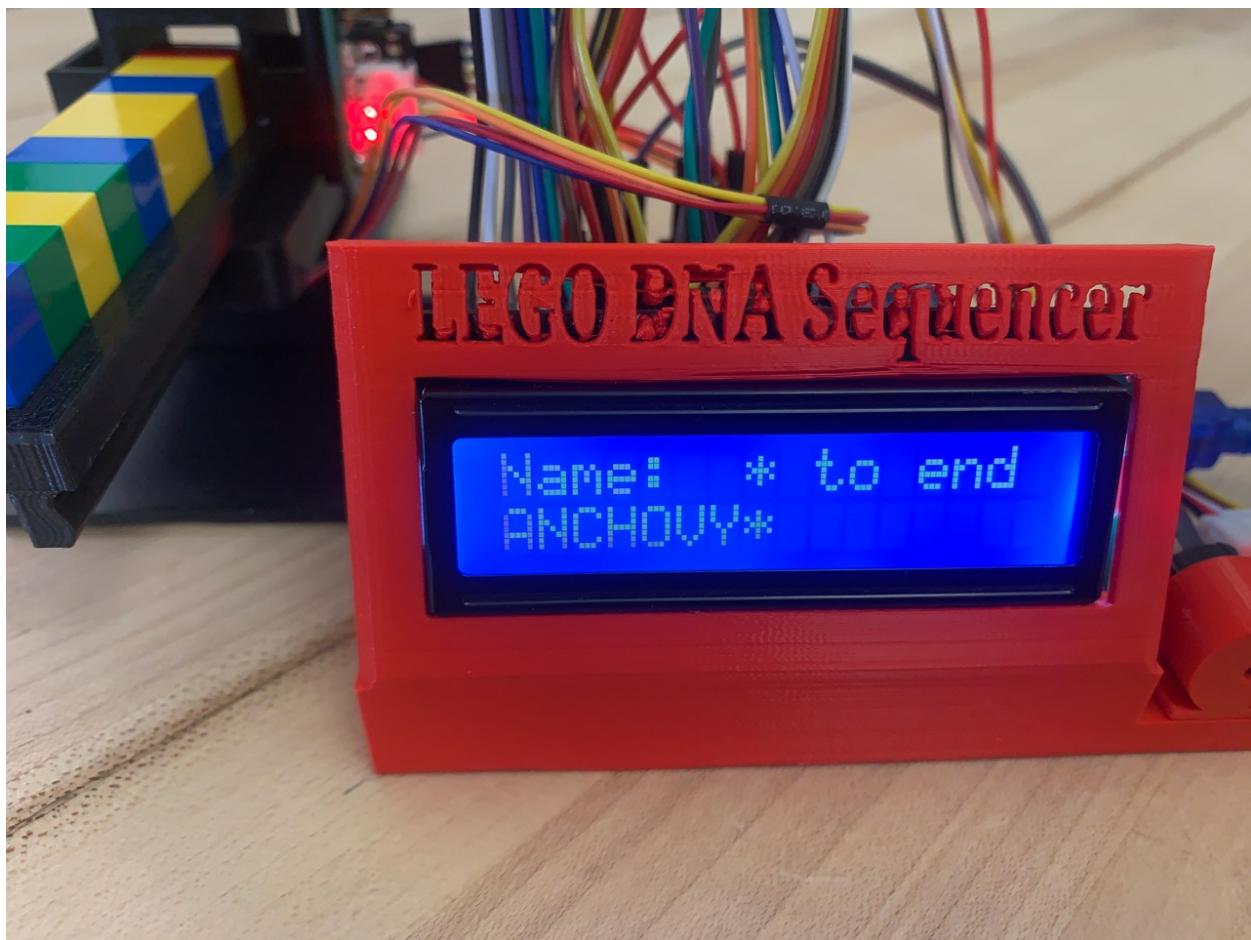
To select a character for the name, press the button and the display will advance for you to enter the next character.



If you wish to delete a previous character, select the '<' character and push the button.



When you have completed entering the name, select the '\*' character.



You will then be prompted NO or YES to accept the database entry.



You should then be able sequence the same tray of LEGO bricks and see that your new genome is successfully matched.



## Troubleshooting

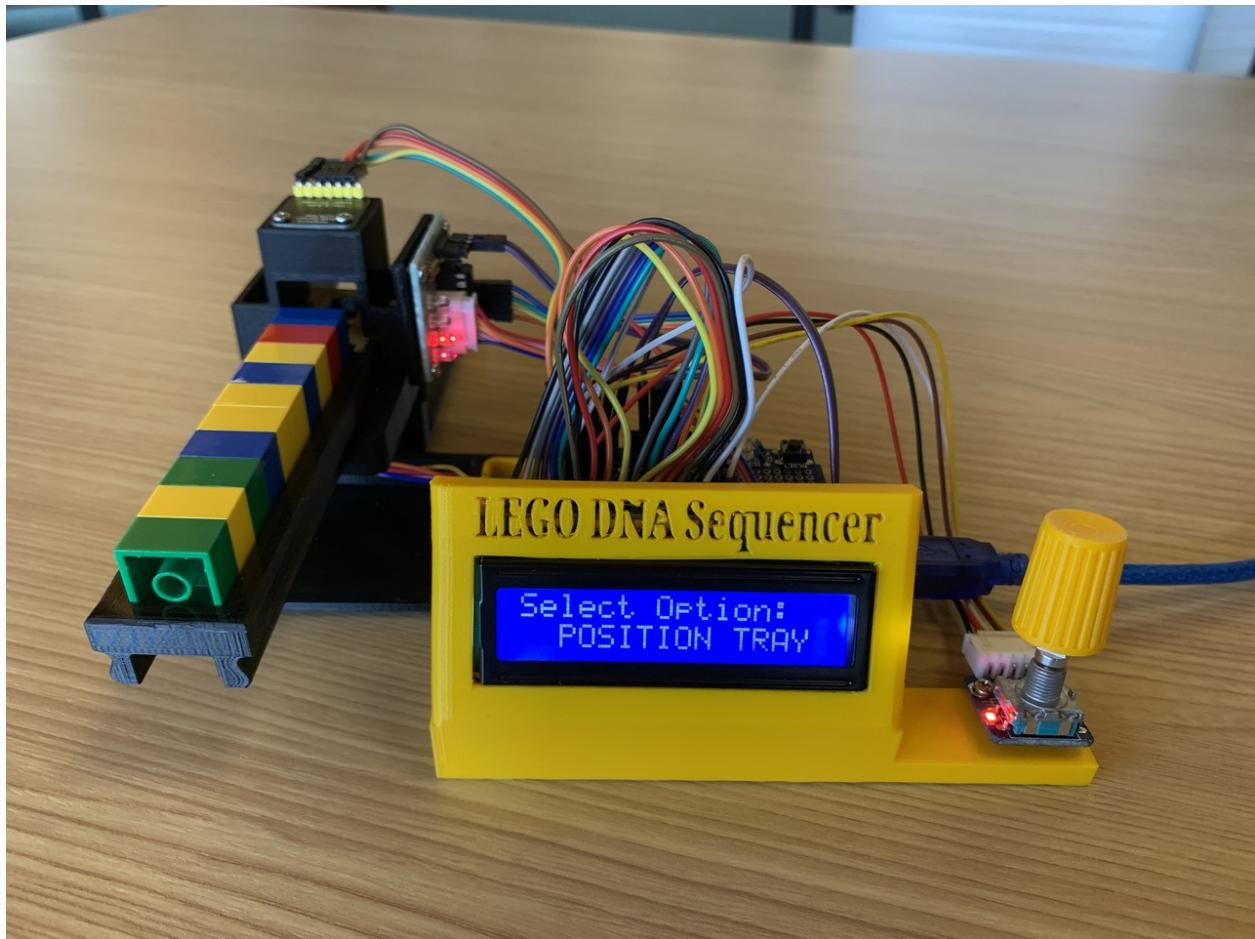
In the event that the sequencer is not correctly identifying a known genome sequence it will be necessary to make some adjustments to either the positioning of the LEGO tray and/or adjustments to the color channel threshold levels.

### Adjustment of the LEGO Tray Position

The “home” initial position of the LEGO tray can be manually adjusted with the maintenance User Interface. NOTE: DO NOT MANUALLY FORCE THE TRAY!

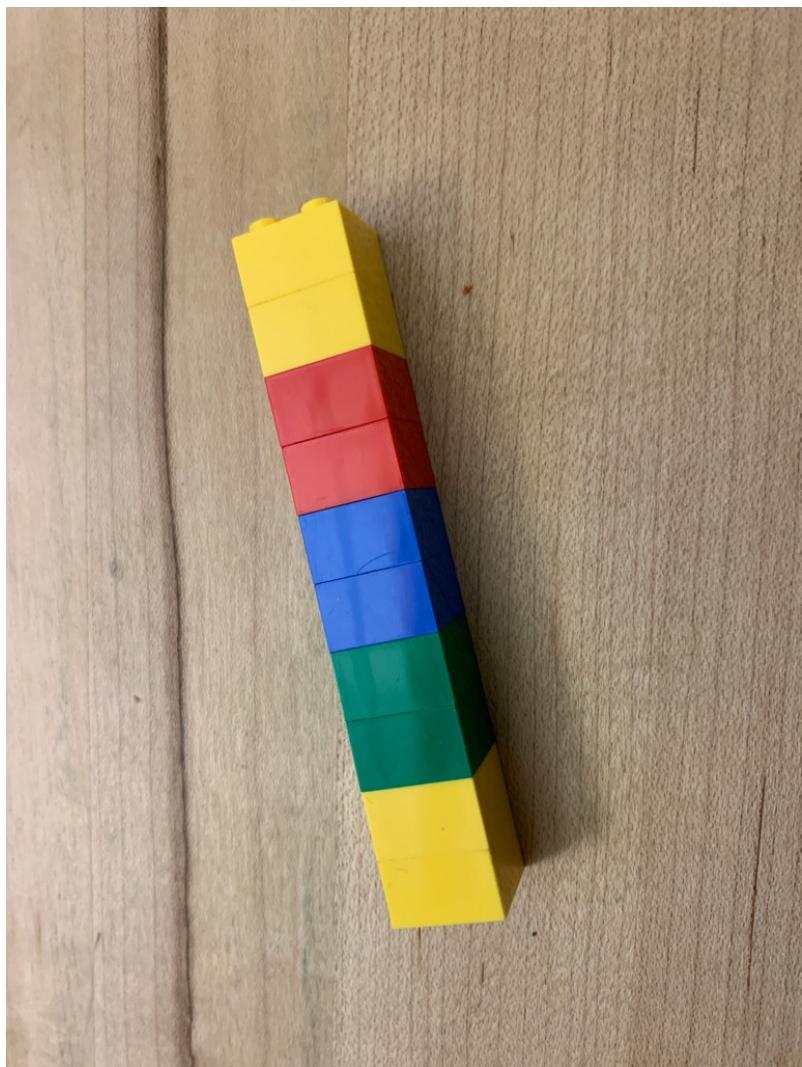
The maintenance User Interface is entered by rotating the knob when the system is in the state where it is ready to begin sequencing with the display showing, “Load LEGO Tray / Push Button”. Each click of the rotating knob will advance to another option. Select “Cancel” to exit from maintenance mode.

When you push the button to select “POSITION TRAY”, rotating the knob clockwise will advance the tray forward and rotating the knob counterclockwise will move the tray backward. Push the button to finish when you have correctly positioned the tray so that the face of the 2nd brick aligns with the face of the color sensor. At that point you should re-sequence and verify the results of your operation. If this fails



## Adjustments to the Color Channel Threshold Levels

The first step in adjusting the color channel threshold levels is to assemble and sequence the YYRRRBGGYY test bricks.



Sequencing this known order of bricks will enable the system to adjust the channel threshold levels used to identify the Red, Green, Blue, and Yellow colors detected by the color sensor.

## Additional Operations

The Additional Operations are accessed by rotating the knob when the system is ready to begin sequencing with the display showing, “Load LEGO Tray / Push Button”.

### CANCEL

Exit from additional operations and return to sequencing LEGO operations.

### UNLOAD TRAY

The LEGO tray will be backed out, removing it from the system

### LOAD TRAY

The LEGO tray should be inserted until it reaches the gear. This will position the tray about 1” from the face of the color sensor. Gently advance the tray forward when you push the “LOAD TRAY”. The tray should automatically move forward to the position where it should be ready to start sequencing.

### POSITION TRAY

Rotating the knob clockwise will advance the tray forward and counterclockwise in reverse direction. Pushing the button will exit positioning the tray.

### ZERO NEW DNA

This operation will remove any genomes that were added to the database. Note that there is limited storage for additional genomes.

### BUZZER OFF

This will turn OFF the buzzer which is used to announce operations and identify progress during sequencing.

## **BUZZER ON**

This will turn OFF the buzzer which is used to announce operations and identify progress during sequencing.

## **ADVANCED**

This selection provides access to system operations.

### **Advanced Operations**

The Advanced Operations include selections that adjust the color channel threshold levels, auto positioning the LEGO tray, displaying the LCD output on an external monitor, and rebooting the system.

## **CANCEL**

Exit from advanced operations and return to sequencing LEGO operations.

## **CLEAR CHANNEL**

This selection displays the current CLEAR channel threshold level and allows you to edit the value.

## **RED CHANNEL**

This selection displays the current RED channel threshold level and allows you to edit the value.

## **BLUE CHANNEL**

This selection displays the current BLUE channel threshold level and allows you to edit the value.

## AUTO CHANNEL

This selection requires that you have scanned the LEGO test bricks YYRRBBGGYY. It will then display the current channel threshold values for CLEAR, RED, and BLUE. It will show the new recommended values and allow you to update the system with those values.

## AUTO POSITION

The auto positioning is also accomplished using the LEGO test bricks YYRRBBGGYY. You should begin with the POSITION TRAY operation to get the tray near to the desired start position. This operation advances the tray to the two RED bricks and then backs up to the estimated start position.

## REMOTE LCD ON

This selection enables the system serial output to show the contents of the LCD. It requires that the RemoteLCD.py program is operating on the laptop computer used to display the large font output. See the next chapter on [Remote LCD](#).

## REMOTE LCD OFF

This selection disables the system serial output to show the contents of the LCD.

## REBOOT

This will immediately Reboot the system and return to the startup screen.

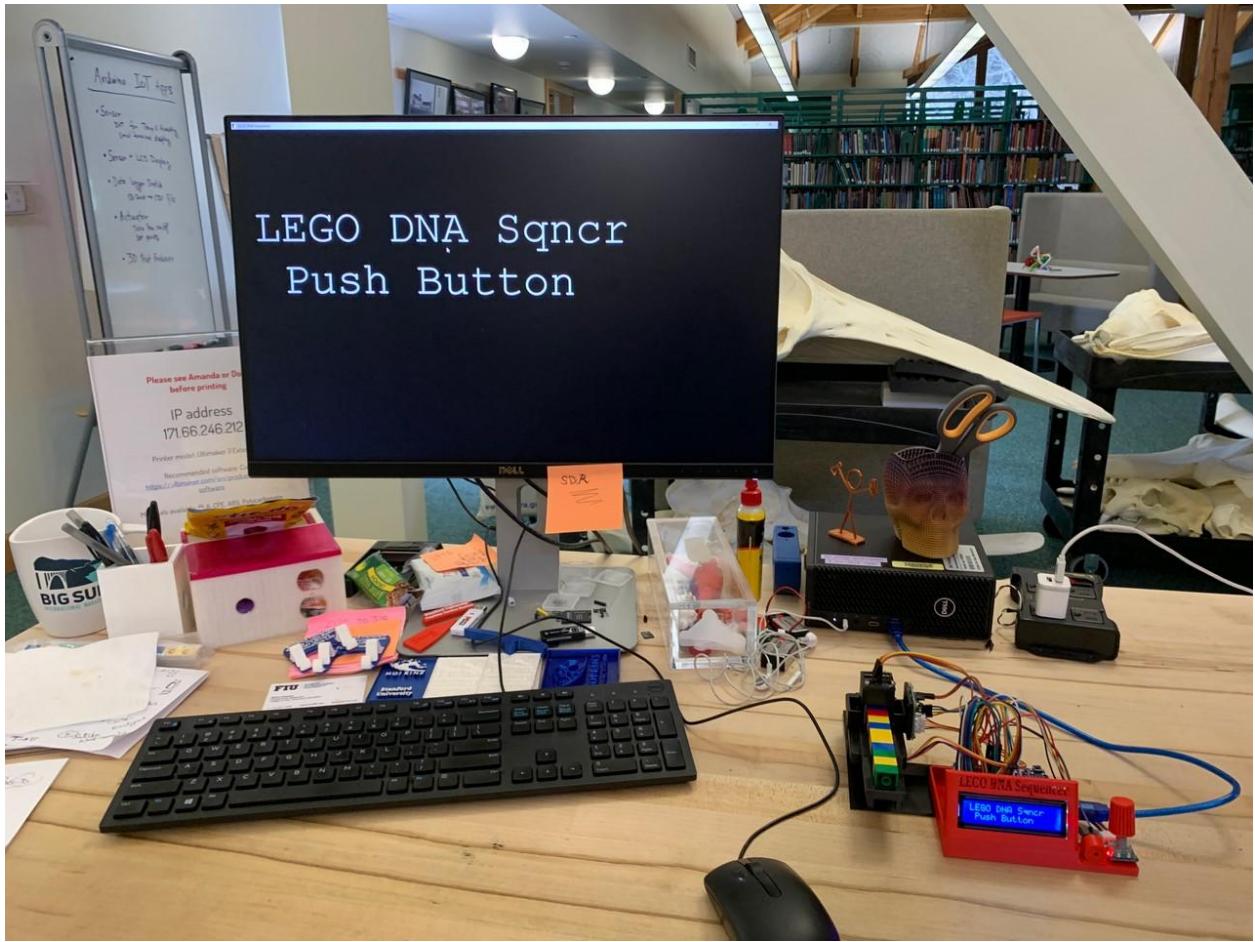
## Remote LCD

The Remote LCD is an optional companion Python program which displays the LCD contents of the LEGO DNA Sequencer on a big screen for a larger viewing audience.

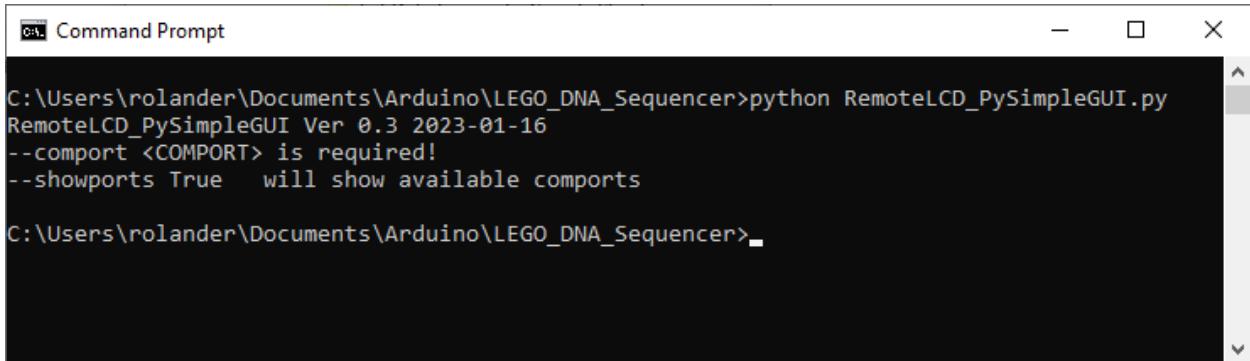
There are two Python versions of the Remote LCD program which require two different GUI libraries:

- PySimpleGUI
- Tkinter

## RemoteLCD\_PySimpleGUI



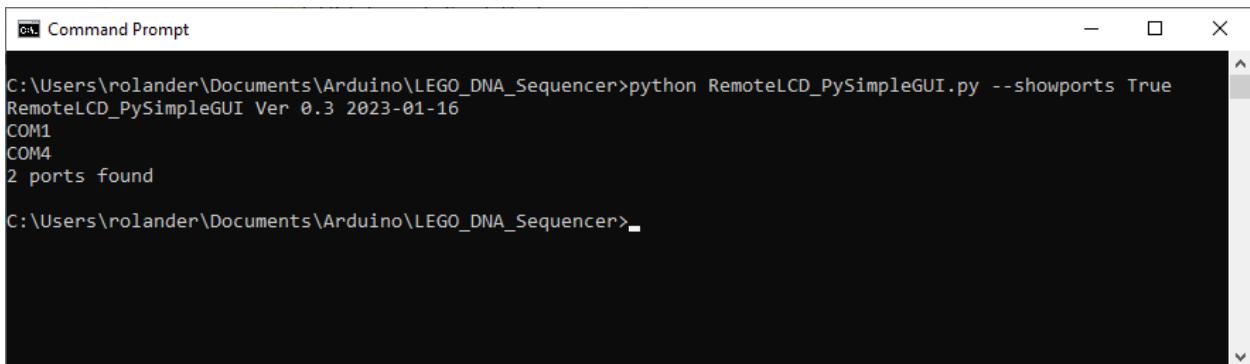
The application is launched with the following command on a Windows PC:



```
C:\Users\rolander\Documents\Arduino\LEGO_DNA_Sequencer>python RemoteLCD_PySimpleGUI.py
RemoteLCD_PySimpleGUI Ver 0.3 2023-01-16
--comport <COMPORT> is required!
--showports True    will show available comports

C:\Users\rolander\Documents\Arduino\LEGO_DNA_Sequencer>
```

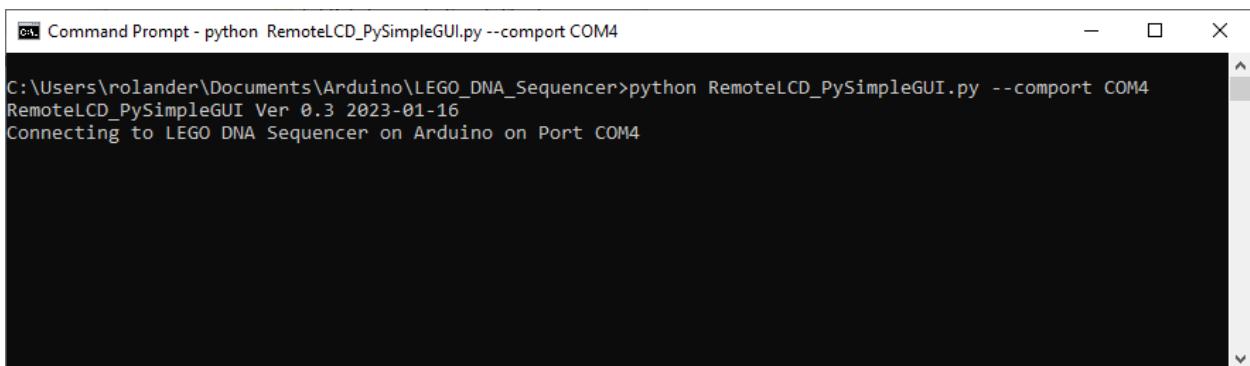
The available comports can be displayed using the following command:



```
C:\Users\rolander\Documents\Arduino\LEGO_DNA_Sequencer>python RemoteLCD_PySimpleGUI.py --showports True
RemoteLCD_PySimpleGUI Ver 0.3 2023-01-16
COM1
COM4
2 ports found

C:\Users\rolander\Documents\Arduino\LEGO_DNA_Sequencer>
```

The following command will begin operation of the Remote LCD display:



```
C:\Users\rolander\Documents\Arduino\LEGO_DNA_Sequencer>python RemoteLCD_PySimpleGUI.py --comport COM4
RemoteLCD_PySimpleGUI Ver 0.3 2023-01-16
Connecting to LEGO DNA Sequencer on Arduino on Port COM4
```

The Welcome screen will be displayed and the LEGO DNA Sequencer will reboot, showing its startup screen.

