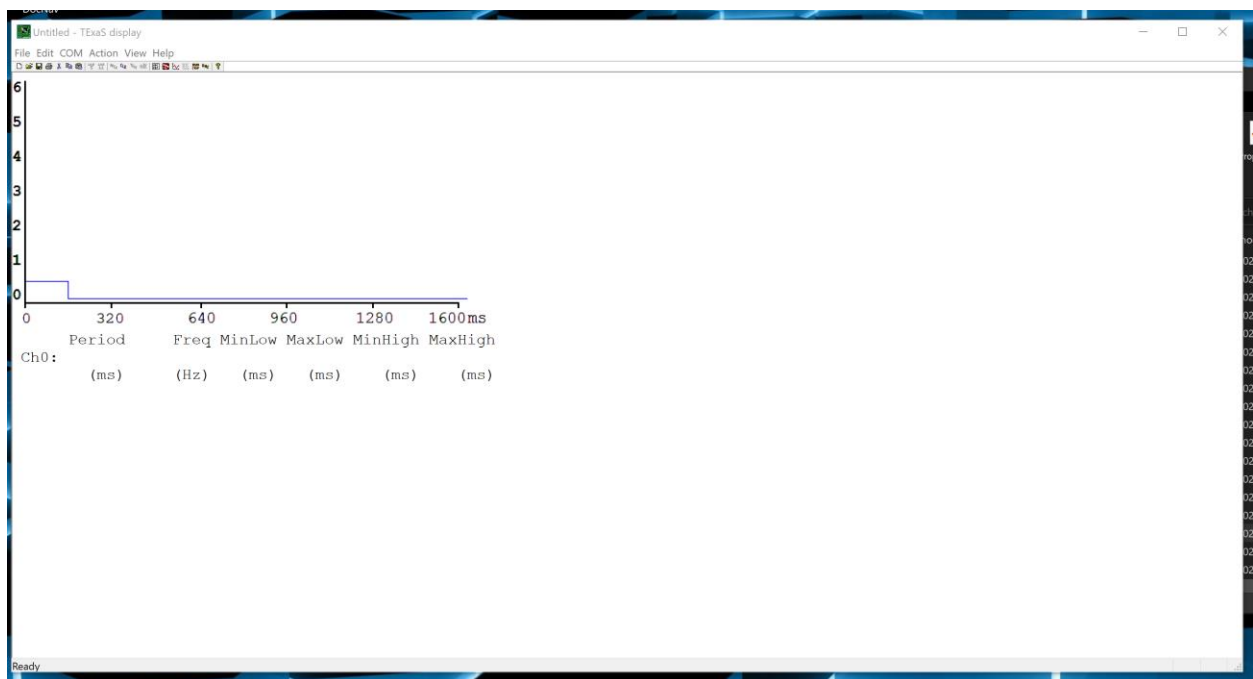
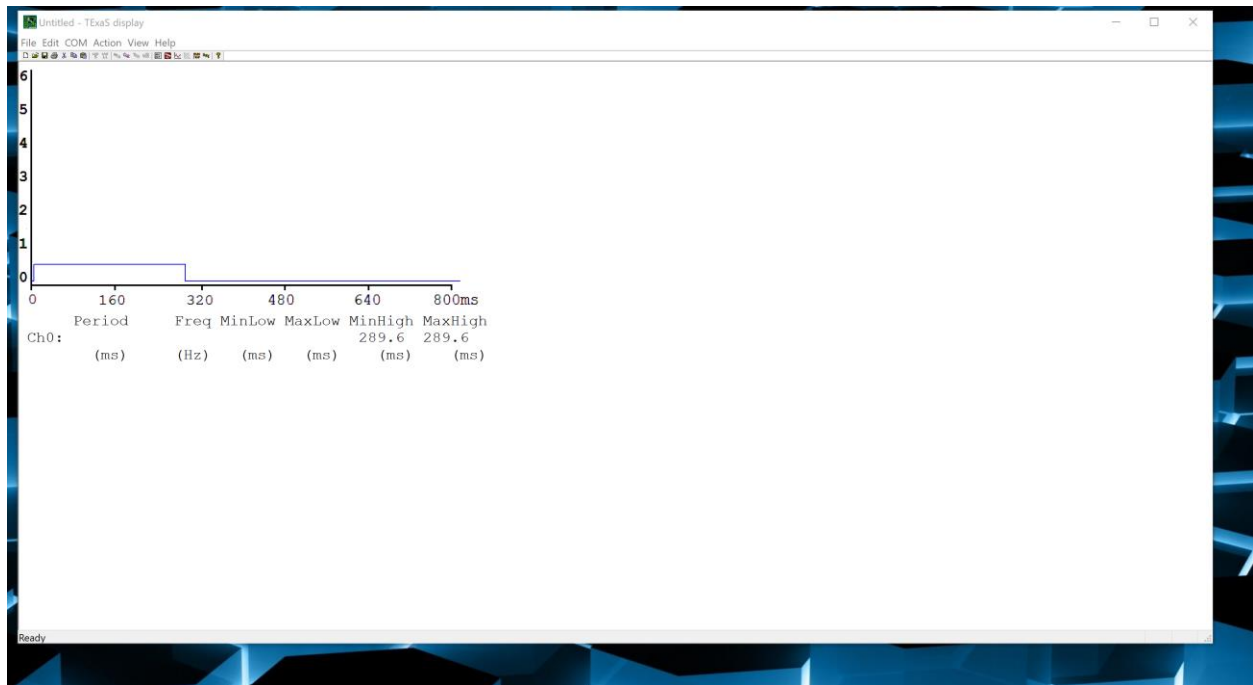


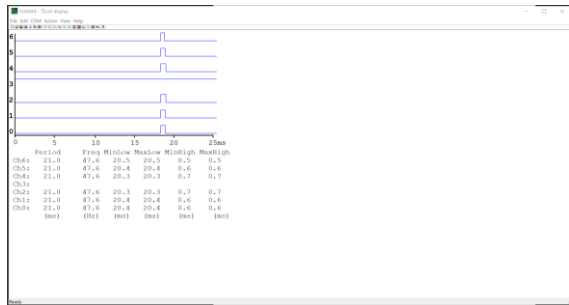
Alex Meyers – Lab 1

Black – about 280ish (320 zoomed in)

White – about 80ish. Needed to put the bottom end on 320 to be able to catch it w/ the screenshot (120 zoomed in)



