structure of Joky code

🔧 Tec Joky Embedded Software Workflow

Type	Step	Description
Start	System Init	Initialize peripherals, timers, LoRa, and system state
Foreground	Timer Interrupt (every 5 sec)	Periodic interrupt for battery monitoring
	→ Read ADC	Read voltage data from ADC pin
	→ Analyze SoC	Estimate State of Charge (SoC) based on ADC reading
	→ Send SoC to RC	Transmit SoC value to remote controller (e.g., via LoRa/UART)
Background	Main Loop	Runs continuously in the background
	→ Receive LoRa Cmds	Listen for incoming commands from the remote controller
	→ Control DC Motors	Decode command and drive motors accordingly
End	Loop / End	System loops or waits for next interrupt or command

notes

- two channals adc with two analog data from current sensor and Voltage

    - to estimate soc

- the cmd receied "lora over UART "

    - "1" for one hit
    - "2" for continous hitting
    - "3" for stop motot

- the data sent from **joky** to **RC**

    - It will only a number sent as a string
    - in **RC** the data sored in an uint8_t arr[2];

- NOTE it may be a version of model a code

    - may be edited in optimization