From that point on the contents of the LCD screen on the LEGO DNA Sequencer will be displayed on your computer screen.

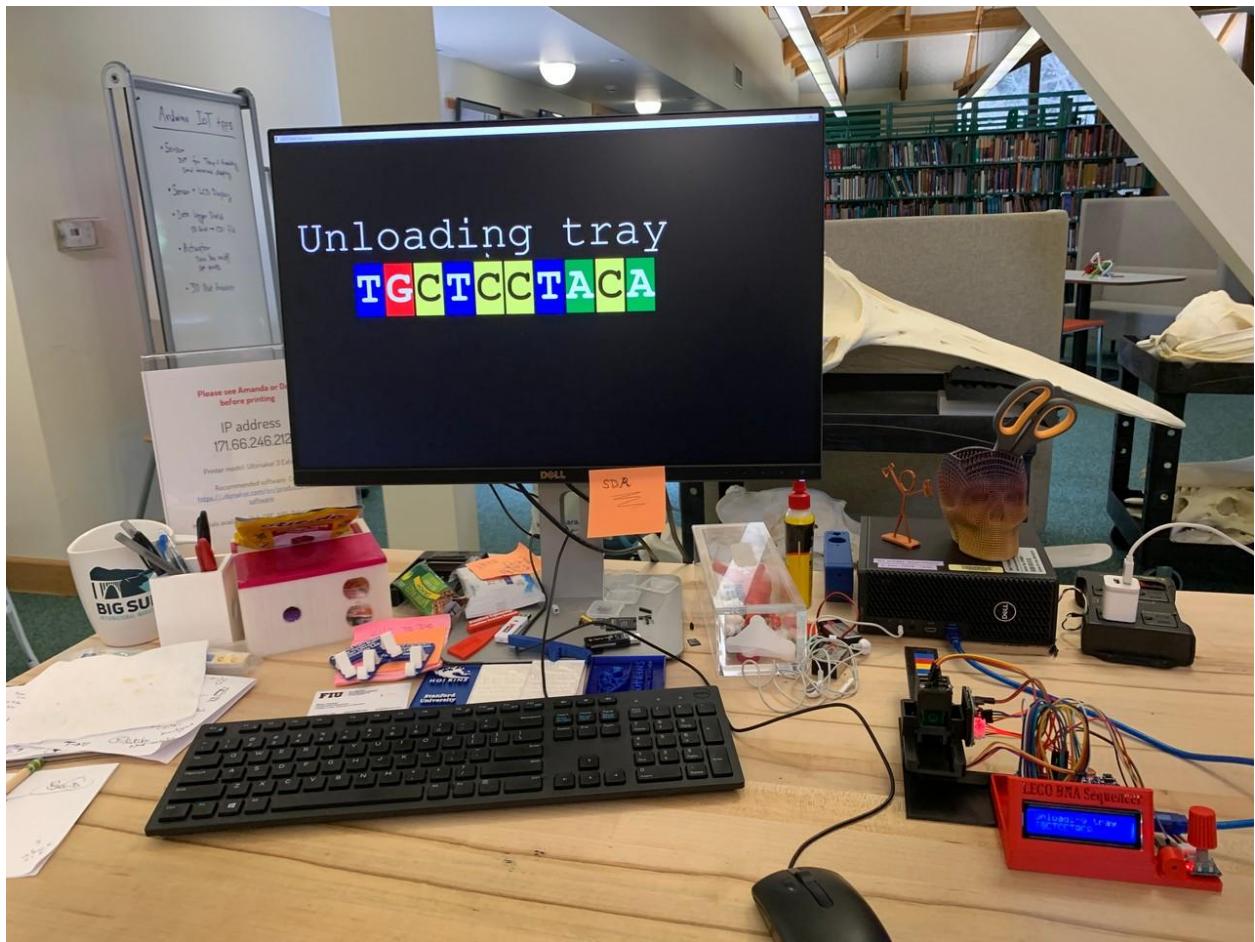
To terminate the RemoteLCD program enter the following keys:

Alt - F4

The the following screens show the RemoteLCD output:









## Installation for Remote LCD for PySimpleGUI

The steps to run the Remote LCD Python program on your laptop computer are as follows:

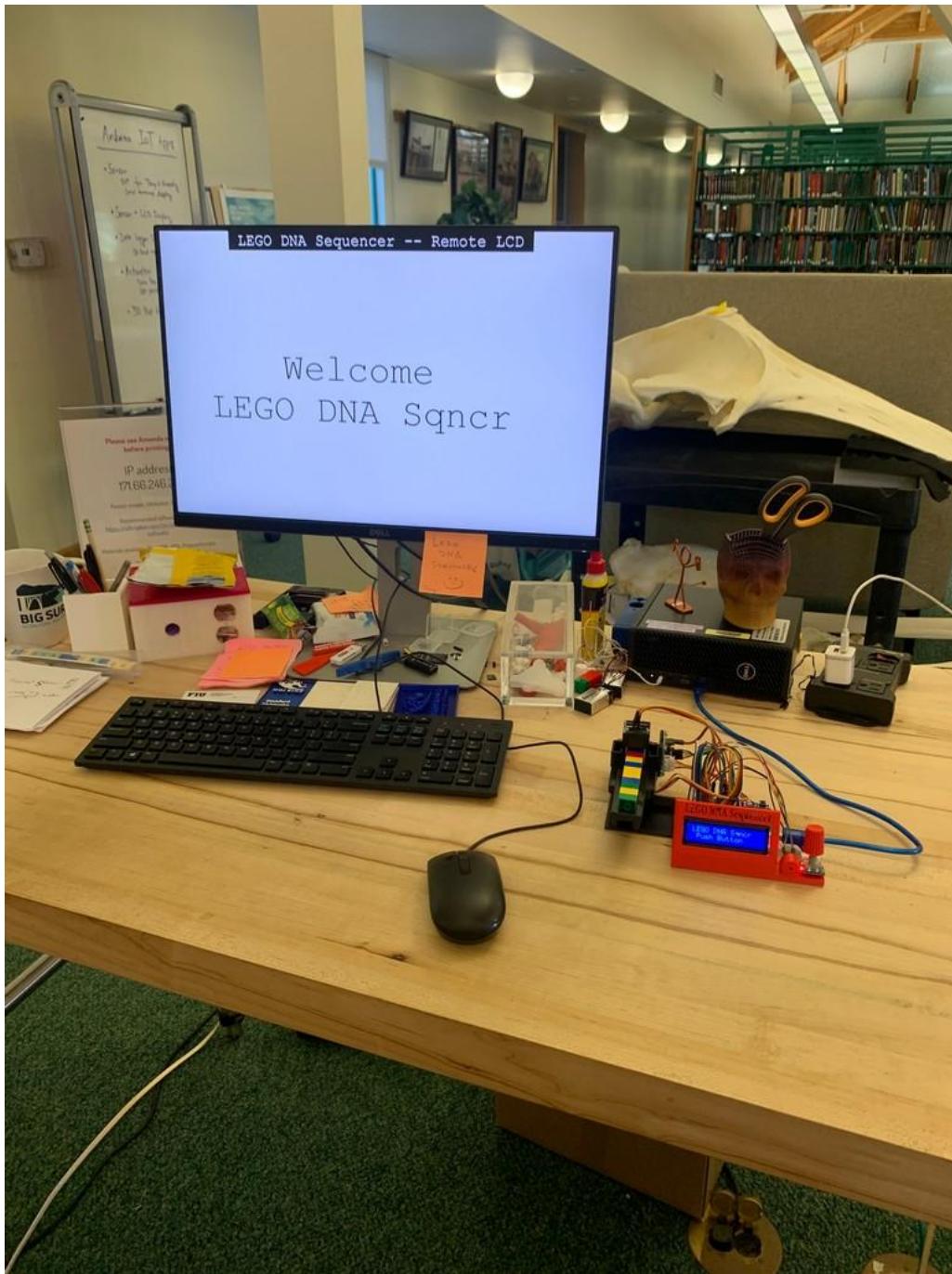
Windows

- [Install python](#)
- [Install pip](#)
- [Install SimpleGUI](#)
- [Install pyserial](#)

Mac

- [Install python](#)
- [Install pip](#)
- [Install PySimpleGUI](#)
- [Install pyserial](#)

# RemoteLCD\_tkinter



The application is launched with the following command on a Windows PC:

---

```
C:\ Command Prompt

C:\Users\rolander\Documents\Arduino\LEGO_DNA_Sequencer>python RemoteLCD.py
RemoteLCD Ver 0.1 2023-01-10
--comport <COMPORT> is required!
--showports True    will show available comports
```

The available comports can be displayed using the following command:

---

```
C:\ Command Prompt

C:\Users\rolander\Documents\Arduino\LEGO_DNA_Sequencer>python RemoteLCD.py --showports True
RemoteLCD Ver 0.1 2023-01-10
COM1
COM4
2 ports found
```

The following command will begin operation of the Remote LCD display:

---

```
C:\ Command Prompt

C:\Users\rolander\Documents\Arduino\LEGO_DNA_Sequencer>python RemoteLCD.py --comport COM4
RemoteLCD Ver 0.1 2023-01-10
Connecting to LEGO DNA Sequencer on Arduino on Port COM4
```

The Welcome screen will be displayed and the LEGO DNA Sequencer will reboot, showing its startup screen.

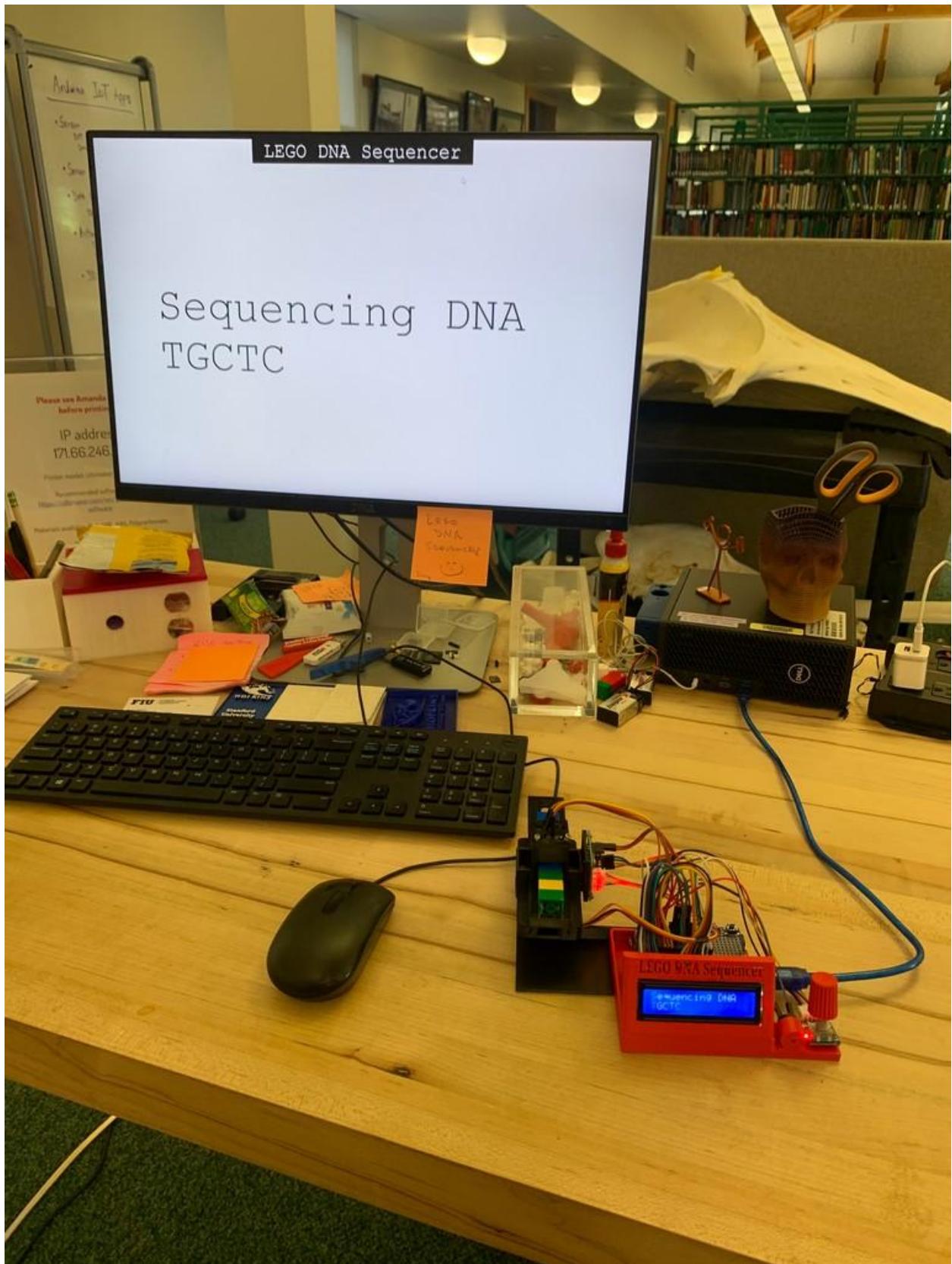
From that point on the contents of the LCD screen on the LEGO DNA Sequencer will be displayed on your computer screen.

To terminate the RemoteLCD program enter the following keys:

Alt - F4

The the following screens show the RemoteLCD output:









## Installation for Remote LCD for tkinter

The steps to run the Remote LCD Python program on your laptop computer are as follows:

Windows

- [Install python](#)
- [Install pip](#)
- [Install tk](#)
- [Install pyserial](#)

Mac

- [Install python](#)
- [Install pip](#)
- [Install tk](#)
- [Install pyserial](#)

# DIY: Build Your Own LEGO DNA Sequencer

A primary objective of this project has been to provide all of the documentation required to independently build your own LEGO DNA Sequencer. To that end all of the components of the system are open source.

The DIY elements include:

- Operators Manual for the end users
- Electronics assembly details with:
  - Parts list
  - Breadboard wiring of components
- STL files for all 3D printed parts
- Assembly instructions for the 3D printed parts and electronics
- Software source code and instructions to upload code to Arduino
- System and unit testing and troubleshooting

## The LEGO DNA Sequencer License

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[License](#)

You are free to:

- Share — copy and redistribute the material in any medium or format
- Adapt — remix, transform, and build upon the material for any purpose, even commercially.

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# Electronics

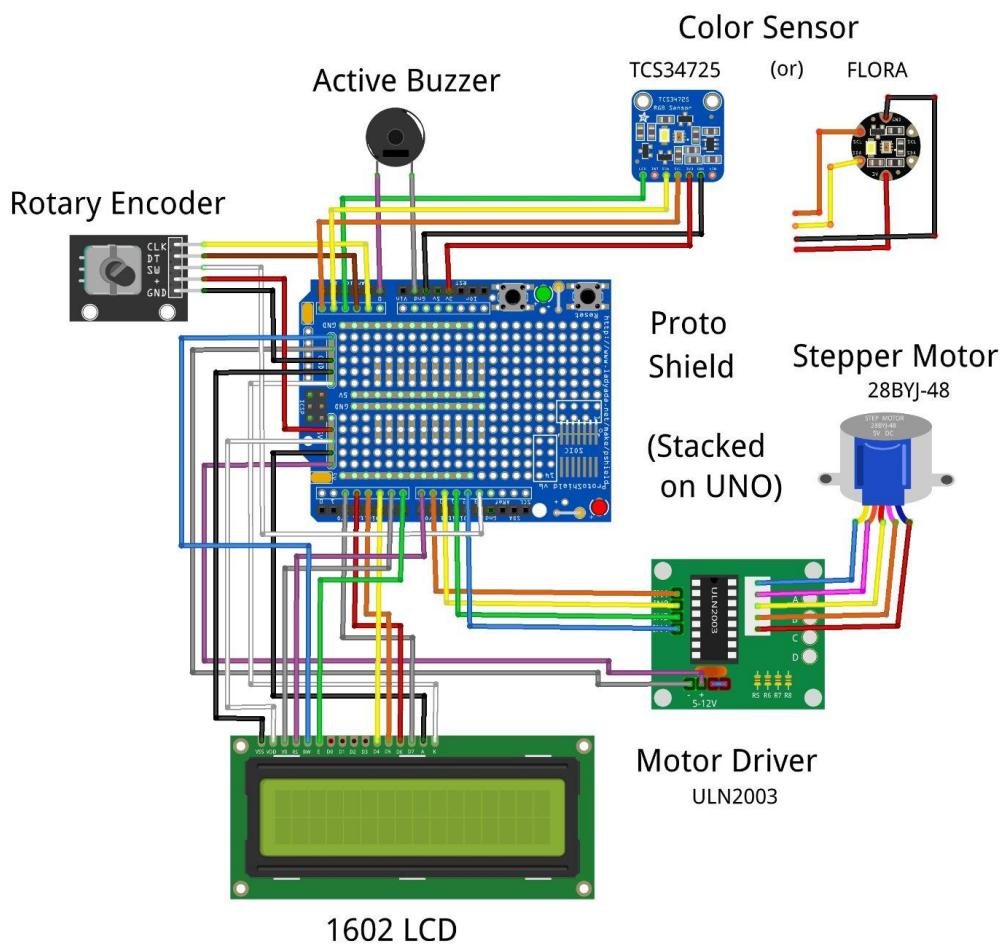
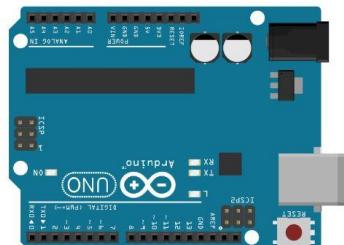
The LEGO DNA Sequencer electronics is controlled by an Arduino UNO microcontroller.

To perform the wiring it is recommended to use the Fritzing application to view the LEGO DNA Sequencer Breadboard which can be zoomed as needed to see the details of the wiring. The newer versions of Fritzing require a nominal fee (about \$10 US) for the download/installation.

# LEGO DNA Sequencer

## Breadboard

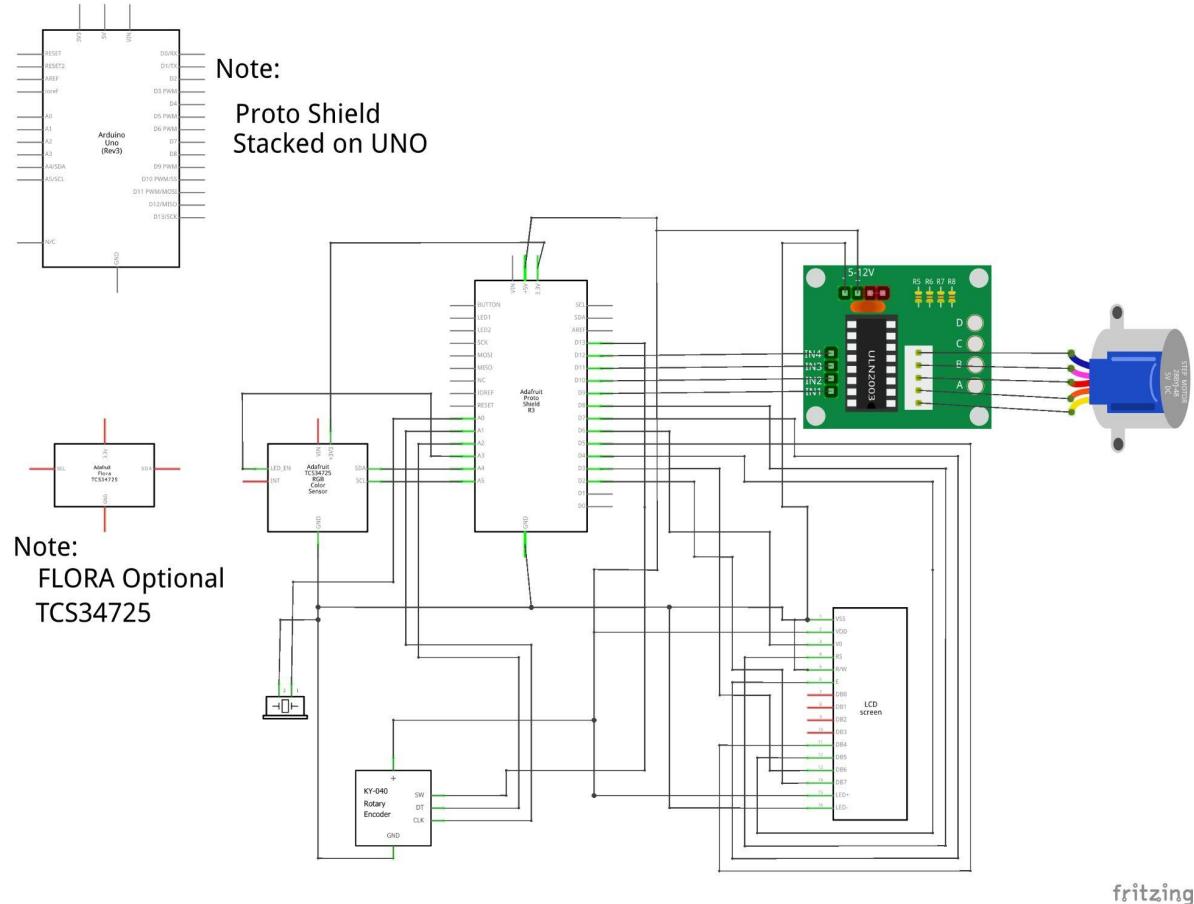
Arduino UNO



fritzing

# LEGO DNA Sequencer

## Schematic

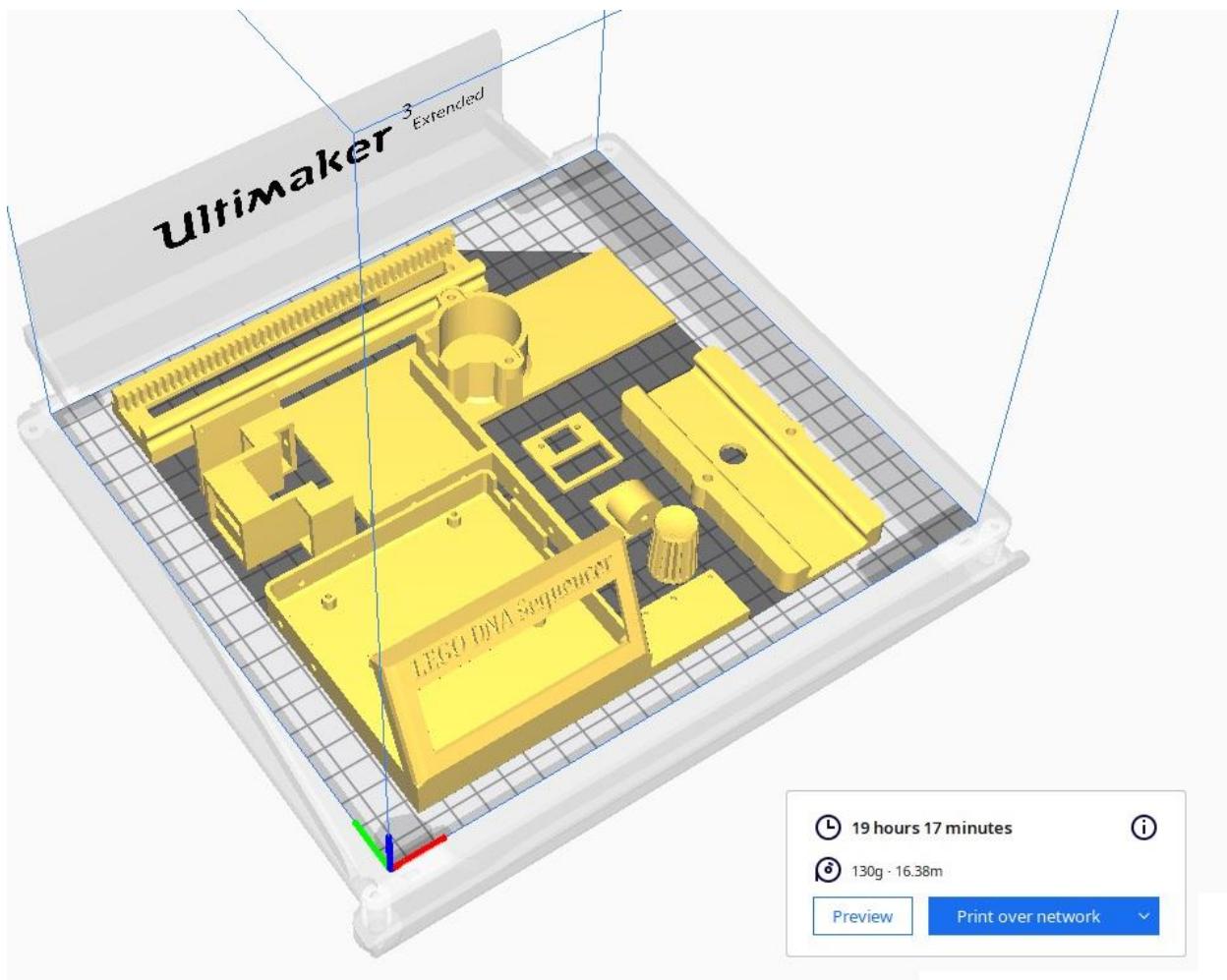


## 3D Printed Parts

There are a total of 8 parts to be printed.