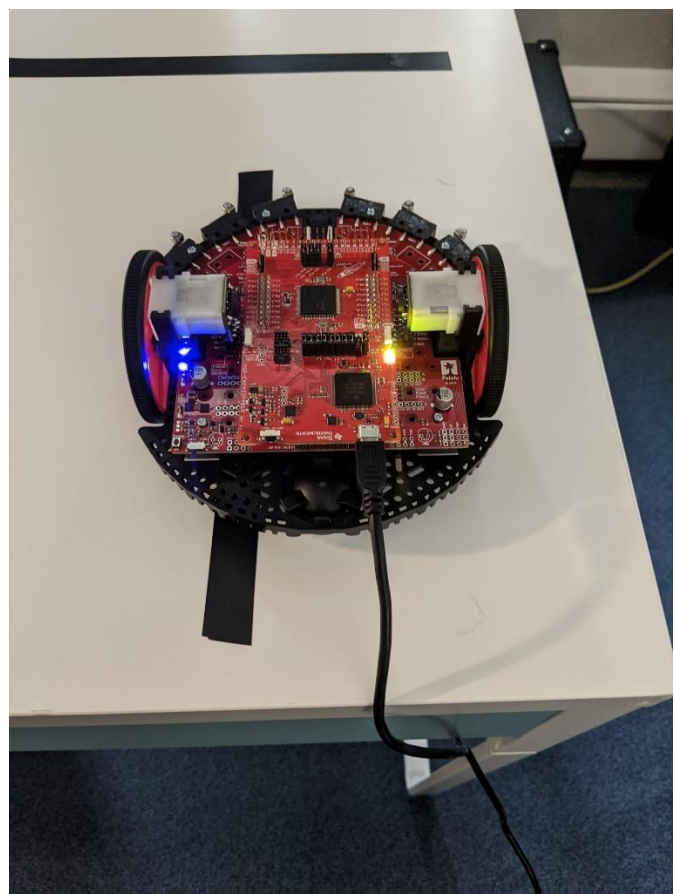
This was my initial reading before I had the battery power feeding to the sensor. After I had the battery power feeding, I ran the regular main function to get an idea of the white/black ratio.

