

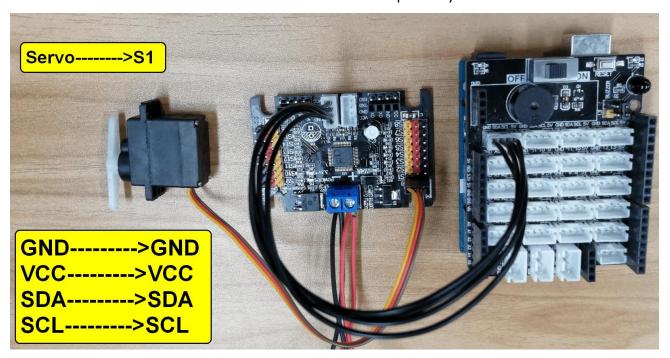
IIC control servo

1. Learning goals

In this course, we mainly learn to use Arduino and 16-channel servo debugging board to control the servo through IIC.

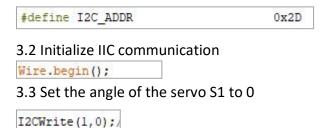
2. Preparation

Connect the SDA and SCL of the module to the SDA and SCL pins of the arduino UNO board. VCC and GND are connected to 5V and GND of Arduino UNO respectively. As shown below.



3. About code

3.1 Configure module address



4. Compiling and downloading code

4.1 We need to open the **.ino** file by Arduino IDE software. Then click"\footnot" under the menu bar to compile the code, and wait for the word "Done compiling" in the lower left corner, as shown in the figure below.

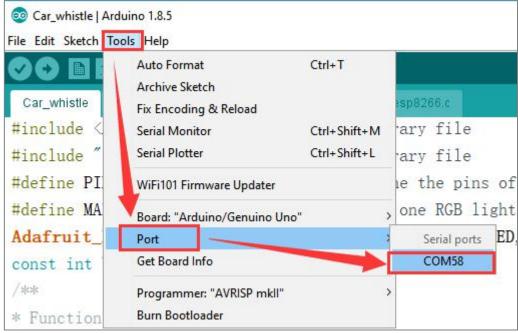


```
File Edit Sketch Tools Help
TM1650.cpp TM1650.h
 pattern_digital_display
  delay (ZUUU);
  if (d. displayRunning("1234567890abcdefg")) {
    while (d.displayRunningShift()) delay(500);
  delay (2000);
  for (int i = 0; i < 20; i++) {
    d. displayOff();
    delay (200);
    d. displayOn();
    delay(200);
  }
Done compiling.
Sketch uses 4596 bytes (14%) of program storage space. Maximum is 32256 bytes.
Global variables use 718 bytes (35%) of dynamic memory, leaving 1330 bytes for local
```

4.2 In the menu bar of Arduino IDE, we need to select 【Tools】---【Port】--- selecting the port that the serial number displayed by the device manager just now, as shown in the figure below.







4.3 After the selection is completed, you need to click "→"under the menu bar to upload the code to the UNO board. When the word "Done uploading" appears in the lower left corner, the code has been successfully uploaded to the UNO board, as shown in the figure below.



```
Car_sing | Arduino 1.8.5

Eile Edit Sketch Tools Help

Car_sing

#include <Arduino. h> //Library file

const int buzzer = 10; //Define the pins of buzzer

/*Individual tones in the score*/

#define BL1 248

#define BL2 278

#define BL3 294

#define BL4 330

#define BL5 371

#dofine RL6 416

Done uploading
```

5. Phenomenon

After the program is downloaded successfully. The servo will rotate 0°, after 2s it will rotate 180°, after 2s servo will rotate 0°, keep the loop like this status.