The 3D printing can be done in a single printing process, or individually.

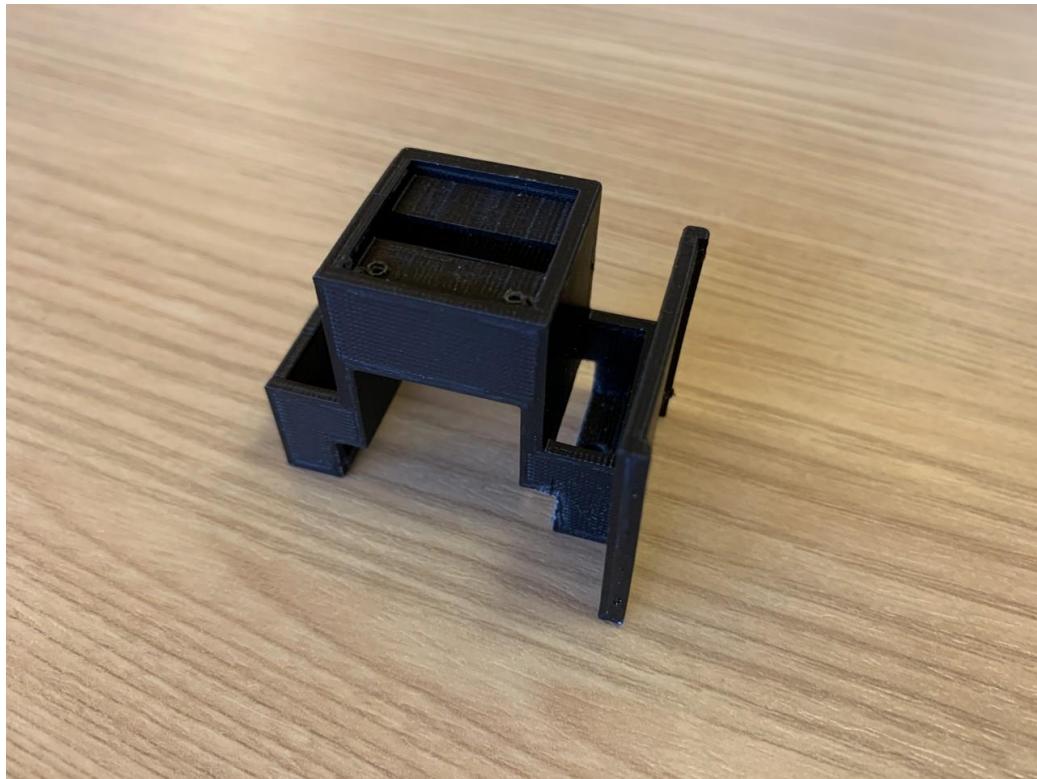


## Arduino and LCD Case



[STL File](#)

## Color Sensor and Motor Drive Mount



[STL File](#)

## Gear



[STL File](#)

## LEGO Tray



[STL File](#)

## Rotary Encoder Knob



[STL File](#)

## Stepper Motor Mount



[STL File](#)

## Tray Holder and Gear Mount



[STL File](#)

## Buzzer Mount



[STL File](#)

Parts Remixed from [Thingiverse.com](https://www.thingiverse.com)

[Arduino Case with LCD display 1602](#)

[28byj stackable linear slide](#)

[Rotary Encoder Knob \(16 x 21.5mm, 6mm flattened shaft\)](#)

## License

[Licensed under the Creative Commons - Attribution - Non-Commercial](#)

## Parts List

The parts required to assemble the LEGO DNA Sequencer include:

### Arduino Advanced Starter Kit

The easiest way to get the parts for the LEGO DNA Sequencer is to use one of the Arduino Advanced Starter Kits. There are several kits available which have all of the electronic parts with the only exception of the TCS34725 Color Sensor.

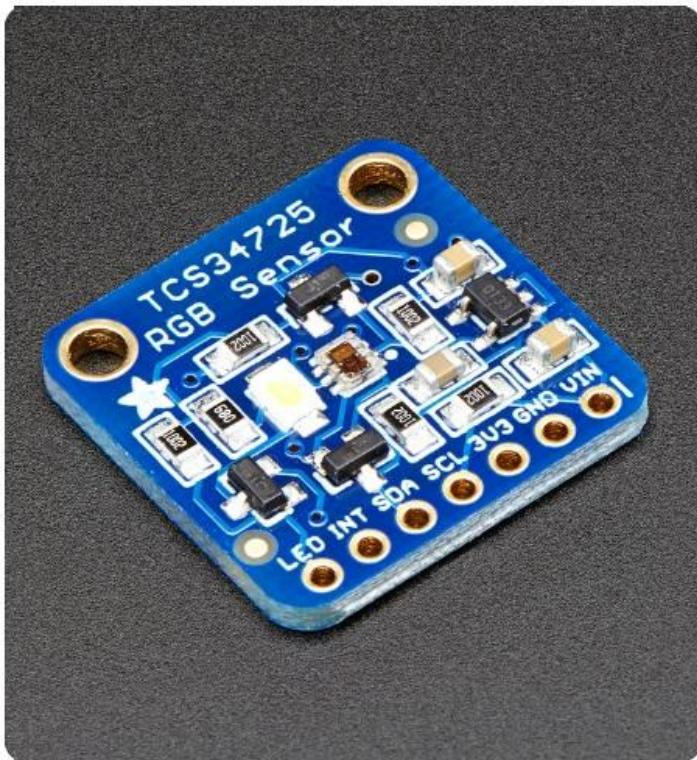
[ELEGOO Upgraded UNO R3 Project Most Complete Starter Kit w/Tutorial Compatible with Arduino IDE \(63 Items\) V2.0](#)



Quick look

\$44<sup>99</sup> prime

## TCS34725 – RGB Color Sensor with IR filter and White LED



RGB Color Sensor with  
IR filter and White LED  
- TCS34725

Product ID: 1334

**\$7.95**

Discontinued

You can grab the Adafruit APDS9960 Proximity,  
Light, RGB, and Gesture Sensor - STEMMA QT /  
Qwiic instead!

---

[Description](#)

[Technical Details](#)

## Hardware for the Assembly

### Sheet Metal Screws

(2) #6  $\frac{3}{4}$ "

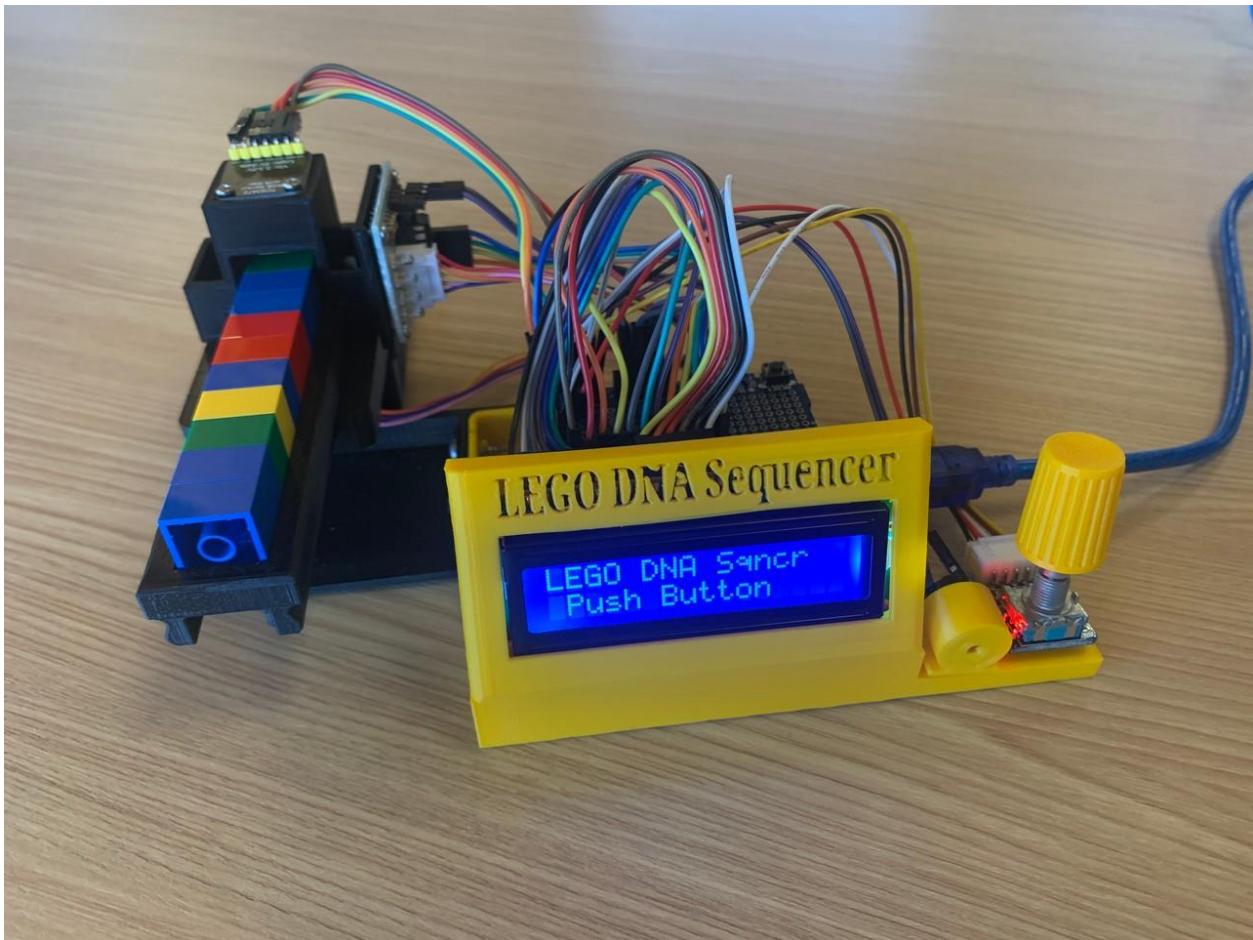
(3) #6  $\frac{1}{2}$ "

(16) #4  $\frac{1}{4}$ "

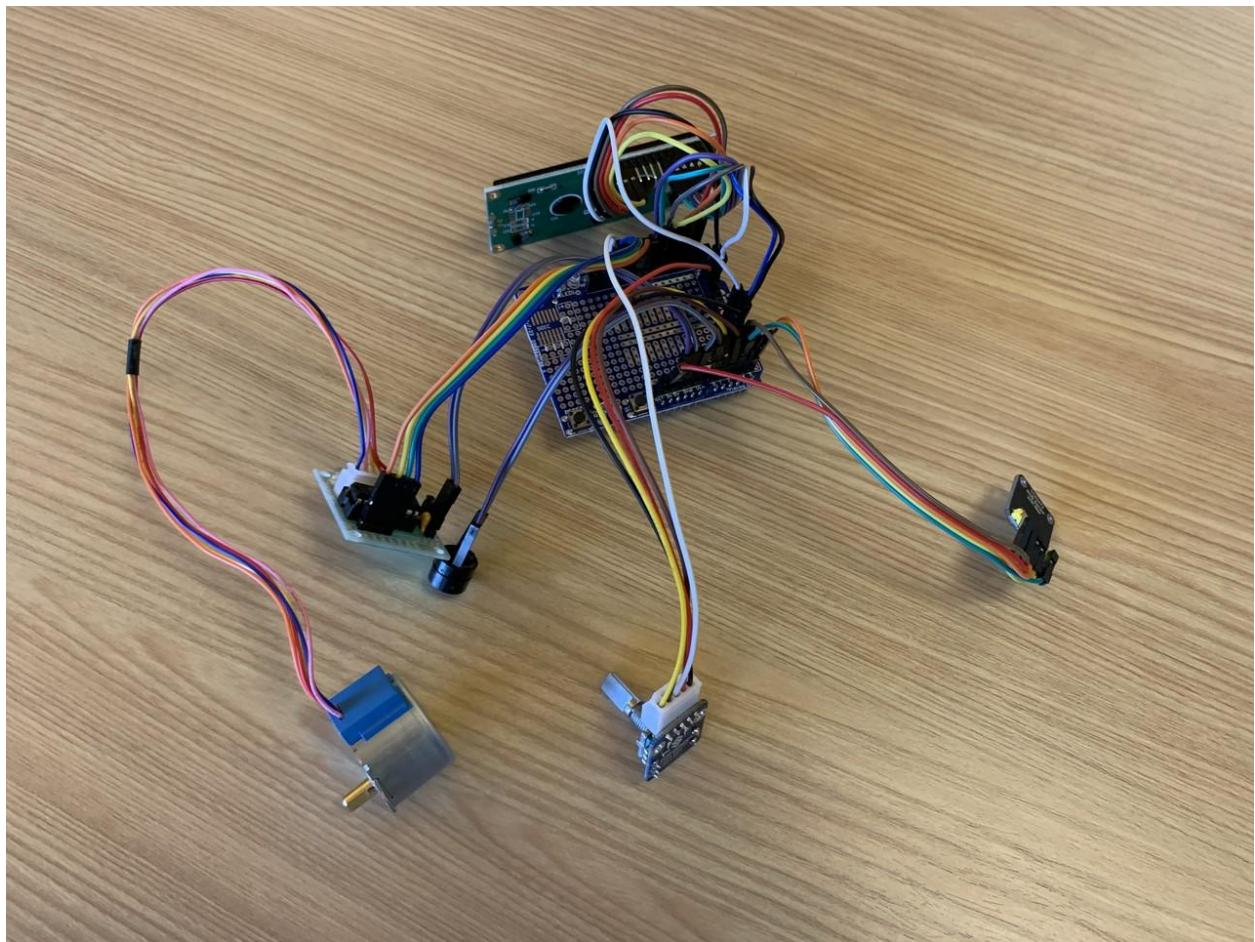


## Assembly and Construction Step Details

The steps in building a DIY LEGO DNA Sequencer includes the following, printing



Assemble the electronics using the [LEGO DNA Sequencer Breadboard](#).

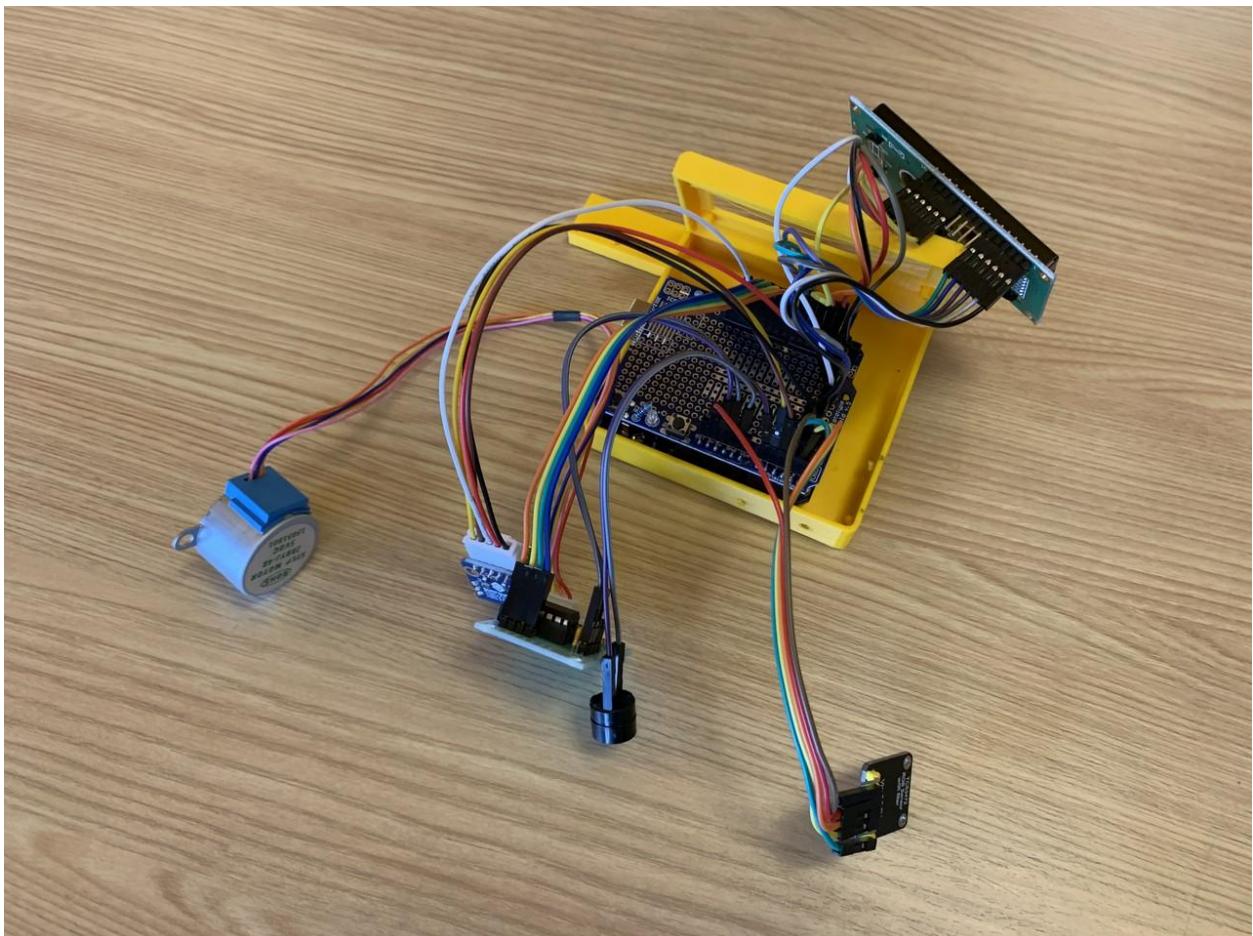


## Arduino and LCD Case

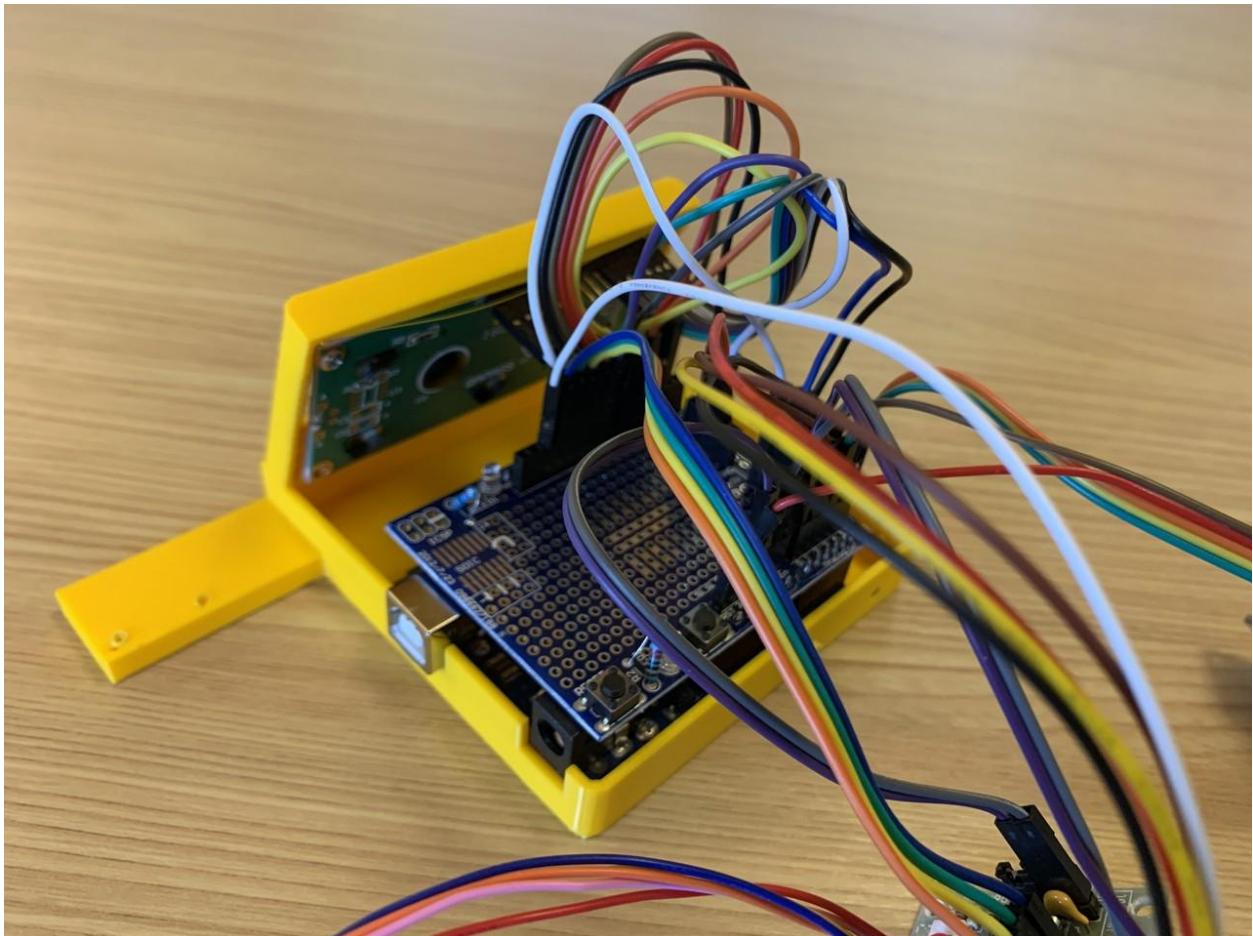
Insert the Arduino in the case and install it with (4) #4  $\frac{1}{4}$ " sheet metal screws.