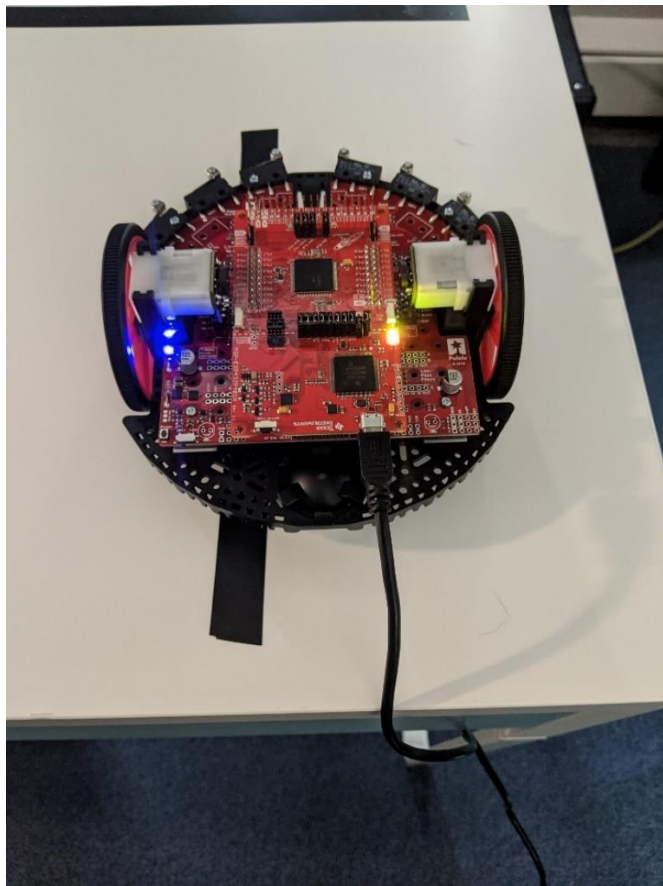
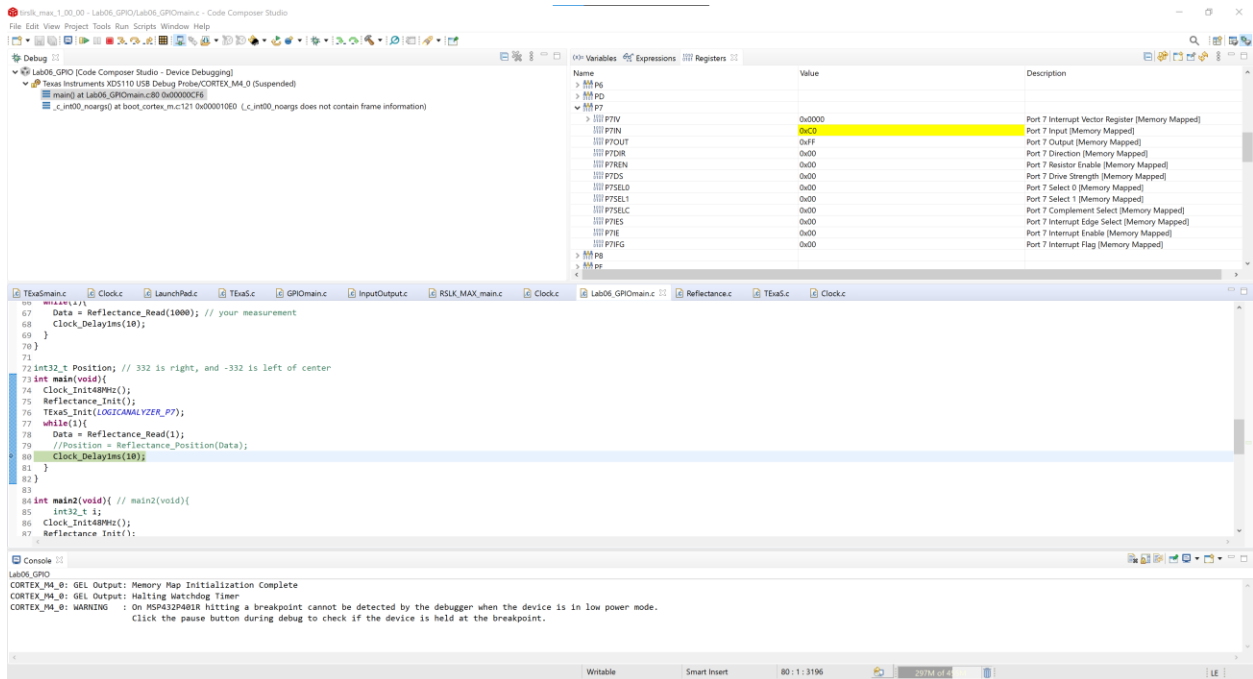


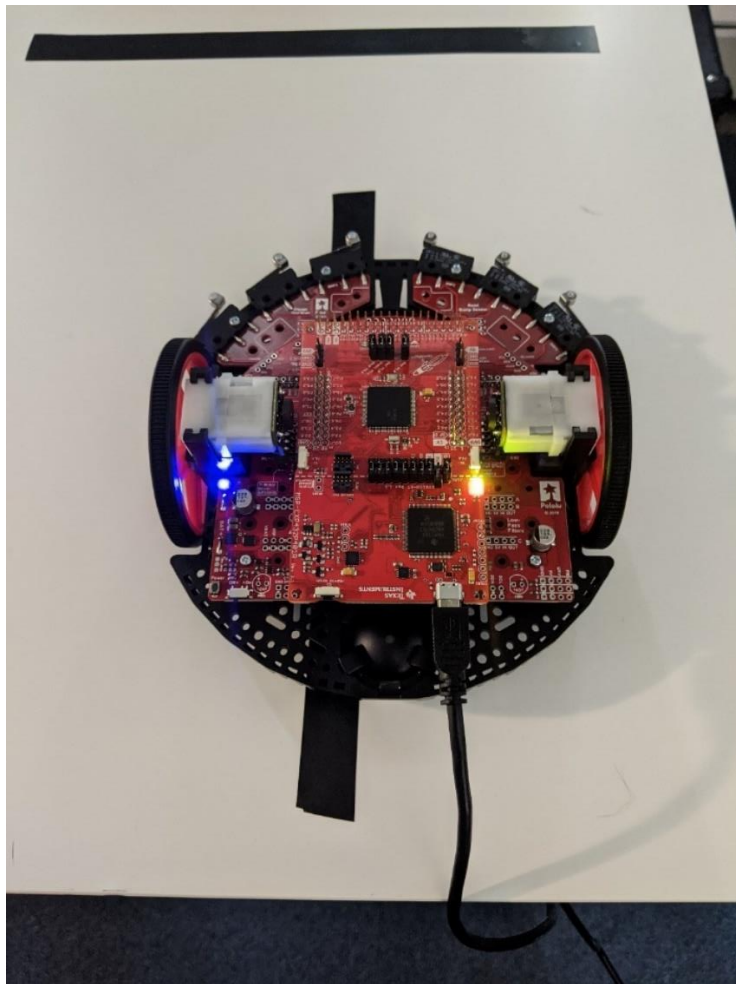