Insert the Proto Shield on top of the Arduino which has been screwed into the case.

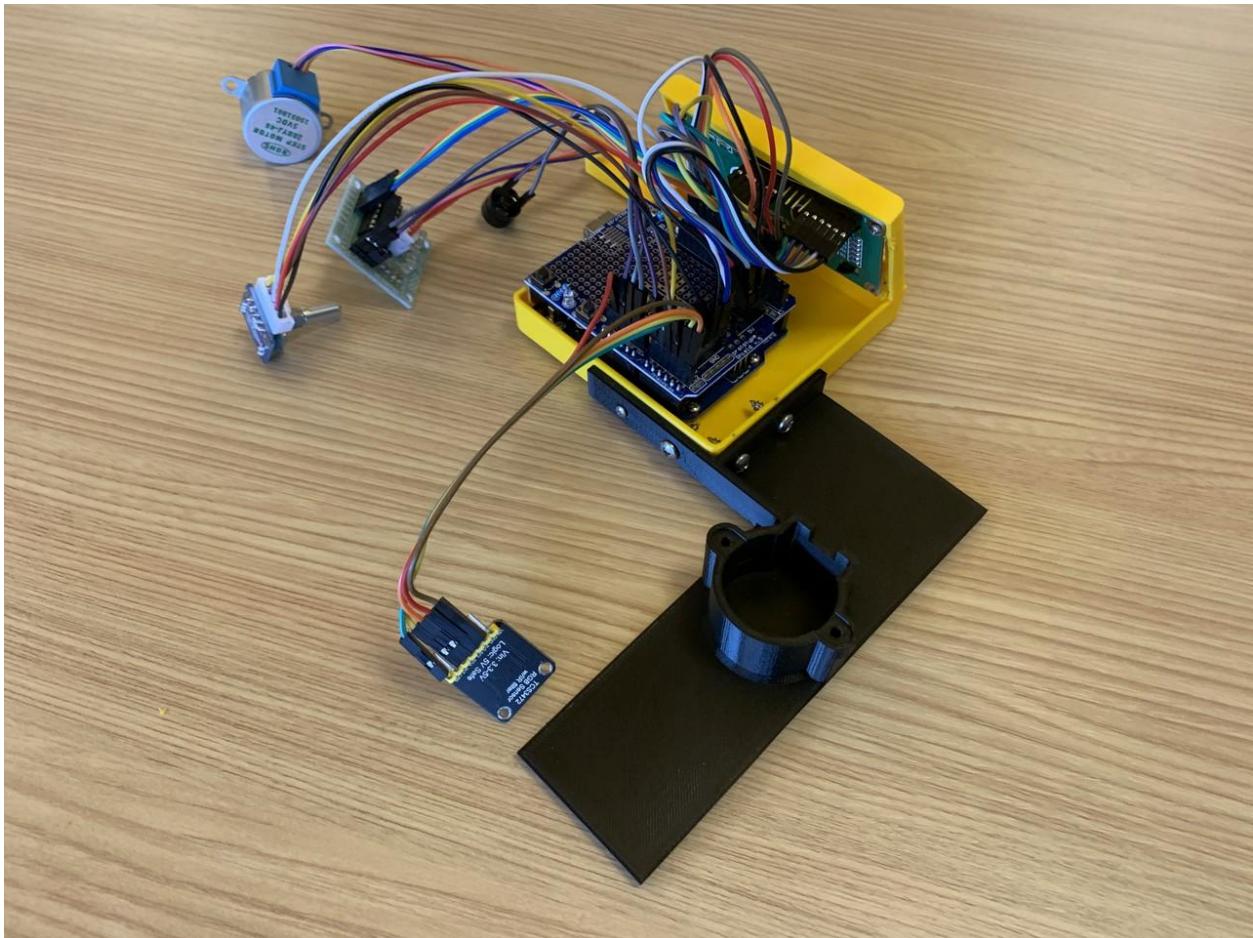


Insert the 1602 LCD Display in the case and install the upper (2) #4  $\frac{1}{4}$ " sheet metal screws. Note that the bottom two mounting screws are not necessary but can also be inserted.

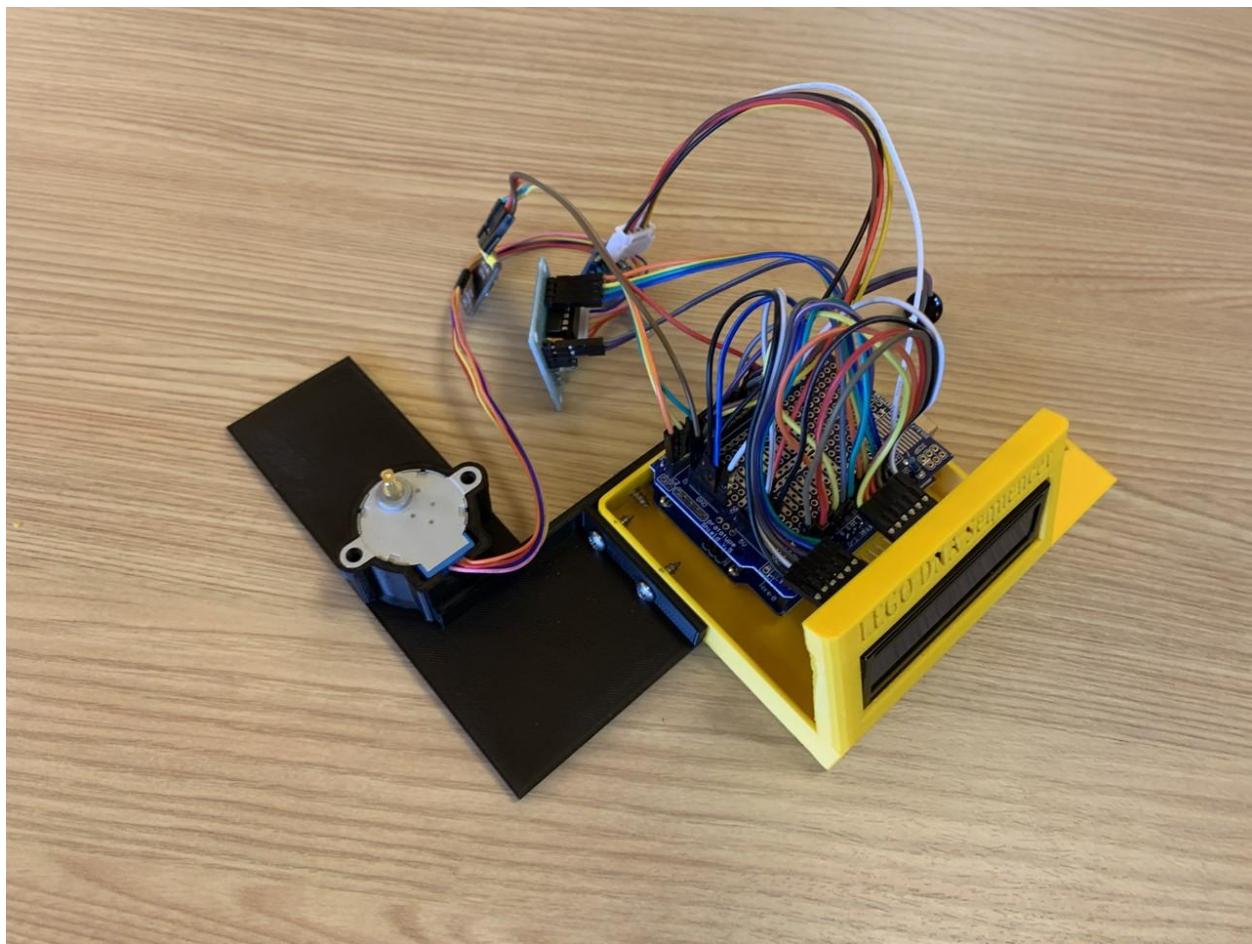


## Complete the Assembly

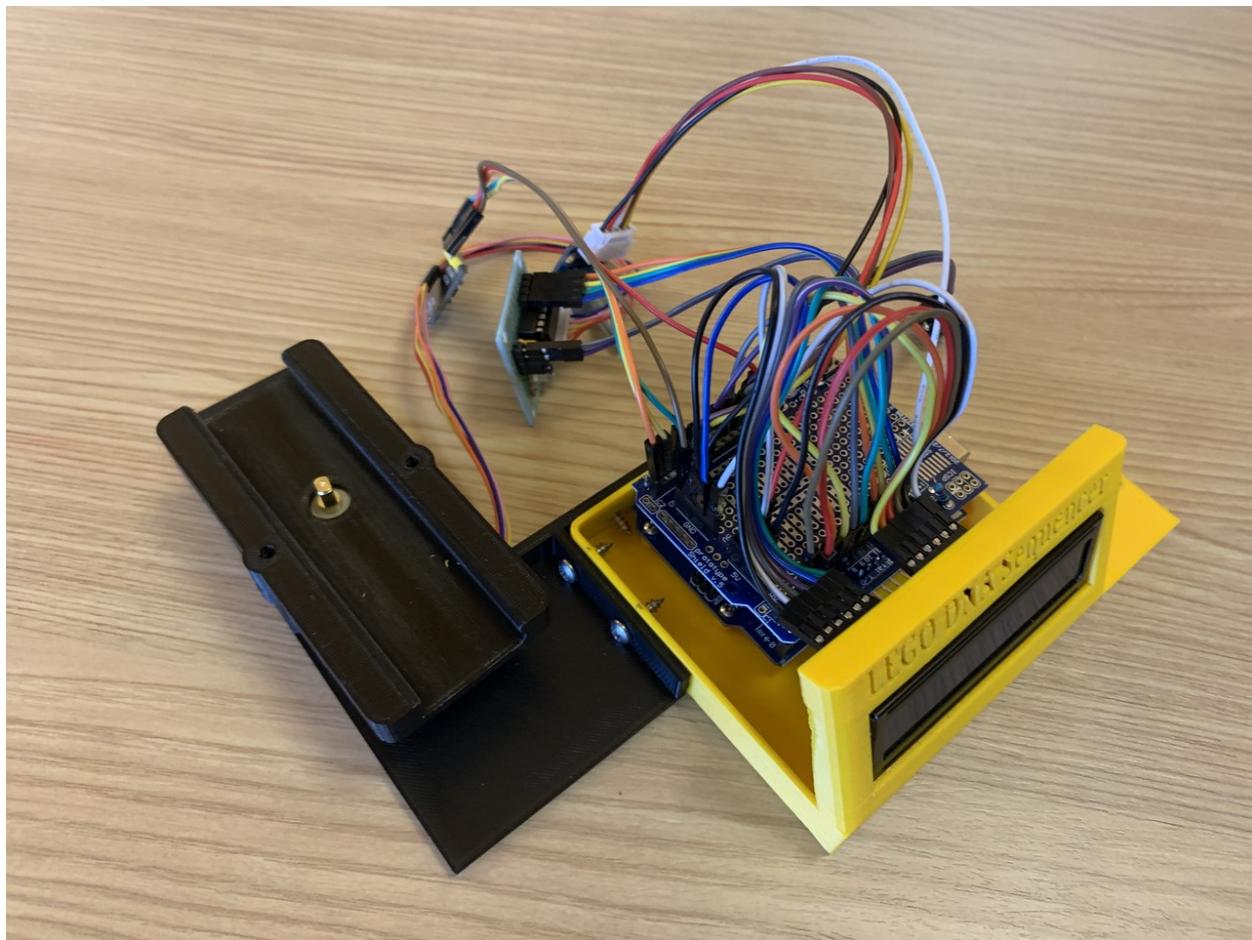
Connect the stepper motor base to the Arduino and LCD case. This is done with (3) #6 ½" sheet metal screws and (1) #4 ¼ sheet metal screw. Note that the shorter screw is used to avoid striking the Arduino UNO.



Insert the 28BYJ-48 Stepper Motor into the base unit.



Mount the tray/gear holder on top of the stepper motor, aligning it with the gear shaft and the two mounting holes.

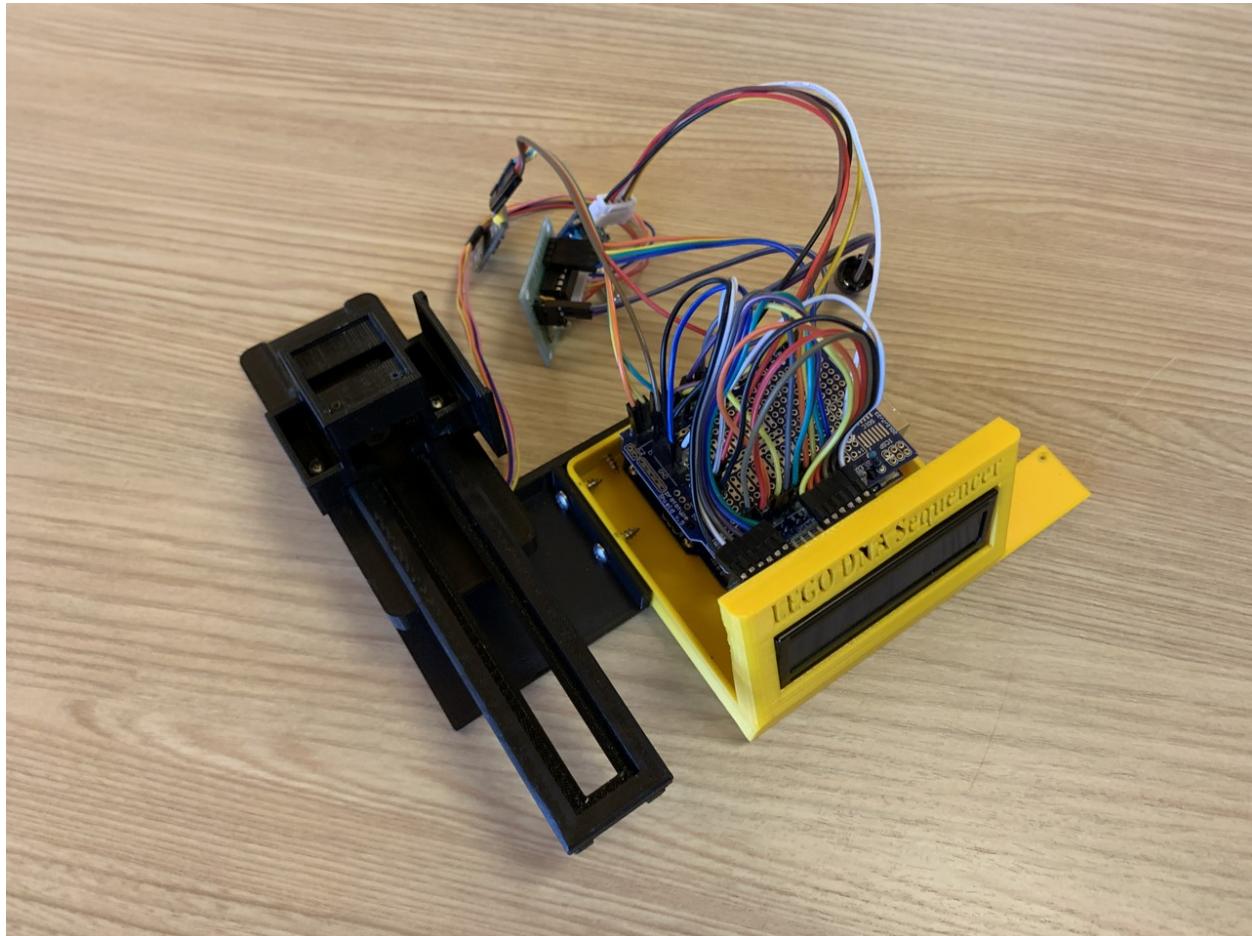


Verify that the gear moves smoothly in the track. This can be done by placing the gear in the opening position of the track and using a flat bladder screwdriver to rotate the gear. You should be able to rotate the gear the entire length of the track. You will need to correct any places where the gear binds and doesn't move smoothly. Sandpaper and a deburring tool may do the job.

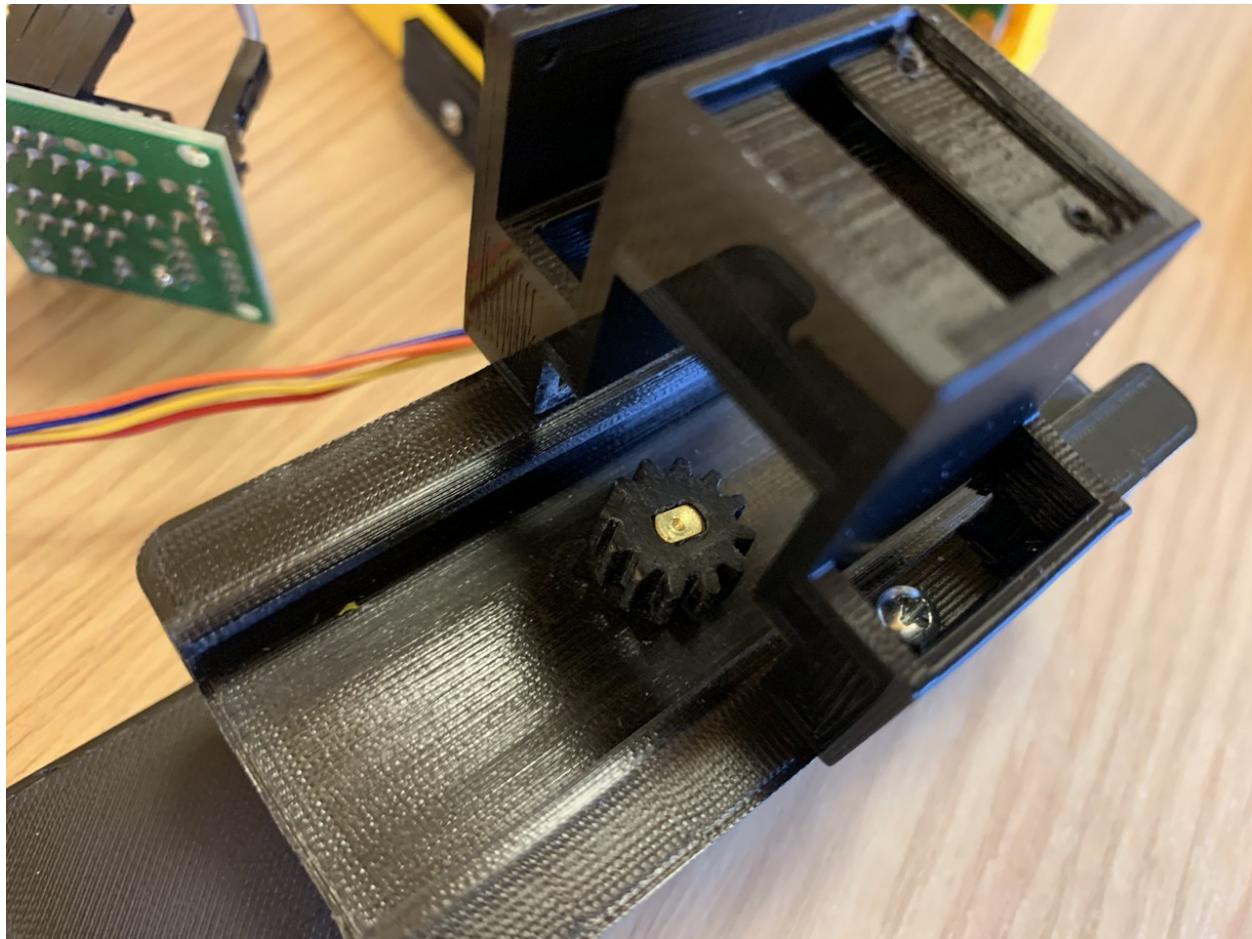


Place the color sensor / motor drive on top of the tray holder. Note that the motor drive attachment must be on the Arduino case side. Insert (2) #6  $\frac{3}{4}$ " sheet metal screws into the two mounting holes and gently tighten them, aligning all three elements: base mount, holder mount, and sensor mount.

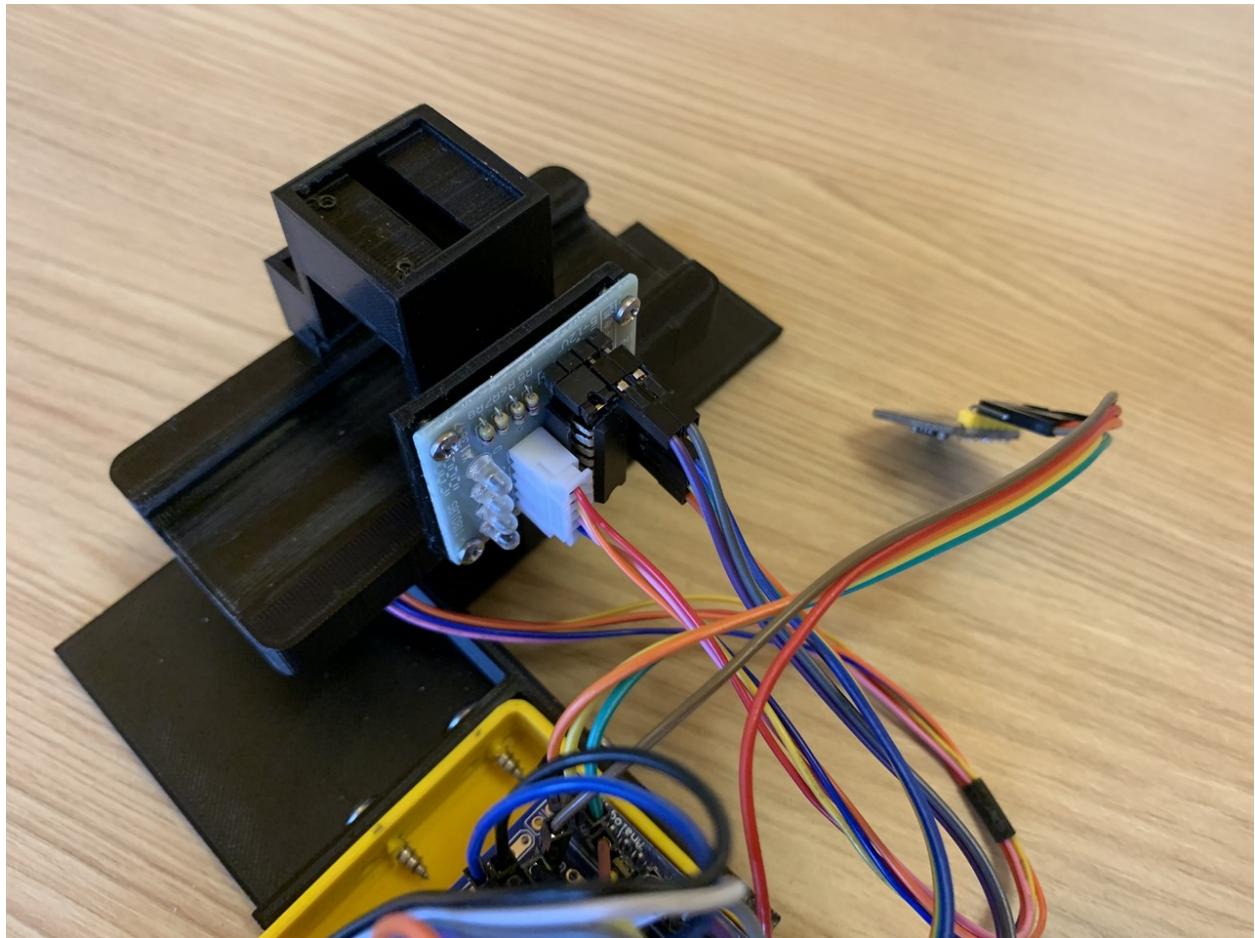
Make certain that the LEGO tray holder slides smoothly back and forth along the entire track.



Insert the gear onto the top of the stepper motor shaft.



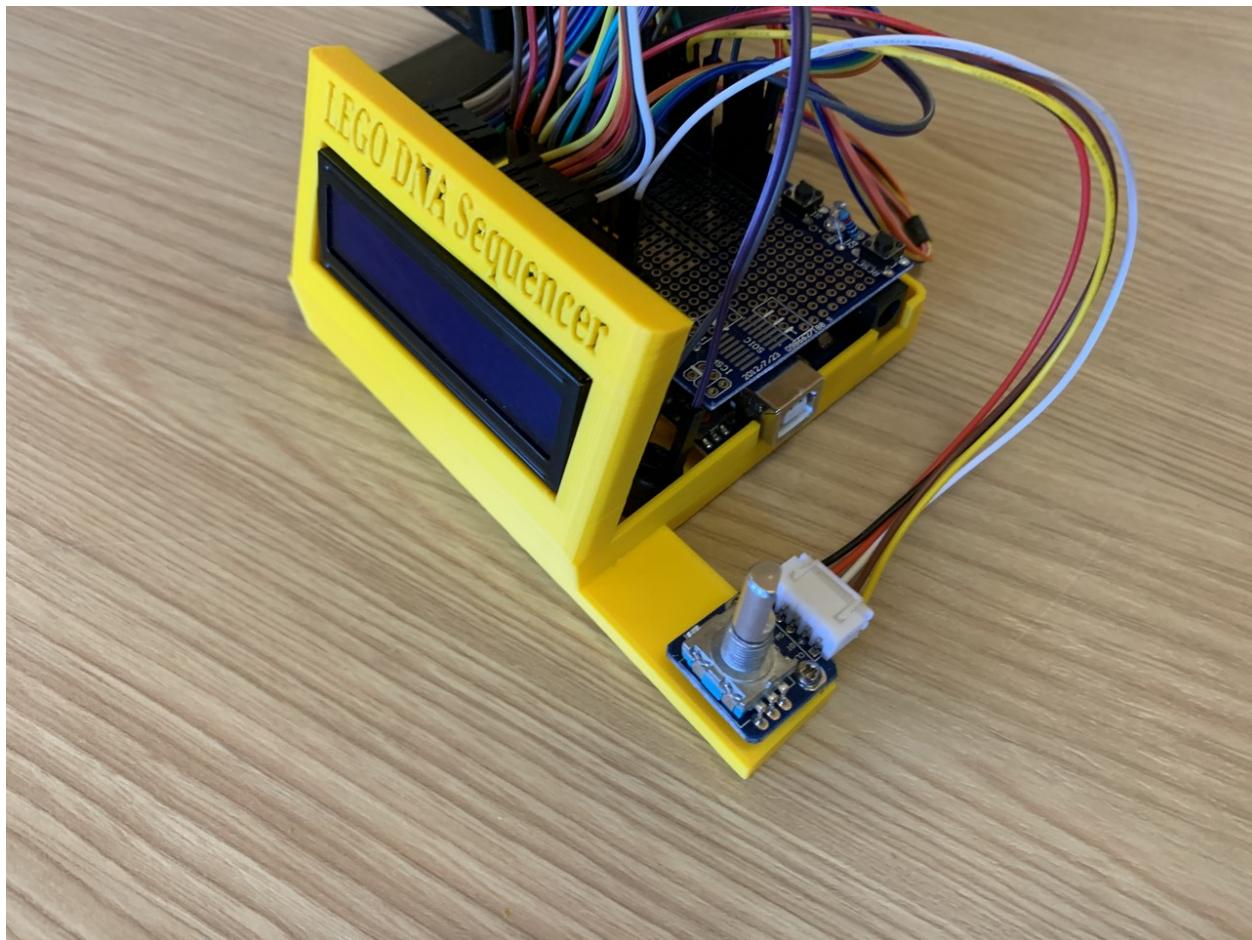
Insert the motor driver on the side of the color sensor and motor driver mount. Make sure that you have oriented the board as shown below.



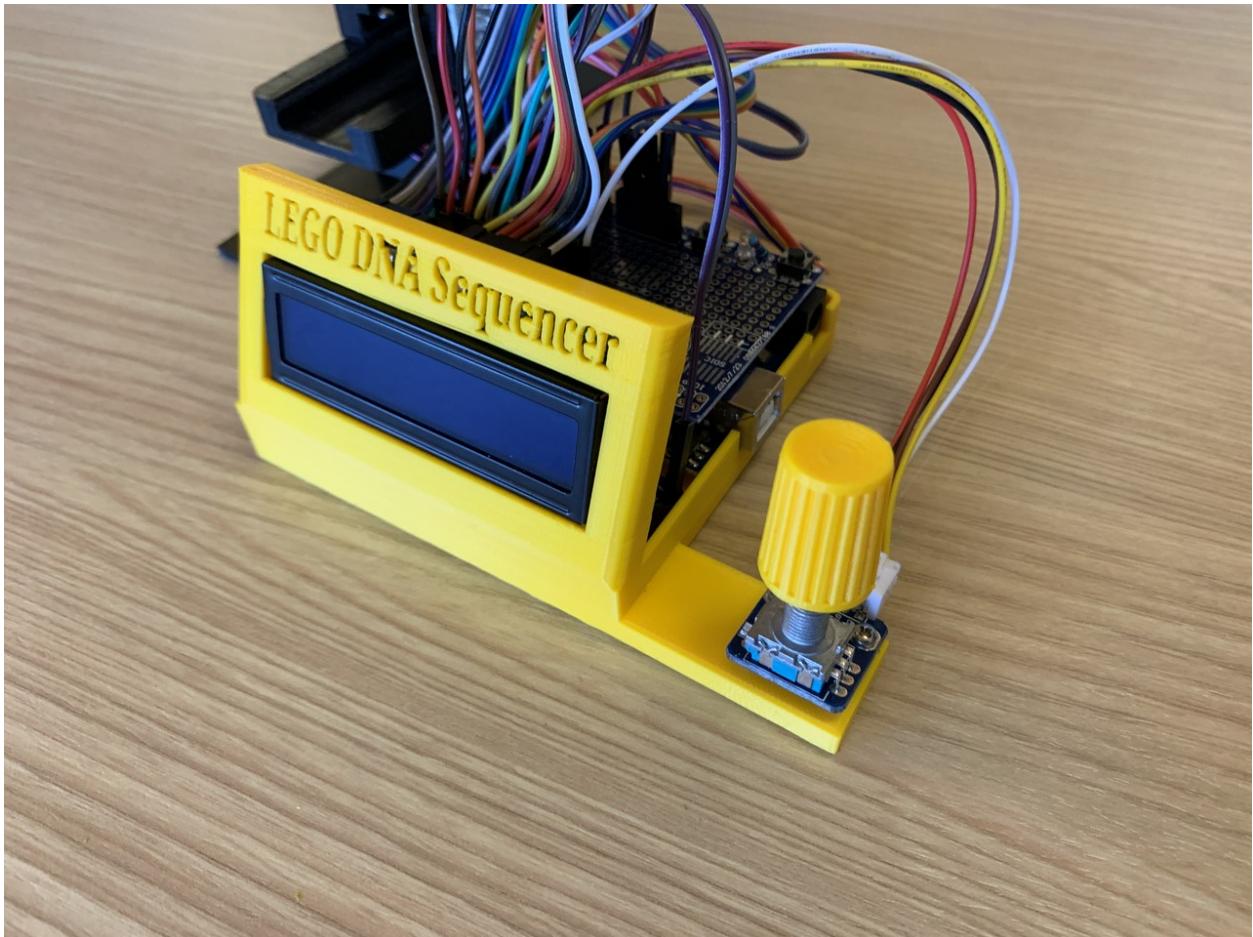
Attach the TCS34725 Color Sensor to the top of the color sensor mount with (2) #4 ¼" sheet metal screws. Note that the cables must protrude from the rear of the assembly.



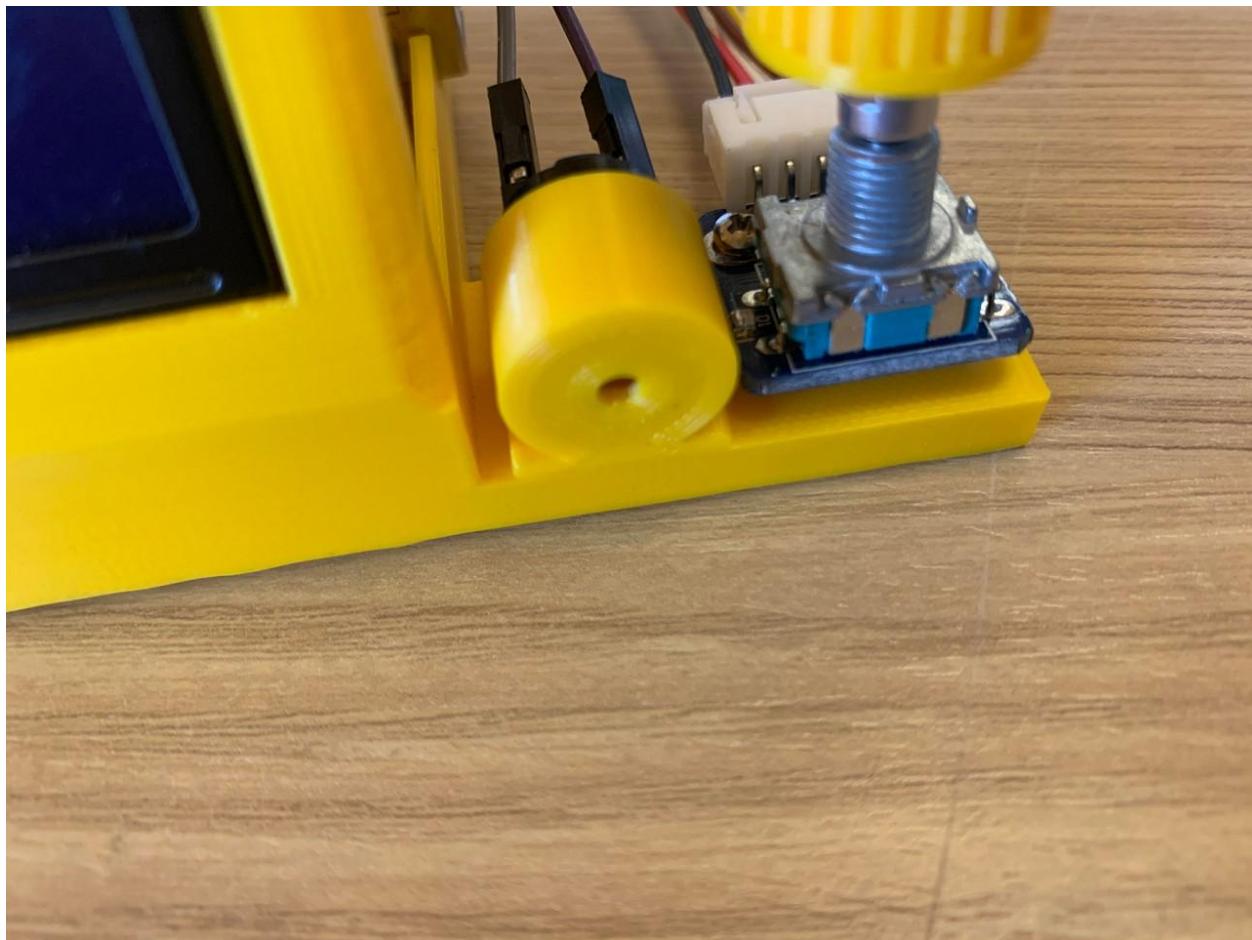
Attach the rotary encoder to the two far right holes in the flange extending from the right side of the Arduino case with (2) #4 1/4" sheet metal screws.



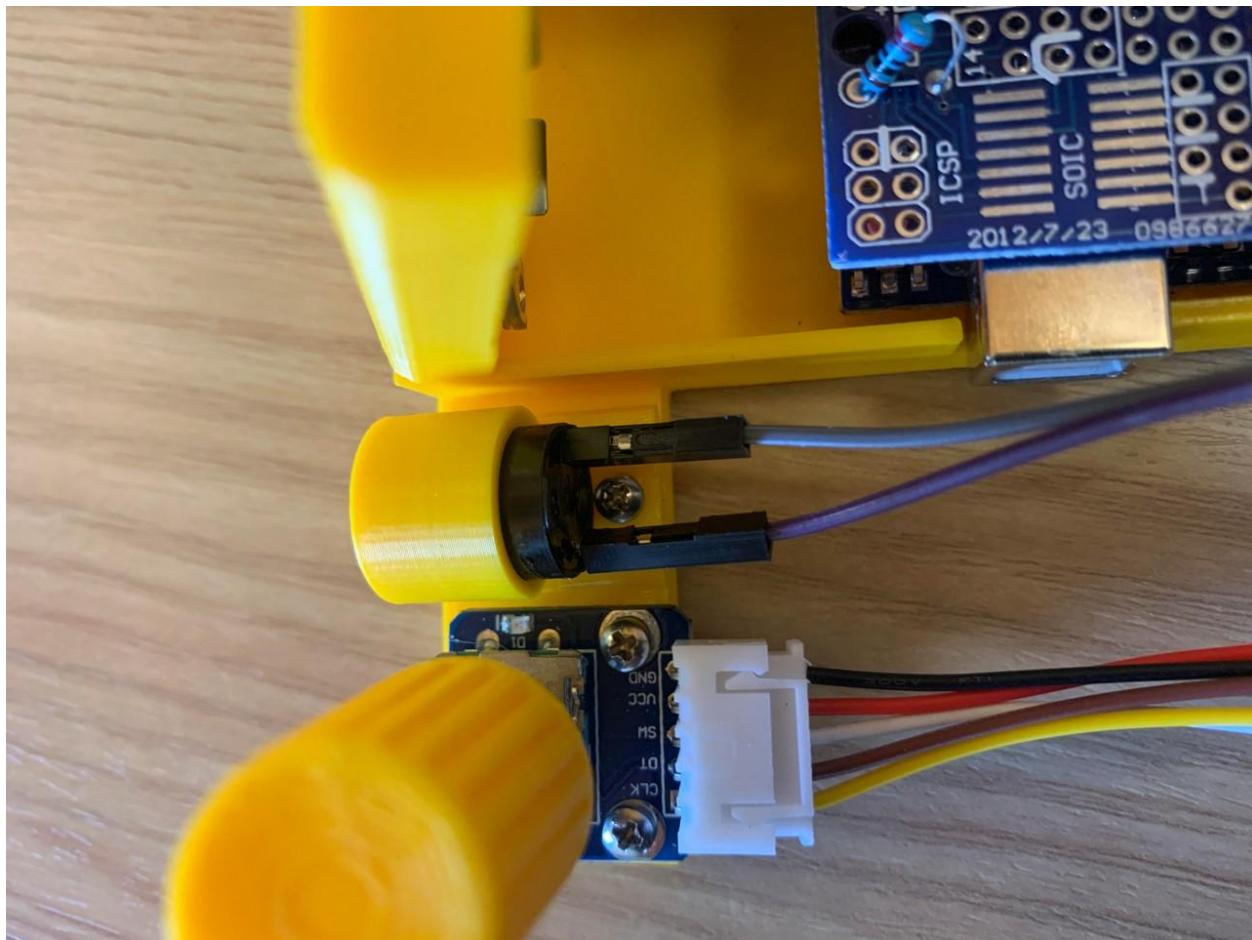
Place the knob on top of the rotary encoder shaft.



Attach the buzzer holder to the remaining hole in the flange extending from the right side of the Arduino case with (1) #4 ¼" sheet metal screw.



Insert the buzzer into the back of the holder with the pins on the aligned so that the sheet metal screw can be inserted between the two pins.



# Unit and System Testing

There are Unit Testing Arduino modules for each of the hardware components, including:

- Buzzer
- LCD and Rotary Encoder
- Stepper Motor
- TCS34725

Successful operation of each of the Unit Tests should be done before a System Test with the LEGO DNA Sequencer.

The Arduino source is provided for each of the Unit Tests.

## Buzzer Unit Test

```
*****  
LEGO DNA Sequencer  
Buzzer Unit Test  
Original Code: 2022-12-24  
Tom Rolander, MSEE  
Mentor for Circuit Design, Software, 3D Printing  
Miller Library, Fabrication Lab  
Hopkins Marine Station, Stanford University,  
120 Ocean View Blvd, Pacific Grove, CA 93950  
+1 831.915.9526 | rolander@stanford.edu  
*****  
  
#define PROGRAM F("LEGO DNA Sequencer - Buzzer Unit Test")  
#define VERSION F("Ver 0.1 2023-04-19")  
#define DEBUG_OUTPUT 1  
#define DEBUG_MODE 0  
  
int buzzer = A0;//the pin of the active buzzer  
  
void setup()  
{  
    Serial.begin(115200);  
    delay(1000);  
    Serial.println();  
    Serial.println(PROGRAM);  
    Serial.println(VERSION);  
  
    pinMode(buzzer, OUTPUT); //initialize the buzzer pin as an output  
}  
  
void Beeps(int iNmbBeeps, int iMSLengthON, int iMSLengthOFF)  
{  
    Serial.print("Number of Beeps = ");  
    Serial.print(iNmbBeeps);  
    Serial.print(", MS Length ON = ");  
    Serial.print(iMSLengthON);  
    Serial.print(", MS Length OFF = ");  
    Serial.println(iMSLengthOFF);  
  
    for (int i=0; i<iNmbBeeps; i++)  
    {  
        digitalWrite(buzzer, HIGH);  
        delay(iMSLengthON);//wait for 1ms  
        digitalWrite(buzzer, LOW);  
        delay(iMSLengthOFF);//wait for 1ms  
    }  
}
```

```
}

void loop()
{
    Beeps(10, 1, 1000);
    delay(5000);

    Beeps(1, 20, 0);
    delay(5000);

    Beeps(2, 20, 250);
    delay(5000);

    Beeps(3, 20, 200);
    delay(5000);
}
```

# LCD and Rotary Encoder Unit Test

```
*****  
LEGO DNA Sequencer  
LCD and Button Unit Test  
  
Original Code: 2022-12-24  
  
Tom Rolander, MSEE  
Mentor for Circuit Design, Software, 3D Printing  
Miller Library, Fabrication Lab  
Hopkins Marine Station, Stanford University,  
120 Ocean View Blvd, Pacific Grove, CA 93950  
+1 831.915.9526 | rolander@stanford.edu  
  
*****/  
  
#define PROGRAM "LEGO DNA Sequencer - LCD and Rotary Encoder Unit Test"  
#define VERSION "Ver 0.1 2023-04-19"  
  
#define DEBUG_OUTPUT 1  
  
#define LED_TCS34725 A3  
  
#include <LiquidCrystal.h>  
int Contrast = 75;  
LiquidCrystal lcd(8, 7, 5, 4, 3, 2);  
  
// Rotary Encoder Inputs  
#define CLK A1  
#define DT A2  
#define SW 13  
  
int counter = 0;  
int currentStateCLK;  
int lastStateCLK;  
String currentDir ="";  
unsigned long lastButtonPress = 0;  
  
void setup()  
{  
    Serial.begin(115200);  
    delay(1000);  
    Serial.println();  
    Serial.println(PROGRAM);  
    Serial.println(VERSION);  
  
    // Set encoder pins as inputs
```

```

pinMode(CLK, INPUT);
pinMode(DT, INPUT);
pinMode(SW, INPUT_PULLUP);

// Read the initial state of CLK
lastStateCLK = digitalRead(CLK);

//pinMode(13, INPUT_PULLUP);

analogWrite(6, Contrast);
lcd.begin(16, 2);

pinMode(LED_TCS34725, OUTPUT);
digitalWrite(LED_TCS34725, LOW);

lcd.setCursor(0, 0);
//lcd.print("      1      ");
//lcd.print("0123456789012345");
lcd.print("LCD Unit Testing");

lcd.setCursor(0, 1);
lcd.print(" Rotary Encoder ");

delay(2000);

lcd.setCursor(0, 0);
lcd.print(" Rotary Encoder ");
lcd.setCursor(0, 1);
lcd.print("      ");
}

void loop()
{
    // Read the current state of CLK
    currentStateCLK = digitalRead(CLK);

    // If last and current state of CLK are different, then pulse occurred
    // React to only 1 state change to avoid double count
    if (currentStateCLK != lastStateCLK && currentStateCLK == 1) {

        // If the DT state is different than the CLK state then
        // the encoder is rotating CCW so decrement
        if (digitalRead(DT) != currentStateCLK) {
            counter--;
            currentDir ="CCW";
        } else {
            // Encoder is rotating CW so increment
            counter++;
            currentDir ="CW";
        }
    }
}

```

```

Serial.print("Direction: ");
Serial.print(currentDir);
Serial.print(" | Counter: ");
Serial.println(counter);

lcd.setCursor(0, 1);
lcd.print("                ");
lcd.setCursor(0, 1);
lcd.print("Counter = ");
lcd.print(counter);
}

// Remember last CLK state
lastStateCLK = currentStateCLK;

// Read the button state
int btnState = digitalRead(SW);

// If we detect LOW signal, button is pressed
if (btnState == LOW) {
    //if 50ms have passed since last LOW pulse, it means that the
    //button has been pressed, released and pressed again
    if (millis() - lastButtonPress > 50) {
        Serial.println("Button pressed!");
        lcd.setCursor(0, 1);
        lcd.print("Button pressed! ");
    }
}

// Remember last button press event
lastButtonPress = millis();
}

// Put in a slight delay to help debounce the reading
delay(1);
}

```

# Stepper Motor Unit Test

```
*****  
LEGO DNA Sequencer  
Stepper Motor Unit Test
```

Original Code: 2022-12-24

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```
******/
```

```
#define PROGRAM "LEGO DNA Sequencer - Stepper Motor Unit Test"  
#define VERSION "Ver 0.1 2023-04-19"  
  
#define DEBUG_OUTPUT 1  
  
#define LED_TCS34725 A3  
  
//Includes the Arduino Stepper Library  
#include <Stepper.h>  
  
// Defines the number of steps per rotation  
const int stepsPerRevolution = 2038;  
  
#define STEPPER_PIN_1 9  
#define STEPPER_PIN_2 10  
#define STEPPER_PIN_3 11  
#define STEPPER_PIN_4 12  
  
// Creates an instance of stepper class  
// Pins entered in sequence IN1-IN3-IN2-IN4 for proper step sequence  
Stepper myStepper = Stepper(stepsPerRevolution, STEPPER_PIN_1, STEPPER_PIN_3,  
STEPPER_PIN_2, STEPPER_PIN_4);  
  
static int iSteps = 0;  
  
void setup() {  
  Serial.begin(115200);  
  delay(1000);  
  Serial.println();  
  Serial.println(PROGRAM);  
  Serial.println(VERSION);
```

```

pinMode (LED_TCS34725, OUTPUT);
digitalWrite (LED_TCS34725, LOW);

myStepper.setSpeed(10);

Serial.println("Hit debugger Send to enter Commands");
help();
}

void help()
{
    Serial.println("Command Line Mode:");
    Serial.println("  Fxxxx to go Forward xxxx steps");
    Serial.println("  Rxxxx to go Reverse xxxx steps");
}

void loop()
{
    if (Serial.available() > 0)
    {
        char cBuffer[7];
        int nChars;
        int iValue = 0;

        nChars = Serial.readBytes(cBuffer, sizeof(cBuffer));
        cBuffer[nChars] = '\0';
        Serial.println(cBuffer);
        cBuffer[0] = toupper(cBuffer[0]);
        if (nChars != 5 ||
            (cBuffer[0] != 'F' && cBuffer[0] != 'R'))
        {
            help();
            return;
        }

        for (int i=1; i<5; i++)
        {
            iValue = (iValue * 10) + (cBuffer[i]-'0');
        }
        if (cBuffer[0] == 'R')
            iValue = 0 - iValue;

        iSteps = iSteps + iValue;
        myStepper.step(iValue);
        Serial.print("Position = ");
        Serial.println(iSteps);
    }
}

```

# TCS34725 Color Sensor Unit Test

NOTE: To run this Unit Test you should remove the gear from the tray holder and move the tray with LEGOs manually under the color sensor.