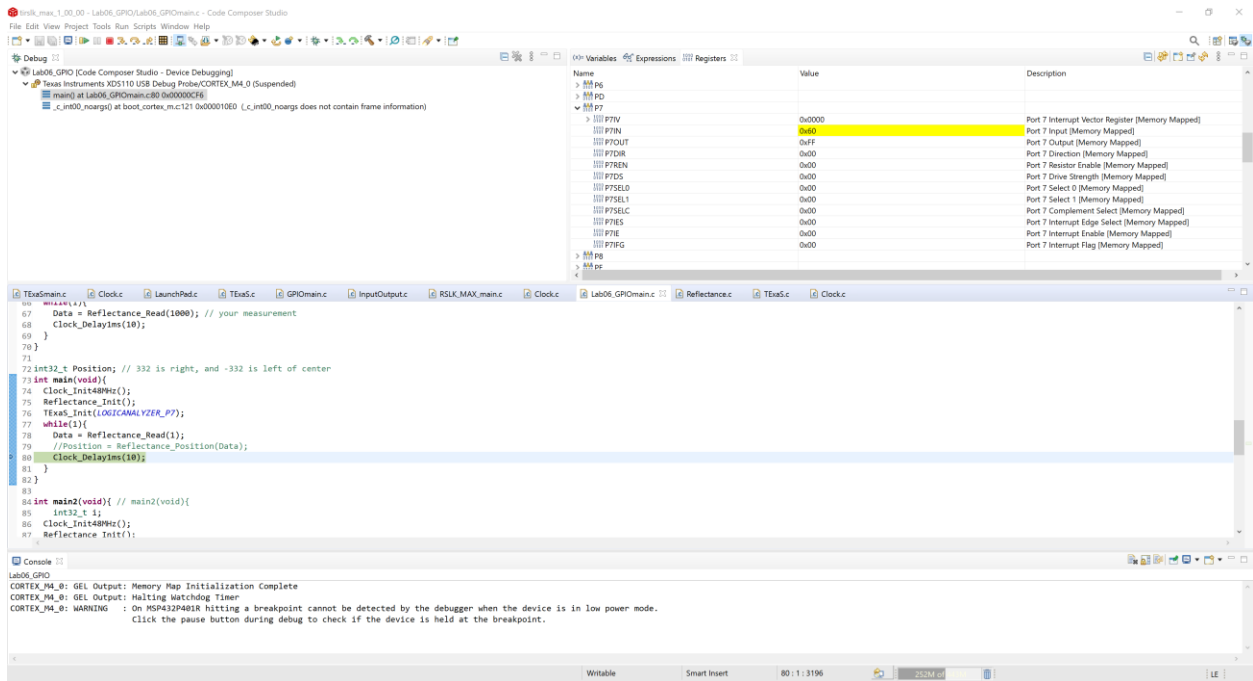
From this, I used 1ms as my value for white.