```
*****  
LEGO DNA Sequencer  
TCS34725 Color Sensor Unit Test  
  
Original Code: 2022-12-24  
  
Tom Rolander, MSEE  
Mentor for Circuit Design, Software, 3D Printing  
Miller Library, Fabrication Lab  
Hopkins Marine Station, Stanford University,  
120 Ocean View Blvd, Pacific Grove, CA 93950  
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*****/  
  
#define PROGRAM "LEGO DNA Sequencer - TCS34725 Color Sensor Unit Test"  
#define VERSION "Ver 0.1 2023-04-19"  
  
#define DEBUG_OUTPUT 1  
  
#include <Wire.h>  
#include "Adafruit_TCS34725.h"  
  
#define CLEAR    -1  
#define RED      3  
#define GREEN    2  
#define BLUE     1  
#define YELLOW   0  
  
#define LED_TCS34725  A3  
  
#define FLORA 1  
  
#if FLORA  
#define CLEAR_CHANNEL_THRESHOLD 3149  
#define RED_CHANNEL_THRESHOLD 700  
#define BLUE_CHANNEL_THRESHOLD 823  
#else  
#define CLEAR_CHANNEL_THRESHOLD 900  
#define RED_CHANNEL_THRESHOLD 170  
#define BLUE_CHANNEL_THRESHOLD 220
```

```

#endif

static int iCLEAR_CHANNEL_THRESHOLD = CLEAR_CHANNEL_THRESHOLD;
static int iRED_CHANNEL_THRESHOLD = RED_CHANNEL_THRESHOLD;
static int iBLUE_CHANNEL_THRESHOLD = BLUE_CHANNEL_THRESHOLD;

/* Initialise with specific int time and gain values */
Adafruit_TCS34725 tcs = Adafruit_TCS34725(TCS34725_INTEGRATIONTIME_50MS,
TCS34725_GAIN_16X);

void setup(void) {
    Serial.begin(115200);
    delay(1000);
    Serial.println();
    Serial.println(PROGRAM);
    Serial.println(VERSION);

    pinMode (LED_TCS34725, OUTPUT);
    digitalWrite (LED_TCS34725, LOW);
    if (tcs.begin()) {
        Serial.println("Found sensor");
        // LED off to prevent overheating
        tcs.setInterrupt(true);
    } else {
        Serial.println("No TCS34725 found ... check your connections");
        while (1);
    }
}

Serial.println("Delay 5 seconds, then turn on LED light");
delay(5000);
digitalWrite (LED_TCS34725, HIGH);
tcs.setInterrupt(false);
}

void loop(void) {
    uint16_t r, g, b, c;
    tcs.getRawData(&r, &g, &b, &c);
    Serial.print("Red: "); Serial.print(r, DEC); Serial.print(" ");
    Serial.print("Green: "); Serial.print(g, DEC); Serial.print(" ");
    Serial.print("Blue: "); Serial.print(b, DEC); Serial.print(" ");
    Serial.print("Clear: "); Serial.print(c, DEC); Serial.print(" ");

    if (c >= iCLEAR_CHANNEL_THRESHOLD)
    {
        Serial.println(F("Y,C"));
    }
    else if (r >= iRED_CHANNEL_THRESHOLD)
    {
        Serial.println(F("R,G"));
    }
}

```

```
        }
    else if (b >= iBLUE_CHANNEL_THRESHOLD)
    {
        Serial.println(F("B,T"));
    }
else
    /* if (g > b && g > r) */
{
    Serial.println(F("G,A"));
}

delay(1000);
}
```

# Arduino Source Code

To compile and run the Arduino code the following libraries are needed for the Arduino IDE:

- [Adafruit\\_TCS34725](#)
  - [MD5](#) Note: this is only required if you enable FILTER\_BAD\_WORDS

```
*****  
*****  
LEGO DNA Sequencer  
Main Program  
  
Original Code: 2022-12-24  
  
Tom Rolander, MSEE  
Mentor for Circuit Design, Software, 3D Printing  
Miller Library, Fabrication Lab  
Hopkins Marine Station, Stanford University,  
120 Ocean View Blvd, Pacific Grove, CA 93950  
+1 831.915.9526 | rolander@stanford.edu  
  
*****  
  
#define PROGRAM F("LEGO DNA Sequencer - Main Program")  
#define VERSION F("Ver 0.9 2023-03-29")  
#define PROGRAM_SHORT F("LEGO DNA Sqncr ")  
#define VERSION_SHORT F("Ver 0.9 03-29-23")  
  
#define DEBUG_OUTPUT 0  
#define DEBUG_MODE 0  
  
#define FILTER_BAD_WORDS 0  
  
#define FLORA 0  
  
#define STATE_START 0  
#define STATE_LOAD_TRAY 1  
#define STATE_SEQUENCING 2  
  
// Proc to reset the Arduino  
void (* re_set)(void) = 0x00;  
  
static bool bRemoteLCDSerial = true;
```

```

static int iState = STATE_START;

static int iStepPosition = 0;

static bool bAutomated = true;

#define BUZZER      A0

#define LED_TCS34725 A3

#if DEBUG_MODE
static bool bCommandLineMode = false;
#endif

// Rotary Encoder Inputs
#define CLK A1
#define DT A2
#define SW 13

static int iRotaryEncoder_Counter = 0;
static int iRotaryEncoder_CurrentStateCLK;
static int iRotaryEncoder_LastStateCLK;
static bool bRotaryEncoder_CurrentDirectionClockwise;
static unsigned long lastButtonPress = 0;

char sNameChars[40] = "ABCDEFGHIJKLMNPQRSTUVWXYZ0123456789 <*>";
//          0           1           2           3
//          0           1
#define NMB_NAME_CHARS 39

char sNumberChars[13] = "0123456789<*>";
//          0           1
//          0           1
#define NMB_NUMBER_CHARS 12

#if FILTER_BAD_WORDS
#include <MD5.h>
#define NMB_BAD_WORDS 10
const unsigned char ucBadWords[NMB_BAD_WORDS][16] =
{
    {0x84, 0xb9, 0x06, 0x03, 0x0d, 0x48, 0x52, 0x7c, 0xe0, 0x5c, 0x36, 0x82,
     0xf, 0x94, 0xc9, 0xa3},
    {0x01, 0x2e, 0x3b, 0x42, 0x29, 0xed, 0x77, 0x78, 0x85, 0x07, 0x44, 0xbb,
     0x32, 0x7f, 0xa5, 0x54},
    {0x71, 0xb4, 0x74, 0xfa, 0xa, 0x68, 0x85, 0x32, 0x55, 0x2a, 0xa, 0x95,
     0x46, 0x4a, 0x9a, 0x00},
    {0x4f, 0x79, 0x1f, 0x1f, 0xc2, 0xf1, 0xbc, 0x1a, 0x86, 0xab, 0xc3, 0x8d,
     0x46, 0x78, 0x9b, 0x34},
}

```

```

    {0x00, 0x94, 0xcf, 0x00, 0x63, 0x7a, 0xee, 0x49, 0xb2, 0x3c, 0x4f, 0x44,
0xba, 0xaf, 0xe0, 0xde},
    {0x4a, 0x46, 0x6a, 0x30, 0x2e, 0x55, 0xdd, 0x2e, 0x4e, 0x8d, 0xf6, 0xde,
0xa7, 0xaa, 0xc3, 0x2f},
    {0xbe, 0x97, 0x62, 0x73, 0xca, 0x31, 0x79, 0xad, 0x77, 0x72, 0x63, 0xfb,
0x26, 0xac, 0x08, 0xd4},
    {0x27, 0x50, 0xfe, 0xdb, 0xda, 0x13, 0x41, 0xe9, 0x84, 0x2b, 0xdd, 0xb7,
0x44, 0xc8, 0x62, 0x03},
    {0xa0, 0x15, 0x4f, 0x58, 0xd6, 0xa4, 0x46, 0x1c, 0x9d, 0x35, 0x3d, 0x04,
0xd6, 0x3d, 0xb0, 0x8b},
    {0xf7, 0x3e, 0x87, 0x12, 0x37, 0x3e, 0xba, 0xab, 0xa7, 0xf8, 0xb6, 0x91,
0xa1, 0x92, 0x24, 0xeb}
};

#endif

#include <EEPROM.h>

#define EEPROM_LEGO_SIGNATURE F("LEGO");

// EEPROM state variables
#define EEPROM_SIZE 512

#define EEPROM_SIGNATURE          0 // 000-003  Signature 'LEGO'
#define EEPROM_CLEAR_CHANNEL_THRESHHOLD 4 // 004-005
iRED_CHANNEL_THRESHHOLD
#define EEPROM_RED_CHANNEL_THRESHHOLD 6 // 006-007
iRED_CHANNEL_THRESHHOLD
#define EEPROM_BLUE_CHANNEL_THRESHHOLD 8 // 008-009
iBLUE_CHANNEL_THRESHHOLD
#define EEPROM_REMOTE_LCD_SERIAL 10 // 010-010 bRemoteLCDSerial
#define EEPROM_NUMBER_OF_LEGO_DNA 11 // 011-011 iNumberOfEEPROM
#define EEPROM_LEGO_DNA 12 // 012-511 LEGO_DNAs

#define EEPROM_LEGODNA_MAX 4
#define EEPROM_LEGODNA_ENTRY_SIZE 28

#define LEGO_DNA_MAX 11

static int iNumberOfEEPROM = 0;

#define NMB_LEGODRICKS 10

int iBrickSequencing[NMB_LEGODRICKS][4];
char sDNASequence[NMB_LEGODRICKS + 1] = "";

int iLEGO_DNA_Number = 7;
#if 1
char sLEGO_DNA_Sequence[LEGO_DNA_MAX][NMB_LEGODRICKS + 1] =

```

```

{ "CCGGTTAACC",
  "CGATGACTAG",
  "TACGCTAGCT",
  "GATCCGATGC",
  "ACTGATCGAT",
  "TAGCTAGCTA",
  "CAGTACGATC"
};

char sLEGO_DNA_Name[LEGO_DNA_MAX][17] =
{ " YYRRBGGYY TEST",
  " SEA URCHIN  ",
  " WHITE SHARK  ",
  " SEA STAR   ",
  " ANCHOVY    ",
  " GIANT KELP  ",
  " PELICAN    "
};

#endif
#if 0
char sLEGO_DNA_Sequence[LEGO_DNA_MAX][NMB_LEGO_BRICKS + 1] =
{ "CCGGTTAACC",
  "ATTGGTCATT",
  "TGCTCCTACA",
  "CACAATCTAC",
  "GCTCCGGGT",
  "CAAATCTTAG",
  "CGTCTACCAA"
};

char sLEGO_DNA_Name[LEGO_DNA_MAX][17] =
{ " YYRRBGGYY TEST",
  " MAKO SHARK  ",
  " ABALONE     ",
  " SQUID       ",
  " COPEPOD    ",
  " SEA STAR   ",
  " TUNA        "
};

#endif

#include <LiquidCrystal.h>
int Contrast = 75;
LiquidCrystal lcd(8, 7, 5, 4, 3, 2);

//Includes the Arduino Stepper Library
#include <Stepper.h>

// Defines the number of steps per rotation
const int stepsPerRevolution = 2038;

```

```

#define STEPPER_PIN_1 9
#define STEPPER_PIN_2 10
#define STEPPER_PIN_3 11
#define STEPPER_PIN_4 12

#define OFFSET_TO_FIRST_BRICK 460
#define STEPS_PER_LEGO_BRICK 550
#define STEPS_PER_AUTO_POSITION 25
#define OFFSET_AUTO_POSITION 200

// Creates an instance of stepper class
// Pins entered in sequence IN1-IN3-IN2-IN4 for proper step sequence
Stepper myStepper = Stepper(stepsPerRevolution, STEPPER_PIN_1, STEPPER_PIN_3,
STEPPER_PIN_2, STEPPER_PIN_4);

#if DEBUG_MODE
#define MAINTENANCE_NMB_OPS 10
#else
#define MAINTENANCE_NMB_OPS 9
#endif
#define MAINTENANCE_OP_CANCEL 0
#define MAINTENANCE_OP_COMMAND_LINE 1
#define MAINTENANCE_OP_UNLOAD_TRAY 2
#define MAINTENANCE_OP_LOAD_TRAY 3
#define MAINTENANCE_OP_POSITION_TRAY 4
#define MAINTENANCE_OP_ZERO_NEW_DNA 5
#define MAINTENANCE_OP_BUZZER_OFF 6
#define MAINTENANCE_OP_BUZZER_ON 7
#define MAINTENANCE_OP_ADVANCED 8
#define MAINTENANCE_OP_VERSION_INFO 9
#endif
#define MAINTENANCE_OP_UNLOAD_TRAY 1
#define MAINTENANCE_OP_LOAD_TRAY 2
#define MAINTENANCE_OP_POSITION_TRAY 3
#define MAINTENANCE_OP_ZERO_NEW_DNA 4
#define MAINTENANCE_OP_BUZZER_OFF 5
#define MAINTENANCE_OP_BUZZER_ON 6
#define MAINTENANCE_OP_ADVANCED 7
#define MAINTENANCE_OP_VERSION_INFO 8

char sMaintenanceOp[MAINTENANCE_NMB_OPS][17] =
{ " CANCEL      ",
#if DEBUG_MODE
" COMMAND LINE ",
#endif
" UNLOAD TRAY  ",
" LOAD TRAY    ",
" POSITION TRAY",

```

```

    " ZERO NEW DNA  ",  

    " BUZZER OFF    ",  

    " BUZZER ON     ",  

    " ADVANCED      ",  

    " VERSION INFO  "  

};  
  

#define ADVANCED_NMB_OPS          9  
  

#define ADVANCED_OP_CANCEL         0  

#define ADVANCED_OP_CLEAR_CHANNEL  1  

#define ADVANCED_OP_RED_CHANNEL   2  

#define ADVANCED_OP_BLUE_CHANNEL  3  

#define ADVANCED_OP_AUTO_CHANNEL  4  

#define ADVANCED_OP_AUTO_POSITION 5  

#define ADVANCED_OP_REMOTE_LCD_ON 6  

#define ADVANCED_OP_REMOTE_LCD_OFF 7  

#define ADVANCED_OP_REBOOT        8  
  

char sAdvancedOp[ADVANCED_NMB_OPS][17] =  

{ " CANCEL          ",  

  " CLEAR CHANNEL   ",  

  " RED CHANNEL     ",  

  " BLUE CHANNEL    ",  

  " AUTO CHANNEL    ",  

  " AUTO POSITION   ",  

  " REMOTE LCD ON  ",  

  " REMOTE LCD OFF ",  

  " REBOOT          "
};  
  

static bool bBuzzer = true;  
  

#include <Wire.h>  

#include "Adafruit_TCS34725.h"  
  

#define CLEAR    -1  

#define RED     'G'  

#define GREEN   'A'  

#define BLUE    'T'  

#define YELLOW  'C'  
  

/* Initialise with specific int time and gain values */  

Adafruit_TCS34725 tcs = Adafruit_TCS34725(TCS34725_INTEGRATIONTIME_50MS,  

TCS34725_GAIN_16X);  
  

#if FLORA  

#define CLEAR_CHANNEL_THRESHHOLD 130

```

```

#define RED_CHANNEL_THRESHOLD 35
#define BLUE_CHANNEL_THRESHOLD 30
#else
#define CLEAR_CHANNEL_THRESHOLD 900
#define RED_CHANNEL_THRESHOLD 170
#define BLUE_CHANNEL_THRESHOLD 220
#endif

static int iCLEAR_CHANNEL_THRESHOLD = CLEAR_CHANNEL_THRESHOLD;
static int iRED_CHANNEL_THRESHOLD = RED_CHANNEL_THRESHOLD;
static int iBLUE_CHANNEL_THRESHOLD = BLUE_CHANNEL_THRESHOLD;

void setup() {
    Serial.begin(115200);
    delay(1000);

#if DEBUG_OUTPUT
    Serial.println();
    Serial.println(PROGRAM);
    Serial.println(VERSION);
#endif

pinMode(BUZZER, OUTPUT); //initialize the buzzer pin as an output

// Set encoder pins as inputs
pinMode(CLK, INPUT);
pinMode(DT, INPUT);
pinMode(SW, INPUT_PULLUP);

// Read the initial state of CLK
iRotaryEncoder_LastStateCLK = digitalRead(CLK);

analogWrite(6, Contrast);
lcd.begin(16, 2);

pinMode(LED_TCS34725, OUTPUT);
digitalWrite(LED_TCS34725, LOW);

if (tcs.begin()) {
#if DEBUG_OUTPUT
    Serial.println(F("Found sensor"));
#endif
    // LED off to prevent overheating
    tcs.setInterrupt(true);

} else {
    Serial.println(F("No TCS34725 found ... check your connections"));
    while (1);
}

```

```

myStepper.setSpeed(10);

char cBuffer[5];
int nChars;
long lStartTime = millis();

#if DEBUG_MODE
    bCommandLineMode = true;
    lcd.setCursor(0, 0);
    lcd.print(F("LEGO DNA Sqncr  "));
    lcd.setCursor(0, 1);
    lcd.print(F("Debugger Console"));
#else
    StartSequencer();
#endif

#if DEBUG_OUTPUT
    for (int i = 0; i < 128; i++)
    {
        int iByte = EEPROM[i];
        if (i % 16 == 0)
            Serial.println("");
        if (iByte < 16)
            Serial.print(F("0"));
        Serial.print(iByte, HEX);
        Serial.print(F(" "));
    }
    Serial.println("");
#endif

LoadEEPROM();

Beeps(3, 10, 200); // 3 Beeps, 10MS ON, 200MS OFF
}

void LoadEEPROM()
{
    if (EEPROM[EEPROM_SIGNATURE + 0] == 'L' &&
        EEPROM[EEPROM_SIGNATURE + 1] == 'E' &&
        EEPROM[EEPROM_SIGNATURE + 2] == 'G' &&
        EEPROM[EEPROM_SIGNATURE + 3] == 'O')
    {
        iCLEAR_CHANNEL_THRESHHOLD =
        readUnsignedIntFromEEPROM(EEPROM_CLEAR_CHANNEL_THRESHHOLD);
        iRED_CHANNEL_THRESHHOLD =
        readUnsignedIntFromEEPROM(EEPROM_RED_CHANNEL_THRESHHOLD);
        iBLUE_CHANNEL_THRESHHOLD =
        readUnsignedIntFromEEPROM(EEPROM_BLUE_CHANNEL_THRESHHOLD);
    }
}

```

```

bRemoteLCDSerial= EEPROM[EEPROM_REMOTE_LCD_SERIAL];
iNumberOfEEPROM = EEPROM[EEPROM_NUMBER_OF_LEGO_DNA];

int index;
int iOffset = EEPROM_LEGO_DNA;
for (index = 0; index < iNumberOfEEPROM; index++)
{
    for (int i = 0; i < 11; i++)
    {
        sLEGO_DNA_Sequence[iLEGO_DNA_Number][i] = EEPROM[iOffset];
        iOffset = iOffset + 1;
    }
    for (int i = 0; i < 17; i++)
    {
        sLEGO_DNA_Name[iLEGO_DNA_Number][i] = EEPROM[iOffset];
        iOffset = iOffset + 1;
    }
}

#if DEBUG_OUTPUT
    Serial.println(F("EEPROM Data"));
    Serial.print(F("Index "));
    Serial.print(iLEGO_DNA_Number);
    Serial.print(F(" ["));
    Serial.print(&sLEGO_DNA_Sequence[iLEGO_DNA_Number][0]);
    Serial.print(F("] ["));
    Serial.print(&sLEGO_DNA_Name[iLEGO_DNA_Number][0]);
    Serial.println(F("]"));
#endif

iLEGO_DNA_Number = iLEGO_DNA_Number + 1;
}

else
{
#if DEBUG_OUTPUT
    Serial.println(F("EEPROM LEGO not found"));
#endif
    SetupEEPROM();
}

#if DEBUG_OUTPUT
    Serial.println(F("EEPROM LEGO found"));
    Serial.print(F("bRemoteLCDSerial = "));
    Serial.println(bRemoteLCDSerial);
    Serial.print(F("iNumberOfEEPROM = "));
    Serial.println(iNumberOfEEPROM);
    Serial.print(F("Clear Channel Threshold = "));
    Serial.println(iCLEAR_CHANNEL_THRESHOLD);
    Serial.print(F("Red Channel Threshold = "));
    Serial.println(iRED_CHANNEL_THRESHOLD);
    Serial.print(F("Blue Channel Threshold = "));
    Serial.println(iBLUE_CHANNEL_THRESHOLD);

```

```

#endif
}

void writeUnsignedIntIntoEEPROM(int address, unsigned int number)
{
    EEPROM[address] = number >> 8;
    EEPROM[address + 1] = number & 0xFF;
}

unsigned int readUnsignedIntFromEEPROM(int address)
{
    return (EEPROM[address] << 8) + EEPROM[address + 1];
}

void SetupEEPROM()
{
    EEPROM[EEPROM_SIGNATURE + 0] = 'L';
    EEPROM[EEPROM_SIGNATURE + 1] = 'E';
    EEPROM[EEPROM_SIGNATURE + 2] = 'G';
    EEPROM[EEPROM_SIGNATURE + 3] = 'O';
    writeUnsignedIntIntoEEPROM(EEPROM_CLEAR_CHANNEL_THRESHOLD,
iCLEAR_CHANNEL_THRESHOLD);
    writeUnsignedIntIntoEEPROM(EEPROM_RED_CHANNEL_THRESHOLD,
iRED_CHANNEL_THRESHOLD);
    writeUnsignedIntIntoEEPROM(EEPROM_BLUE_CHANNEL_THRESHOLD,
iBLUE_CHANNEL_THRESHOLD);
    EEPROM[EEPROM_REMOTE_LCD_SERIAL] = bRemoteLCDSerial;
    EEPROM[EEPROM_NUMBER_OF_LEGO_DNA] = iNumberOfEEPROM;

#if DEBUG_OUTPUT
    Serial.println(F("EEPROM LEGO initialized"));
#endif

}

void UpdateLCD(char cColor, int index)
{
    char lcd1[17] = "Sequencing DNA  ";
    char lcd2[17] = "                 ";
    lcd2[index] = cColor;
    for(int i=0; i<index; i++)
        lcd2[i] = sDNASequence[i];
    RemoteLCDSerial(lcd1, lcd2);
    lcd.print(cColor);
}

char GetLEGOColor(int index)
{
    char cRetcode = '\0';

```

```

uint16_t r, g, b, c;

tcs.getRawData(&r, &g, &b, &c);

iBrickSequencing[index][0] = r;
iBrickSequencing[index][1] = g;
iBrickSequencing[index][2] = b;
iBrickSequencing[index][3] = c;

#if DEBUG_OUTPUT
    Serial.print(iStepPosition, DEC); Serial.print(F(","));
    Serial.print(r, DEC); Serial.print(F(","));
    Serial.print(g, DEC); Serial.print(F(","));
    Serial.print(b, DEC); Serial.print(F(","));
    Serial.print(c, DEC); Serial.print(F("")));
#endif

if (c >= iCLEAR_CHANNEL_THRESHOLD)
{
    UpdateLCD(YELLOW, index);
    cRetcode = YELLOW;
#if DEBUG_OUTPUT
    Serial.println(F("Y,C"));
#endif
}
else if (r >= iRED_CHANNEL_THRESHOLD)
{
    UpdateLCD(RED, index);
    cRetcode = RED;
#if DEBUG_OUTPUT
    Serial.println(F("R,G"));
#endif
}
else if (b >= iBLUE_CHANNEL_THRESHOLD)
{
    UpdateLCD(BLUE, index);
    cRetcode = BLUE;
#if DEBUG_OUTPUT
    Serial.println(F("B,T"));
#endif
}
else
/* if (g > b && g > r) */
{
    UpdateLCD(GREEN, index);
    cRetcode = GREEN;
#if DEBUG_OUTPUT
    Serial.println(F("G,A"));
#endif
}

```

```

#endif
}

return (cRetcode);
}

void StartSequencer()
{
    lcd.setCursor(0, 0);
    lcd.print(F("LEGO DNA Sqncr  "));
    lcd.setCursor(0, 1);
    lcd.print(F(" Push Button      "));
    F_RemoteLCDSerial(F("LEGO DNA Sqncr  "),F(" Push Button      "));
}

void help()
{
#if DEBUG_OUTPUT
    Serial.println(F("Command Line Mode:"));
    Serial.println(F(" Lxxxx to go Left xxxx steps"));
    Serial.println(F(" Rxxxx to go Right xxxx steps"));
    Serial.println(F(" Sxxxx set RPM to xxxx"));
    Serial.println(F(" C to Read Color Sensor"));
    Serial.println(F(" K Read Color Sensor until Send"));
    Serial.println(F(" 1 Color Sensor Light ON"));
    Serial.println(F(" 0 Color Sensor Light OFF"));
    Serial.println(F(" M Manual Sequencer"));
    Serial.println(F(" A Automated Sequencer"));
    Serial.println(F(" E to Start Sequencer"));
    Serial.println(F(" Z zero out added DNAs"));
#endif
}

bool GetButtonPressed()
{
    // Read the button state
    int btnState = digitalRead(SW);

    //If we detect LOW signal, button is pressed
    if (btnState == LOW)
    {
        //if 50ms have passed since last LOW pulse, it means that the
        //button has been pressed, released and pressed again
        if (millis() - lastButtonPress > 50) {
            //      lcd.setCursor(0, 1);
            //      lcd.print("Button pressed! ");
        }
    }

    // Wait for button to be released
}

```

```

while (digitalRead(SW) == LOW)
;

// Remember last button press event
lastButtonPress = millis();
return (true);
}
return (false);
}

bool GetYesOrNo(bool bInitialResponse, char *sQuestion)
{
    bool bResponse = bInitialResponse;

    char lcd1[17] = "                ";
    char lcd2[17];
    strncpy(lcd1, sQuestion, strlen(sQuestion));

    lcd.setCursor(0, 0);
    lcd.print(F("                "));
    lcd.setCursor(0, 0);
    lcd.print(sQuestion);
    lcd.setCursor(0, 1);
    if (bInitialResponse == false)
    {
        lcd.print(F("[NO] YES      "));
        strcpy(lcd2, "[NO] YES      ");
    }
    else
    {
        lcd.print(F(" NO [YES]      "));
        strcpy(lcd2, " NO [YES]      ");
    }
    if (bRemoteLCDSerial)
    {
        delay(500);
        RemoteLCDSerial(lcd1, lcd2);
    }

    while (GetButtonPressed() == false)
    {
        delay(1);
        if (CheckRotaryEncoder())
        {
            if (bRotaryEncoder_CurrentDirectionClockwise == false)
            {
                if (bResponse != false)
                {
                    lcd.setCursor(0, 1);

```

```

        lcd.print(F("[NO]    YES      "));
        strcpy(lcd2,"[NO]    YES      ");
    }
    bResponse = false;
}
else
{
    if (bResponse != true)
    {
        lcd.setCursor(0, 1);
        lcd.print(F(" NO    [YES]      "));
        strcpy(lcd2," NO    [YES]      ");
    }
    bResponse = true;
}
if (bRemoteLCDSerial)
{
    delay(500);
    RemoteLCDSerial(lcd1, lcd2);
}
}
}
while (digitalRead(SW) == LOW)
;

return (bResponse);
}

///////////////////////////////
int GetNumber(int iCurrentValue, char *iName, int iOffsetEEPROM)
{
    lcd.setCursor(0, 0);
    lcd.print(F("Enter "));
    lcd.write((byte) 0xff);
    lcd.print(F(" to end "));
    lcd.setCursor(0, 1);
    lcd.print(F("      "));
    lcd.setCursor(0, 1);
    lcd.print(iName);
    lcd.print(F("="));

    int iOffset = strlen(iName) + 1;
    char sNewNumber[5] = "";
    char cNextChar;

    sprintf(sNewNumber, "%d", iCurrentValue);
    lcd.print(sNewNumber);

    int index = strlen(sNewNumber);

```

```

while (index < 5)
{
    cNextChar = GetNextNumber(index + iOffset);
    if (cNextChar == '\0')
    {
        break;
    }
    if (cNextChar == '<')
    {
        if (index > 0)
        {
            lcd.setCursor(index + iOffset, 1);
            lcd.print(' ');
            index = index - 1;
            continue;
        }
    }
    sNewNumber[index] = cNextChar;
    index = index + 1;
    sNewNumber[index] = '\0';
}

if (strlen(sNewNumber) != 0)
{
    int iValue = 0;
    for (int i = 0; i < 4; i++)
    {
        if (sNewNumber[i] == '\0')
            break;
        iValue = (iValue * 10) + (sNewNumber[i] - '0');
    }
    if (iValue != iCurrentValue)
    {
        char sTemp[17] = "SET ";
        strcat(sTemp, iName);
        strcat(sTemp, "=");
        strcat(sTemp, sNewNumber);
        if (GetYesOrNo(false, sTemp))
        {
            writeUnsignedIntIntoEEPROM(iOffsetEEPROM, iValue);
            return (iValue);
        }
    }
}
return (-1);
}
///////////
bool CheckRotaryEncoder()

```

```

{
    bool bResponse = true;

    // Read the current state of CLK
    iRotaryEncoder_CurrentStateCLK = digitalRead(CLK);

    // If last and current state of CLK are different, then pulse occurred
    // React to only 1 state change to avoid double count
    if (iRotaryEncoder_CurrentStateCLK != iRotaryEncoder_LastStateCLK &&
iRotaryEncoder_CurrentStateCLK == 1) {

        // If the DT state is different than the CLK state then
        // the encoder is rotating CCW so decrement
        if (digitalRead(DT) != iRotaryEncoder_CurrentStateCLK) {
            iRotaryEncoder_Counter--;
            bRotaryEncoder_CurrentDirectionClockwise = false;
        } else {
            // Encoder is rotating CW so increment
            iRotaryEncoder_Counter++;
            bRotaryEncoder_CurrentDirectionClockwise = true;
        }
    }
    else
    {
        bResponse = false;
    }

    // Remember last CLK state
    iRotaryEncoder_LastStateCLK = iRotaryEncoder_CurrentStateCLK;
    delay(10);
    return (bResponse);
}

void loop()
{
#if DEBUG_MODE
    if (bCommandLineMode)
    {
        if (Serial.available() > 0)
        {
            char cBuffer[7];
            int nChars;
            int iValue = 0;

            nChars = Serial.readBytes(cBuffer, sizeof(cBuffer));
            Serial.print(F("nChars = "));
            Serial.println(nChars);
            cBuffer[nChars] = '\0';
            Serial.print(F("cBuffer = "));

```

```

Serial.println(cBuffer);

cBuffer[0] = toupper(cBuffer[0]);

if (nChars == 1)
{
    switch (cBuffer[0])
    {
        case 'Z':
            iNumberOfEEPROM = 0;
            iLEGO_DNA_Number = 6;
            for (int i = 0; i < 512; i++)
                EEPROM[i] = '\0';
            SetupEEPROM();
            break;

        case 'E':
            StartSequencer();
            iState = STATE_START;
            bCommandLineMode = false;
            return;

        case 'M':
            bAutomated = false;
            break;

        case 'A':
            bAutomated = true;
            break;

        case 'C':
            GetLEGOColor(0);
            break;

        case 'K':
            while (Serial.available() <= 0)
            {
                GetLEGOColor(0);
                delay(500);
            }
            nChars = Serial.readBytes(cBuffer, sizeof(cBuffer));
            help();
            break;

        case '1':
            tcs.setInterrupt(false);
            digitalWrite(LED_TCS34725, HIGH);
            break;
    }
}

```

```

        case '0':
            tcs.setInterrupt(true);
            digitalWrite (LED_TCS34725, LOW);
            break;

        default:
            Serial.println(F("Unrecognized command!"));
            help();
            break;
    }
    return;
}
if (nChars != 5 ||
    (cBuffer[0] != 'L' && cBuffer[0] != 'R' && cBuffer[0] != 'S'))
{
    help();
    return;
}

for (int i = 1; i < 5; i++)
{
    iValue = (iValue * 10) + (cBuffer[i] - '0');
}
Serial.print(F("Value = "));
if (cBuffer[0] == 'R')
    iValue = 0 - iValue;
Serial.println(iValue);

if (cBuffer[0] == 'S')
    myStepper.setSpeed(iValue);
else
{
    MoveTray(iValue);
    GetLEGOCOLOR(0);
}
return;
}
#endif

if (iState == STATE_START)
{
    if (GetButtonPressed())
    {
        //      while (digitalRead(SW) == LOW)
        //      ;
        iState = STATE_LOAD_TRAY;
    }
    else

```

```

    {
        return;
    }
}

if (iState == STATE_LOAD_TRAY)
{
    F_RemoteLCDSerial(F("Load LEGO Tray   "), F(" Push Button      "));
    lcd.setCursor(0, 0);
    lcd.print(F("Load LEGO Tray   "));
    lcd.setCursor(0, 1);
    lcd.print(F(" Push Button      "));

    Beeps(1, 5, 0); // 1 Beep, 5MS ON, 0MS OFF

    while (GetButtonPressed() == false)
    {
        if (CheckRotaryEncoder())
        {
            lcd.setCursor(0, 0);
            lcd.print(F("Select Option:  "));

            int iMaintenanceOp = MAINTENANCE_OP_CANCEL;

            while (true)
            {
                lcd.setCursor(0, 1);
                lcd.print(sMaintenanceOp[iMaintenanceOp]);

                if (GetButtonPressed())
                    break;

                int iCounter = iRotaryEncoder_Counter;
                if (CheckRotaryEncoder())
                {
                    if (iRotaryEncoder_Counter > iCounter)
                    {
                        iMaintenanceOp++;
                        if (iMaintenanceOp >= MAINTENANCE_NMB_OPS)
                            iMaintenanceOp = MAINTENANCE_OP_CANCEL;
                    }
                    else
                    {
                        iMaintenanceOp--;
                        if (iMaintenanceOp < 0)
                            iMaintenanceOp = MAINTENANCE_OP_VERSION_INFO;
                    }
                }
            }
        }
    }
}

```

```

        switch (iMaintenanceOp)
        {
            case MAINTENANCE_OP_CANCEL:
#if DEBUG_OUTPUT
                Serial.println(F("Cancel"));
#endif
                StartSequencer();
                iState = STATE_START;
#if DEBUG_MODE
                bCommandLineMode = false;
#endif
                break;

#if DEBUG_MODE
            case MAINTENANCE_OP_COMMAND_LINE:
                Serial.println(F("Enter Command Line Mode"));
                bCommandLineMode = true;
                break;
#endif

            case MAINTENANCE_OP_UNLOAD_TRAY:
#if DEBUG_OUTPUT
                Serial.println(F("Unload Tray"));
#endif
                myStepper.step(-4000);
                iStepPosition = 0;
                break;

            case MAINTENANCE_OP_LOAD_TRAY:
#if DEBUG_OUTPUT
                Serial.println(F("Load Tray"));
#endif
                myStepper.step(1640);
                iStepPosition = 0;
                break;

            case MAINTENANCE_OP_POSITION_TRAY:
#if DEBUG_OUTPUT
                Serial.println(F("Position Tray"));
#endif
                {
                    int iCounter = iRotaryEncoder_Counter;
                    while (GetButtonPressed() == false)
                    {
                        if (CheckRotaryEncoder())
                        {
#endif
#if DEBUG_OUTPUT
                            #if 0

```

```

        Serial.print(F("iCounter = "));
        Serial.print(iCounter);
        Serial.print(F(" iRotaryEncoder_Counter = "));
        Serial.println(iRotaryEncoder_Counter);

#endif
#endif

        if (iRotaryEncoder_Counter > iCounter)
            MoveTray(50);
        else
            MoveTray(-50);
        iCounter = iRotaryEncoder_Counter;
    }
}

break;

case MAINTENANCE_OP_ZERO_NEW_DNA:
    iNumberOfEEPROM = 0;
    iLEGO_DNA_Number = 6;
    for (int i = EEPROM_NUMBER_OF_LEGO_DNA; i < 512; i++)
        EEPROM[i] = '\0';
    SetupEEPROM();
    break;

case MAINTENANCE_OP_BUZZER_ON:
    bBuzzer = true;
    break;

case MAINTENANCE_OP_BUZZER_OFF:
    bBuzzer = false;
    break;

case MAINTENANCE_OP_ADVANCED:
    Advanced();
    break;

case MAINTENANCE_OP_VERSION_INFO:
    lcd.setCursor(0, 0);
    lcd.print(PROGRAM_SHORT);
    lcd.setCursor(0, 1);
    lcd.print(VERSION_SHORT);
    while (GetButtonPressed() == false &&
           CheckRotaryEncoder() == false)
    {
        delay(100);
    }
    break;
}

```

```

        return;
    }
}

iState = STATE_SEQUENCING;
}

lcd.setCursor(0, 0);
lcd.print(F("Sequencing DNA  "));
lcd.setCursor(0, 1);
lcd.print(F("          "));

F_RemoteLCDSerial(F("Sequencing DNA  "), F("          "));

lcd.setCursor(0, 1);

// STATE_SEQUENCING
tcs.setInterrupt(false);
digitalWrite (LED_TCS34725, HIGH);

myStepper.setSpeed(10);
iStepPosition = 0;
MoveTray(OFFSET_TO_FIRST_BRICK);

sDNASequence[NMB_LEGO_BRICKS] = '\0';

#if DEBUG_OUTPUT
Serial.println("");
Serial.println(F("----- CSV -----"));
Serial.println(F("P,R,G,B,Y,M,DNA"));
#endif

for (int i = 0; i < NMB_LEGO_BRICKS; i++)
{
    if (bAutomated == false)
    {
        lcd.setCursor(0, 0);
        lcd.print(F("Position LEGO # "));
        lcd.print(i);
        lcd.setCursor(0, 1);
        lcd.print(F(" Push Button      "));

        while (GetButtonPressed() == false)
        ;
    }

    delay(100); // Delay a little for visual effect
    sDNASequence[i] = GetLEGOCOLOR(i);
}

```

```

if (i < 9)
{
    Beeps(1, 2, 0); // 1 Beep, 2MS ON, 0MS OFF
    MoveTray(STEPS_PER_LEGOTRICK);
}
else
{
    tcs.setInterrupt(true);
    digitalWrite (LED_TCS34725, LOW);

    lcd.setCursor(0, 0);
    lcd.print(F("Unloading tray "));

    char lcd1[17] = "Unloading tray ";
    char lcd2[17] = " ";
    for(int i=0; i<NMB_LEGOTRICKS; i++)
        lcd2[i] = sDNASequence[i];
    RemoteLCDSerial(lcd1, lcd2);

    Beeps(2, 5, 250); // 2 Beeps, 5MS ON, 250MS OFF

    myStepper.setSpeed(15);
    MoveTray(-5410);

#if DEBUG_MODE
    Serial.print(F("["));
    Serial.print(sDNASequence);
    Serial.println(F("]"));
    for (int i = 0; i < NMB_LEGOTRICKS; i++)
    {
        for (int j = 0; j < 4; j++)
        {
            Serial.print(iBrickSequencing[i][j]);
            Serial.print(F(" "));
        }
        Serial.println("");
    }
#endif
    myStepper.setSpeed(10);
    iState = STATE_LOAD_TRAY;

    if ((strcmp(sDNASequence, "AAAAAAAAAA") == 0) ||
        (strcmp(sDNASequence, "CCCCCCCCCC") == 0) ||
        (strcmp(sDNASequence, "GGGGGGGGGG") == 0) ||
        (strcmp(sDNASequence, "TTTTTTTTTT") == 0))
    {
        lcd.setCursor(0, 0);
        lcd.print(F("EMPTY TRAY ERROR"));
        lcd.setCursor(0, 1);

```

```

lcd.print(F(" PUSH BUTTON      "));

Beeps(4, 10, 200); // 4 Beeps, 10MS ON, 200MS OFF

while (GetButtonPressed() == false)
{
}

else
{
    int index;
    for (index = 0; index < iLEGO_DNA_Number; index++)
    {
        if (strcmp(sDNASequence, sLEGO_DNA_Sequence[index]) == 0)
            break;
    }

    if (index < iLEGO_DNA_Number)
    {
        lcd.setCursor(0, 0);
        lcd.print(F("Successful match"));
        lcd.setCursor(0, 1);
        lcd.print(sLEGO_DNA_Name[index]);

        char lcd1[17] = "Successful match";
        char lcd2[17] = "";
        strcpy(lcd2, sLEGO_DNA_Name[index]);
        RemoteLCDSerial(lcd1, lcd2);

        Beeps(3, 5, 200); // 3 Beeps, 5MS ON, 200MS OFF
    }
    else
    {
        lcd.setCursor(0, 0);
        lcd.print(F("DNA not a match "));
        lcd.setCursor(0, 1);
        lcd.print(F(" UNKNOWN DNA!  "));
        F_RemoteLCDSerial(F("DNA not a match "), F(" UNKNOWN DNA!  "));

        Beeps(4, 10, 200); // 4 Beeps, 10MS ON, 200MS OFF
    }
}

while (GetButtonPressed() == false)
;

if (index >= iLEGO_DNA_Number)
{
    if (GetYesOrNo(false, "Add to Database?"))
    {
#if DEBUG_OUTPUT

```

```

Serial.println(F("Add to Database!"));

#endif

lcd.setCursor(0, 0);
lcd.print(F("Name: * to end "));
lcd.setCursor(0, 1);
lcd.print(F("          "));
F_RemoteLCDSerial(F("Name: * to end "), F("          "));

char sNewName[17] = "";
char cNextChar;

int index = 0;
while (index < 16)
{
    cNextChar = GetNextChar(index);
    if (cNextChar == '\0')
    {
        break;
    }
    if (cNextChar == '<')
    {
        if (index > 0)
        {
            lcd.setCursor(index, 1);
            lcd.print(' ');
            index = index - 1;
            sNewName[index] = '\0';
            char lcd1[17] = "Name: * to end ";
            char lcd2[17] = "          ";
            strncpy(lcd2, sNewName, strlen(sNewName));
            RemoteLCDSerial(lcd1, lcd2);
            continue;
        }
    }
    sNewName[index] = cNextChar;
    index = index + 1;
    sNewName[index] = '\0';

    char lcd1[17] = "Name: * to end ";
    char lcd2[17] = "          ";
    strncpy(lcd2, sNewName, strlen(sNewName));
    RemoteLCDSerial(lcd1, lcd2);
}
for (; index < 16; index++)
{
    sNewName[index] = ' ';
}
sNewName[16] = '\0';

```