This photo was taken at the end of the experiment. Initially, it was just the vertical and horizontal pieces of tape, but at the end when I was doing the measurements, I added the piece of paper with a center line and 10, 20, and 33.4 measurements in both directions.







Code Composer Studio interface showing the debug console and registers.

Debug Console:

```

67 Data = Reflectance_Read(1000); // your measurement
68 Clock_Delayms(10);
69 }
70 }
71
72 int32_t Position; // 332 is right, and -332 is left of center
73 int main(void){
74   Clock_Init48MHz();
75   Reflectance_Init();
76   Texas_Ini(L0GICANALYZER_P7);
77   while(1){
78     Data = Reflectance_Read(1);
79     //Position = Reflectance_Position(Data);
80     Clock_Delayms(10);
81   }
82 }
83
84 int main2(void){ // main2(void){
85   int32_t i;
86   Clock_Init48MHz();
87   Reflectance_Init();

```

Registers:

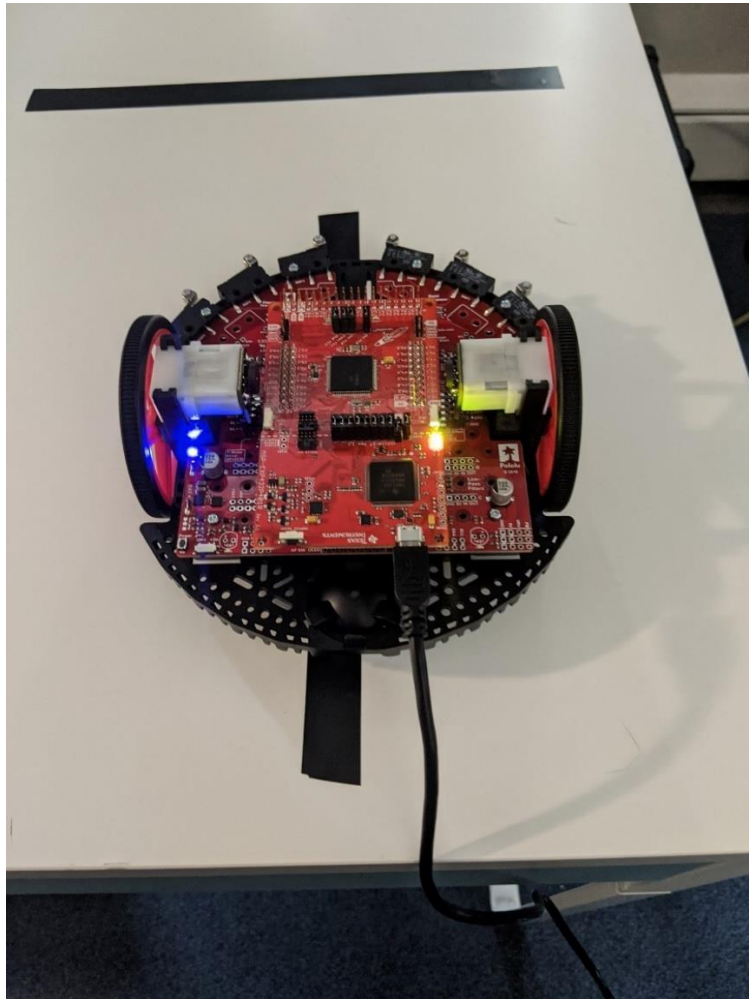
Name	Value	Description
> M0_P6		
> M0_P0		
> P7		
> P7_P7V	0x0000	Port 7 Interrupt Vector Register (Memory Mapped)
> P7_P7IN	0x00	Port 7 Input (Memory Mapped)