```

if (strcmp(sNewName, "") != 0)
    if (GetYesOrNo(false, sNewName))
    {
        if (iNumberOfEEPROM >= (EEPROM_LEGODNA_MAX - 1))
        {
            lcd.setCursor(0, 0);
            lcd.print(F("EEPROM DB full! "));
            lcd.setCursor(0, 1);
            lcd.print(F(" Push Button "));
        }

        while (GetButtonPressed() == false)
        ;
    }
else
{
#endif DEBUG_OUTPUT
    Serial.print(F("Adding to Database ["));
    Serial.print(sDNASequence);
    Serial.print(F("] = ["));
    Serial.print(sNewName);
    Serial.println(F("]")));
}

#if FILTER_BAD_WORDS
    // Check for Bad Word
    bool bBadWord = false;
    for (int i = 0; i < NMB_BAD_WORDS; i++)
    {
        char sQuad[5] = "      ";
        for (int j = 0; j < 13; j++)
        {
            int k;
            strncpy(sQuad, &sNewName[j], 4);
            //generate the MD5 hash for our string
            unsigned char* hash = MD5::make_hash(sQuad);

            for (k = 0; k < 16; k++)
            {
                if (hash[k] == ucBadWords[i][k])
                    continue;
                break;
            }
            if (k == 16)
                bBadWord = true;
            free(hash);
            if (bBadWord)
                break;
        }
        if (bBadWord)

```



```

void Advanced()
{
    while (GetButtonPressed() == false)
    {
        while (true)
        {
            lcd.setCursor(0, 0);
            lcd.print(F("Select Option: "));

            int iAdvancedOp = ADVANCED_OP_CANCEL;

            while (true)
            {
                lcd.setCursor(0, 1);
                lcd.print(sAdvancedOp[iAdvancedOp]);

                if (GetButtonPressed())
                    break;

                int iCounter = iRotaryEncoder_Counter;
                if (CheckRotaryEncoder())
                {
                    if (iRotaryEncoder_Counter > iCounter)
                    {
                        iAdvancedOp++;
                        if (iAdvancedOp >= ADVANCED_NMB_OPS)
                            iAdvancedOp = ADVANCED_OP_CANCEL;
                    }
                    else
                    {
                        iAdvancedOp--;
                        if (iAdvancedOp < 0)
                            iAdvancedOp = ADVANCED_OP_REBOOT;
                    }
                }
            }

            int iResult;
            switch (iAdvancedOp)
            {
                case ADVANCED_OP_CANCEL:
                    return;

                case ADVANCED_OP_CLEAR_CHANNEL:
                    iResult = GetNumber(iCLEAR_CHANNEL_THRESHOLD, "CLEAR",
EEPROM_CLEAR_CHANNEL_THRESHOLD);
                    if (iResult > 0)
                        iCLEAR_CHANNEL_THRESHOLD = iResult;
            }
        }
    }
}

```

```

        break;

    case ADVANCED_OP_RED_CHANNEL:
        iResult = GetNumber(iRED_CHANNEL_THRESHOLD, "RED",
EEPROM_RED_CHANNEL_THRESHOLD);
        if (iResult > 0)
            iRED_CHANNEL_THRESHOLD = iResult;
        break;

    case ADVANCED_OP_BLUE_CHANNEL:
        iResult = GetNumber(iBLUE_CHANNEL_THRESHOLD, "BLUE",
EEPROM_BLUE_CHANNEL_THRESHOLD);
        if (iResult > 0)
            iBLUE_CHANNEL_THRESHOLD = iResult;
        break;

    case ADVANCED_OP_AUTO_CHANNEL:
        if (sDNASequence[0] == '\0')
        {
            lcd.setCursor(0, 0);
            lcd.print(F("SCAN TEST LEGOS!"));
            lcd.setCursor(0, 1);
            lcd.print(F("PUSH BUTTON      "));
            while (GetButtonPressed() == false)
            {
                delay(100);
            }
            break;
        }
        if (GetYesOrNo(false, "SCAN YYRRBBGGYY?"))
        {
            char sTemp[17] = "";
            sprintf(sTemp,"C%d R%d B%d",iCLEAR_CHANNEL_THRESHOLD,
iRED_CHANNEL_THRESHOLD,iBLUE_CHANNEL_THRESHOLD);
            lcd.setCursor(0, 0);
            lcd.print(F("CURRENT CHANNELS"));
            lcd.setCursor(0, 1);
            lcd.print(F("          "));
            lcd.setCursor(0, 1);
            lcd.print(sTemp);
            while (GetButtonPressed() == false)
            {
                delay(100);
            }
            int iClear = iBrickSequencing[0][3];
            int iRed = iBrickSequencing[2][0];
            int iBlue = iBrickSequencing[4][2];
            if (iBrickSequencing[1][3] < iClear)
                iClear = iBrickSequencing[1][3];
        }
    }
}

```

```

    if (iBrickSequencing[3][0] < iRed)
        iRed = iBrickSequencing[3][0];
    if (iBrickSequencing[5][2] < iBlue)
        iBlue = iBrickSequencing[5][2];
    iClear = iClear - ((iClear * 1)/10);
    iRed = iRed - ((iRed * 1)/10);
    iBlue = iBlue - ((iBlue * 1)/10);
    sprintf(sTemp,"C%d R%d B%d?", iClear, iRed, iBlue);
    if (GetYesOrNo(false, sTemp))
    {
        iCLEAR_CHANNEL_THRESHOLD = iClear;
        iRED_CHANNEL_THRESHOLD = iRed;
        iBLUE_CHANNEL_THRESHOLD = iBlue;
        writeUnsignedIntIntoEEPROM(EEPROM_CLEAR_CHANNEL_THRESHOLD,
iCLEAR_CHANNEL_THRESHOLD);
        writeUnsignedIntIntoEEPROM(EEPROM_RED_CHANNEL_THRESHOLD,
iRED_CHANNEL_THRESHOLD);
        writeUnsignedIntIntoEEPROM(EEPROM_BLUE_CHANNEL_THRESHOLD,
iBLUE_CHANNEL_THRESHOLD);
    }
}
break;

case ADVANCED_OP_AUTO_POSITION:
{
    lcd.setCursor(0, 0);
    lcd.print(F("USE TEST LEGO      "));
    lcd.setCursor(0, 1);
    lcd.print(F(" Push Button      "));
    while (GetButtonPressed() == false)
    {
        delay(100);
    }
    // Advance 25 steps at a time until red found and then red lost
    lcd.setCursor(0, 0);
    lcd.print(F("AUTO POSITIONING"));
    lcd.setCursor(0, 1);
    lcd.print(F("      "));

    tcs.setInterrupt(false);
    digitalWrite (LED_TCS34725, HIGH);

    MoveTray(OFFSET_TO_FIRST_BRICK);
    MoveTray(STEPS_PER_LEGOTRICK);

    iStepPosition = 0;
    bool bWaitingForRED = true;
    int iStartPositionRED = 0;
    int iEndPositionRED = 0;
}

```

```

        while (iStepPosition < 4000)
        {
            MoveTray(STEPS_PER_AUTO_POSITION);
            lcd.setCursor(0, 1);
            char cColor = GetLEGOColor(0);
            if (bWaitingForRED == true &&
                cColor == RED)
            {
                //Serial.print("RED = "); Serial.println(iStepPosition);
                iStartPositionRED = iStepPosition;
                bWaitingForRED = false;
            }
            else
                if (bWaitingForRED == false &&
                    cColor != RED)
                {
                    //Serial.print("BLUE = "); Serial.println(iStepPosition);
                    iEndPositionRED = iStepPosition;
                    break;
                }
            }
            tcs.setInterrupt(true);
            digitalWrite (LED_TCS34725, LOW);

            if (iStartPositionRED == 0 || iEndPositionRED == 0)
            {
                lcd.setCursor(0, 0);
                lcd.print(F("AUTO POSITIONING"));
                lcd.setCursor(0, 1);
                lcd.print(F("    FAILURE      "));
                while (GetButtonPressed() == false)
                {
                    delay(100);
                }
                break;
            }
            else
            {
                int iSecondREDStart = (iEndPositionRED + iStartPositionRED)/2;
                //Serial.print("2nd RED = "); Serial.println(iSecondREDStart);
                MoveTray(iSecondREDStart-iStepPosition);
                int iMove = 0 - (STEPS_PER_LEGOTRICK *2);
                //Serial.print("iMove = "); Serial.println(iMove);
                iMove = iMove - OFFSET_TO_FIRST_BRICK;
                //Serial.print("iMove = "); Serial.println(iMove);
                iMove = iMove - OFFSET_AUTO_POSITION;
                //Serial.print("iMove = "); Serial.println(iMove);
                MoveTray(iMove);
            }
        }
    }
}

```

```

        break;
    }

    case ADVANCED_OP_REMOTE_LCD_ON:
        bRemoteLCDSerial = true;
        EEPROM[EEPROM_REMOTE_LCD_SERIAL] = bRemoteLCDSerial;
        re_set();
        break;

    case ADVANCED_OP_REMOTE_LCD_OFF:
        bRemoteLCDSerial = false;
        EEPROM[EEPROM_REMOTE_LCD_SERIAL] = bRemoteLCDSerial;
        re_set();
        break;

    case ADVANCED_OP_REBOOT:
        re_set();
        break;

    default:
        break;
    }
}
}

char GetNextChar(int index)
{
    int iCurrentCharIndex = NMB_NAME_CHARS - 1;
    char cCurrentChar = sNameChars[NMB_NAME_CHARS - 1];

    lcd.setCursor(index, 1);
    lcd.print(cCurrentChar);

    int iCurrentCounter = iRotaryEncoder_Counter;
    while (GetButtonPressed() == false)
    {
        if (CheckRotaryEncoder())
        {
            if (iCurrentCounter != iRotaryEncoder_Counter)
            {
                if (iRotaryEncoder_Counter > iCurrentCounter)
                {
                    iCurrentCharIndex = iCurrentCharIndex + (iRotaryEncoder_Counter -
iCurrentCounter);
                    if (iCurrentCharIndex >= NMB_NAME_CHARS)
                        iCurrentCharIndex = 0;
                }
                else

```

```

    {
        iCurrentCharIndex = iCurrentCharIndex - (iCurrentCounter -
iRotaryEncoder_Counter);
        if (iCurrentCharIndex < 0)
            iCurrentCharIndex = NMB_NAME_CHARS - 1;
    }
    lcd.setCursor(index, 1);
    cCurrentChar = sNameChars[iCurrentCharIndex];
    lcd.print(cCurrentChar);
    iCurrentCounter = iRotaryEncoder_Counter;
}
}

if (cCurrentChar == '*')
    cCurrentChar = '\0';
return (cCurrentChar);
}

char GetNextNumber(int index)
{
    int iCurrentCharIndex = NMB_NUMBER_CHARS - 1;
    char cCurrentChar = sNumberChars[NMB_NUMBER_CHARS - 1];

    lcd.setCursor(index, 1);
    lcd.print(cCurrentChar);

    int iCurrentCounter = iRotaryEncoder_Counter;
    while (GetButtonPressed() == false)
    {
        if (CheckRotaryEncoder())
        {
            if (iCurrentCounter != iRotaryEncoder_Counter)
            {
                if (iRotaryEncoder_Counter > iCurrentCounter)
                {
                    iCurrentCharIndex = iCurrentCharIndex + (iRotaryEncoder_Counter -
iCurrentCounter);
                    if (iCurrentCharIndex >= NMB_NUMBER_CHARS)
                        iCurrentCharIndex = 0;
                }
                else
                {
                    iCurrentCharIndex = iCurrentCharIndex - (iCurrentCounter -
iRotaryEncoder_Counter);
                    if (iCurrentCharIndex < 0)
                        iCurrentCharIndex = NMB_NUMBER_CHARS - 1;
                }
            }
            lcd.setCursor(index, 1);
            cCurrentChar = sNumberChars[iCurrentCharIndex];
        }
    }
}

```

```

        lcd.print(cCurrentChar);
        iCurrentCounter = iRotaryEncoder_Counter;
    }
}
}

if (cCurrentChar == '*')
    cCurrentChar = '\0';
return (cCurrentChar);
}

void Beeps(int iNmbBeeps, int iMSLengthON, int iMSLengthOFF)
{
    if (bBuzzer == false)
        return;

    for (int i = 0; i < iNmbBeeps; i++)
    {
        digitalWrite(BUZZER, HIGH);
        delay(iMSLengthON); //wait for 1ms
        digitalWrite(BUZZER, LOW);
        delay(iMSLengthOFF); //wait for 1ms
    }
}

void MoveTray(int iSteps)
{
    iStepPosition = iStepPosition + iSteps;
    myStepper.step(iSteps);
}

#if 0
void TestNameEntry()
{
    Serial.println(F("Add to Database!"));
    lcd.setCursor(0, 0);
    lcd.print(F("Name: "));
    lcd.write((byte) 0xff);
    lcd.print(F(" to end "));
    lcd.setCursor(0, 1);
    lcd.print(F(""));

    char sNewName[17] = "";
    char cNextChar;

    int index = 0;
    while (index < 16)
    {
        cNextChar = GetNextChar(index);
        if (cNextChar == '\0')

```

```

{
    break;
}
if (cNextChar == '<')
{
    if (index > 0)
    {
        lcd.setCursor(index, 1);
        lcd.print(' ');
        index = index - 1;
        continue;
    }
}
sNewName[index] = cNextChar;
index = index + 1;
sNewName[index] = '\0';
}
for (; index < 16; index++)
{
    sNewName[index] = ' ';
}
sNewName[16] = '\0';
Serial.println(sNewName);
}
#endif

bool F_RemoteLCDSerial(const __FlashStringHelper *lcd1, const
__FlashStringHelper *lcd2)
{
    if (bRemoteLCDSerial == false)
        return (false);

    Serial.print('[');
    Serial.print(lcd1);
    Serial.println("");
    Serial.print(lcd2);
    Serial.print(']');
}

bool RemoteLCDSerial(char *lcd1, char *lcd2)
{
    if (bRemoteLCDSerial == false)
        return (false);

    Serial.print('[');
    Serial.print(lcd1);
    Serial.println("");
    Serial.print(lcd2);
    Serial.print(']');
}

```

}

# Remote LCD Python Source Code

There are two versions of the Remote LCD program which use different GUI libraries:

## RemoteLCD\_PySimpleGUI

```
"""
*****
RemoteLCD_PySimpleGUI
The purpose of this Python program is to remotely display the
contents of an Arduino 1602 LCD. It was created to facilitate
a large group of persons watching the LEGO DNA Sequencer.

Original Code: 2023-01-08
Revision:      2022-01-10

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*****
"""

Program = "RemoteLCD_PySimpleGUI"
Version = "Ver 0.3"
RevisionDate = "2023-01-16"

import sys
import os
import time
import serial
import argparse
from types import NoneType
import PySimpleGUI as sg

def getbackgroundcolor(x):
    if chr(x) == 'A':
        return 'green'
    if chr(x) == 'C':
        return 'yellow'
```

```

if chr(x) == 'G':
    return 'red'
if chr(x) == 'T':
    return 'blue'

def gettextcolor(x):
    if chr(x) == 'C':
        return 'black'
    else:
        return 'white'

print (Program, Version, RevisionDate)

parser = argparse.ArgumentParser("RemoteLCD")
parser.add_argument('--comport', type=str, required=False, help="COM port")
parser.add_argument('--showports', required=False, choices=('True','False'))
args = parser.parse_args()

if type(args.showports) is not NoneType:
    os.system("python -m serial.tools.list_ports")
    exit(0)

if type(args.comport) is NoneType:
    print ("--comport <COMPORT> is required!")
    print ("--showports True will show available comports")
    exit(1)

print ("Connecting to LEGO DNA Sequencer on Arduino on Port",args.comport)

SerialObj = serial.Serial(args.comport) # COMxx format on Windows
#SerialObj = serial.Serial('COM4') # COMxx format on Windows
#                         # ttyUSBx format on Linux

SerialObj.baudrate = 115200 # set Baud rate to 9600
SerialObj.bytesize = 8      # Number of data bits = 8
SerialObj.parity   ='N'     # No parity
SerialObj.stopbits = 1      # Number of Stop bits = 1

sg.theme('Black')
layout = [ [sg.Text('LEGO DNA Sqncr', font=("Courier",120), key='LINE1')],
           [sg.Text(' Push Button', font=("Courier",120), key='LINE2'),
            sg.Text(' ', font=("Courier",120), key='LINE2-COL0'),
            sg.Text(' ', font=("Courier",120), key='LINE2-COL1'),
            sg.Text(' ', font=("Courier",120), key='LINE2-COL2'),
            sg.Text(' ', font=("Courier",120), key='LINE2-COL3'),
            sg.Text(' ', font=("Courier",120), key='LINE2-COL4'),
            sg.Text(' ', font=("Courier",120), key='LINE2-COL5'),
            sg.Text(' ', font=("Courier",120), key='LINE2-COL6')]
```

```

        sg.Text(' ', font=("Courier",120), key='LINE2-COL7'),
        sg.Text(' ', font=("Courier",120), key='LINE2-COL8'),
        sg.Text(' ', font=("Courier",120), key='LINE2-COL9'),
        sg.Text(' ', font=("Courier",120), key='LINE2-COL10'),
        sg.Text(' ', font=("Courier",120), key='LINE2-COL11'),
        sg.Text(' ', font=("Courier",120), key='LINE2-COL12'),
        sg.Text(' ', font=("Courier",120), key='LINE2-COL13'),
        sg.Text(' ', font=("Courier",120), key='LINE2-COL14'),
        sg.Text(' ', font=("Courier",120), key='LINE2-COL15')]
    ]

# Create the Window
window = sg.Window('LEGO DNA Sequencer', layout, margins=(50,250)).Finalize()
window.Maximize()

# Event Loop to process "events"
while True:
    event, values = window.read(timeout=10)
    if event == sg.WIN_CLOSED: # if user closes window
        break
    if SerialObj.in_waiting != 0:
        letter = SerialObj.read()
        if letter == b'[':
            lcd1 = SerialObj.read(16)
            SerialObj.read(2)    #Ignore the '\r\n'
            lcd2 = SerialObj.read(16)
            SerialObj.read(1)    #Ignore the ']'
            window['LINE1'].update(str(lcd1, 'UTF-8'))
            if str(lcd1, 'UTF-8') == "Sequencing DNA " or str(lcd1, 'UTF-8') == "Unloading tray ":
                window['LINE2'].update(' ')
                for x in range(10):
                    window['LINE2-COL'+str(x)].update(background_color='black')
                    window['LINE2-COL'+str(x)].update(' ')
                n = range(10, 16)
                for x in n:
                    window['LINE2-COL'+str(x)].update(background_color='black')
                    window['LINE2-COL'+str(x)].update(' ')
                for x in range(10):
                    backgroundcolor = getbackgroundcolor(lcd2[x])
                    window['LINE2-COL'+str(x)].update(background_color=backgroundcolor)
                    textcolor = gettextcolor(lcd2[x])
                    window['LINE2-COL'+str(x)].update(text_color=textcolor)
                    window['LINE2-COL'+str(x)].update(font=("Courier",120, 'bold'))
                    window['LINE2-COL'+str(x)].update(chr(lcd2[x]))
            else:
                window['LINE2'].update(background_color='black')

```

```
    window['LINE2'].update(text_color='white')
    window['LINE2'].update(font=("Courier",120, 'normal'))
    window['LINE2'].update(str(lcd2, 'UTF-8')+'      ')
window.close()
```

## RemoteLCD\_tkinter

```
"""
*****  
RemoteLCD_tkinter  
The purpose of this Python program is to remotely display the  
contents of an Arduino 1602 LCD. It was created to facilitate  
a large group of persons watching the LEGO DNA Sequencer.  
  
Original Code: 2023-01-08  
Revision:      2022-01-10  
  
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Mentor, Circuit Design & Software  
Miller Library, Fabrication Lab  
Hopkins Marine Station, Stanford University,  
120 Ocean View Blvd, Pacific Grove, CA 93950  
+1 831.915.9526 | rolander@stanford.edu  
*****/  
  
"""  
Program = "RemoteLCD_tkinter"  
Version = "Ver 0.1"  
RevisionDate = "2023-01-10"  
  
import sys  
import os  
import tkinter as tk  
import time  
import serial  
import argparse  
from types import NoneType  
  
  
def Draw():  
    global text  
    frame=tk.Frame(root,bd=1)  
    frame.place(x=10,y=10)  
    frame.pack(side="left")  
    text=tk.Label(frame,text='', font=("Courier", 120))  
    text.pack()  
    text.configure(text=" Welcome\n LEGO DNA Sqncr")  
  
def Refresher():  
    global text
```

```

if SerialObj.in_waiting != 0:
    letter = SerialObj.read()
    if letter == b'[':
        lcd1 = SerialObj.read(16)
        SerialObj.read(2)    #Ignore the '\r\n'
        lcd2 = SerialObj.read(16)
        SerialObj.read(1)    #Ignore the ']'
        #text.configure(text="0123456789012345\n" + time.asctime())
        text.configure(text= "  " + str(lcd1, 'UTF-8') + "\n  " + str(lcd2,
'UTF-8'))
        #text.configure(text= lcd1 + "\n" + lcd2)
    root.after(1000, Refresher) # every second...

print (Program, Version, RevisionDate)

parser = argparse.ArgumentParser("RemoteLCD")
parser.add_argument('--comport', type=str, required=False, help="COM port")
parser.add_argument('--showports', required=False, choices=('True', 'False'))
args = parser.parse_args()

if type(args.showports) is not NoneType:
    os.system("python -m serial.tools.list_ports")
    exit(0)

if type(args.comport) is NoneType:
    print ("--comport <COMPORT> is required!")
    print ("--showports True will show available comports")
    exit(1)

print ("Connecting to LEGO DNA Sequencer on Arduino on Port",args.comport)

SerialObj = serial.Serial(args.comport) # COMxx format on Windows

#SerialObj = serial.Serial('COM4') # COMxx format on Windows
#                         # ttyUSBx format on Linux

SerialObj.baudrate = 115200 # set Baud rate to 9600
SerialObj.bytesize = 8      # Number of data bits = 8
SerialObj.parity   ='N'     # No parity
SerialObj.stopbits = 1      # Number of Stop bits = 1

root=tk.Tk()
root.title("LEGO DNA Sequencer")
root.geometry("1540x340")
root.attributes('-fullscreen', True)
label = tk.Label(root, text=" LEGO DNA Sequencer -- Remote LCD ",
font=("Courier", 48), bg="black", fg="white")
label.pack()

```

```
Draw()  
Refresher()  
root.mainloop()
```

## Credits

This project has been clearly inspired by the LEGO DNA Sequencer created by Sam Nicholls and Tom Blanchard at [Monster DNA Lab](#). It is a very well conceived open source project.

Peter Shum was a Post Doc at the Hopkins Marine Station of Stanford University and implemented the [MonsterLab Sequencer](#) for a Hopkins Open House Day in 2018.

Dr. Amanda Whitmire is the Head Librarian & Bibliographer of the Miller Library at the Hopkins Marine Station and has provided the facilities of her Fabrication Lab for this project.