> P7_P7OUT	0xFF	Port 7 Output (Memory Mapped)
> P7_P7DIR	0x00	Port 7 Direction (Memory Mapped)
> P7_P7REN	0x00	Port 7 Resistor Enable (Memory Mapped)
> P7_P7DS	0x00	Port 7 Drive Strength (Memory Mapped)
> P7_P7SELO	0x00	Port 7 Select 0 (Memory Mapped)
> P7_P7SEL1	0x00	Port 7 Select 1 (Memory Mapped)
> P7_P7SELC	0x00	Port 7 Complement Select (Memory Mapped)
> P7_P7IES	0x00	Port 7 Interrupt Edge Select (Memory Mapped)
> P7_P7IE	0x00	Port 7 Interrupt Enable (Memory Mapped)
> P7_P7IFG	0x00	Port 7 Interrupt Flag (Memory Mapped)
> M0_P8		
> M0_P9		

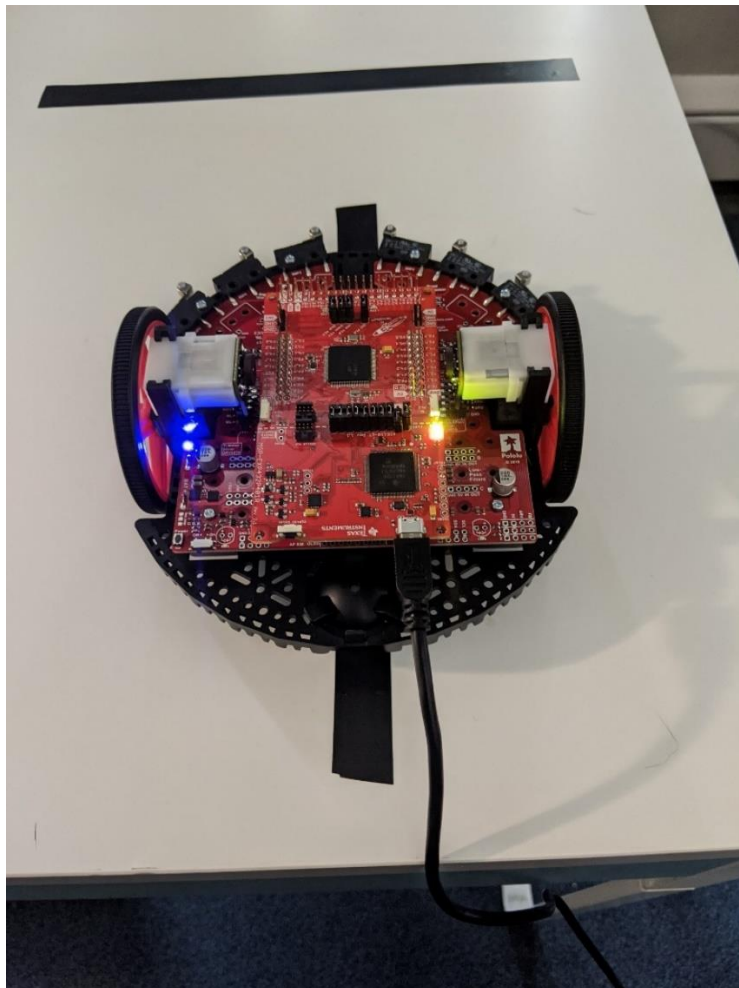
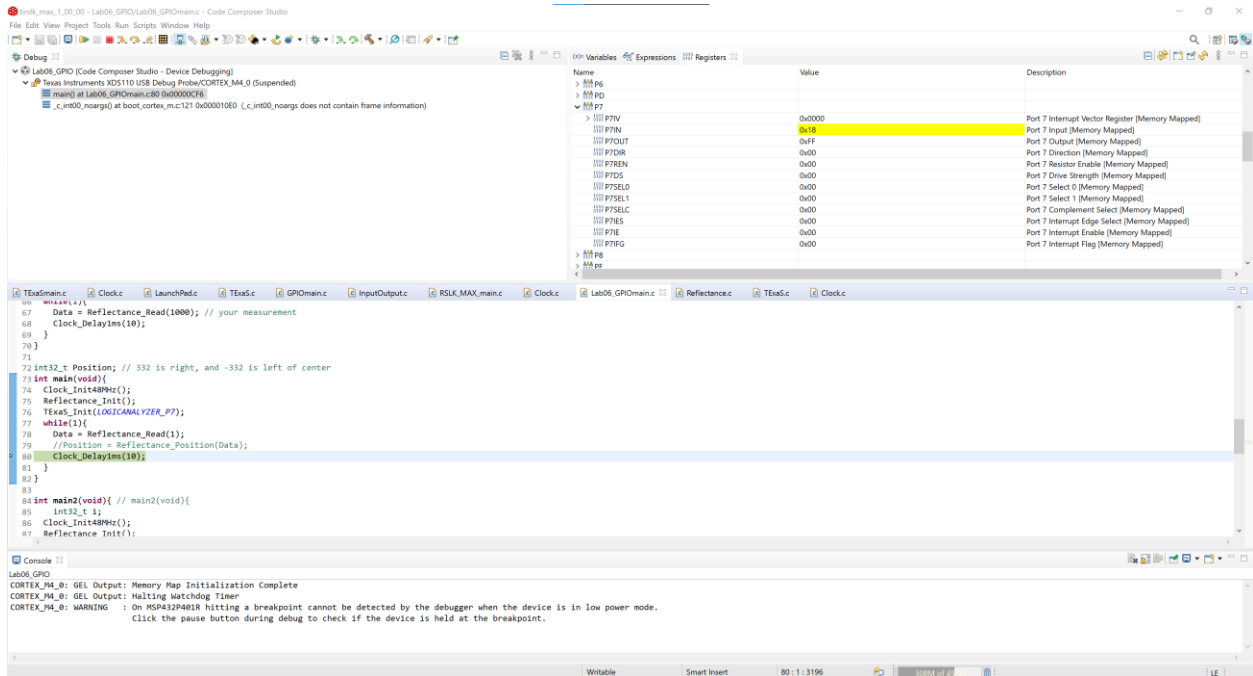
Console:

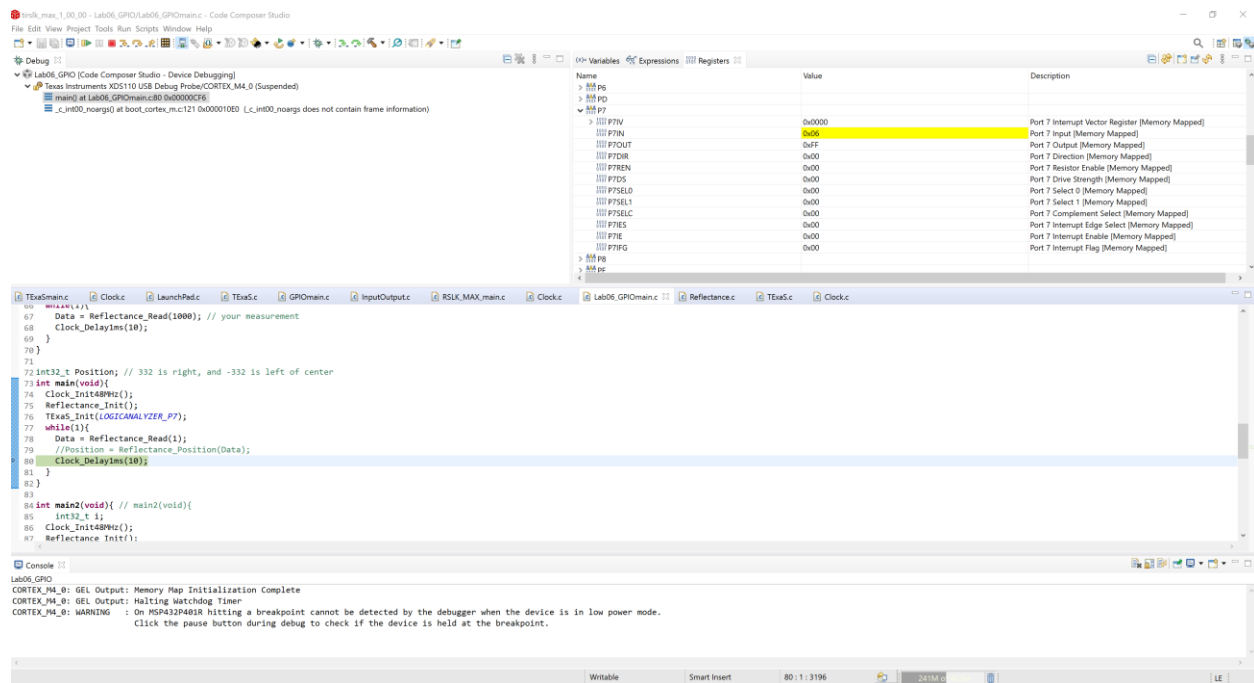
```

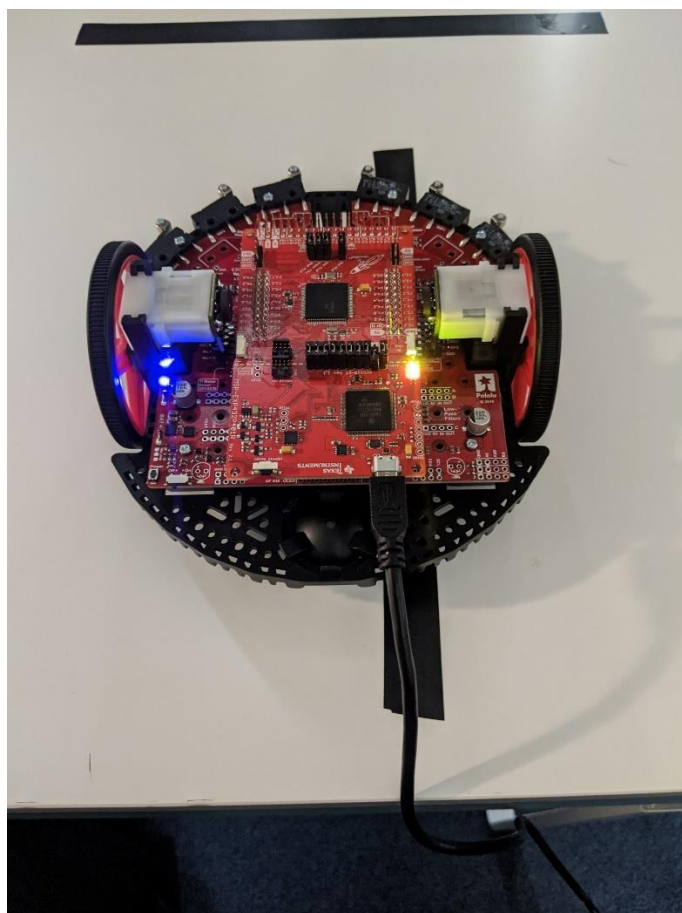
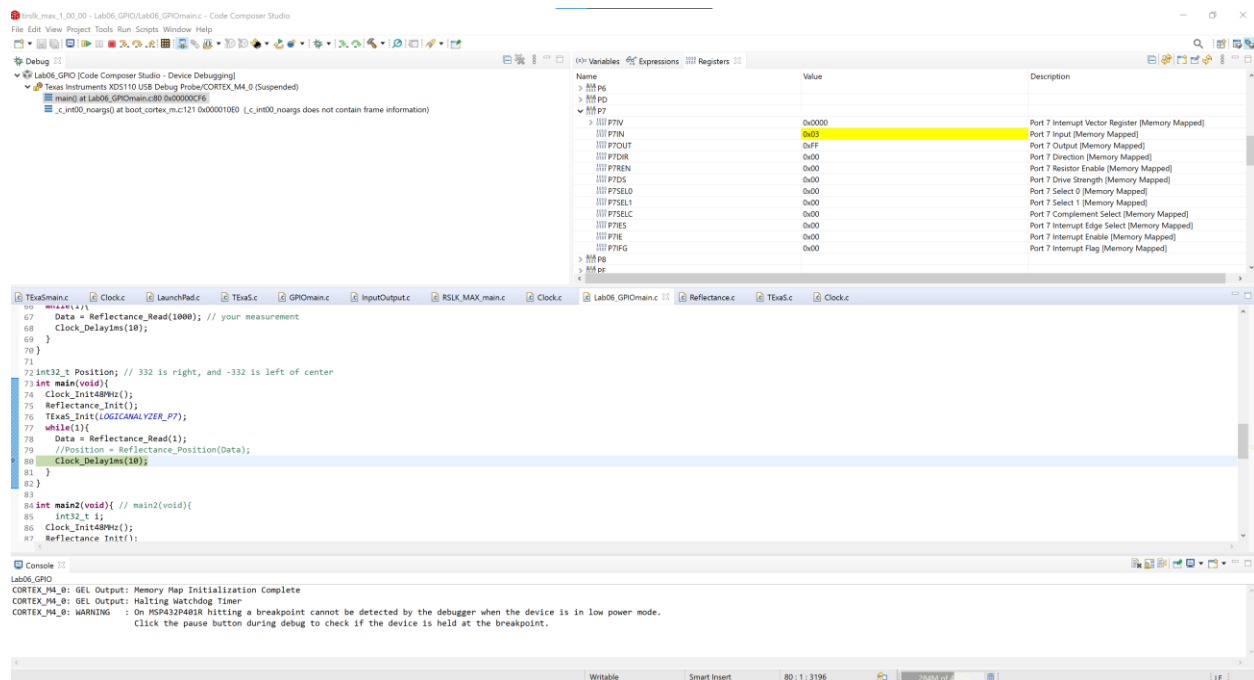
Lab06_GPIO
Cortex_M0_0: GEL Output: Memory Map Initialization Complete
Cortex_M0_0: GEL Output: Halting Watchdog Timer
Cortex_M0_0: WARNING : On MSP432P401R hitting a breakpoint cannot be detected by the debugger when the device is in low power mode.
Click the pause button during debug to check if the device is held at the breakpoint.

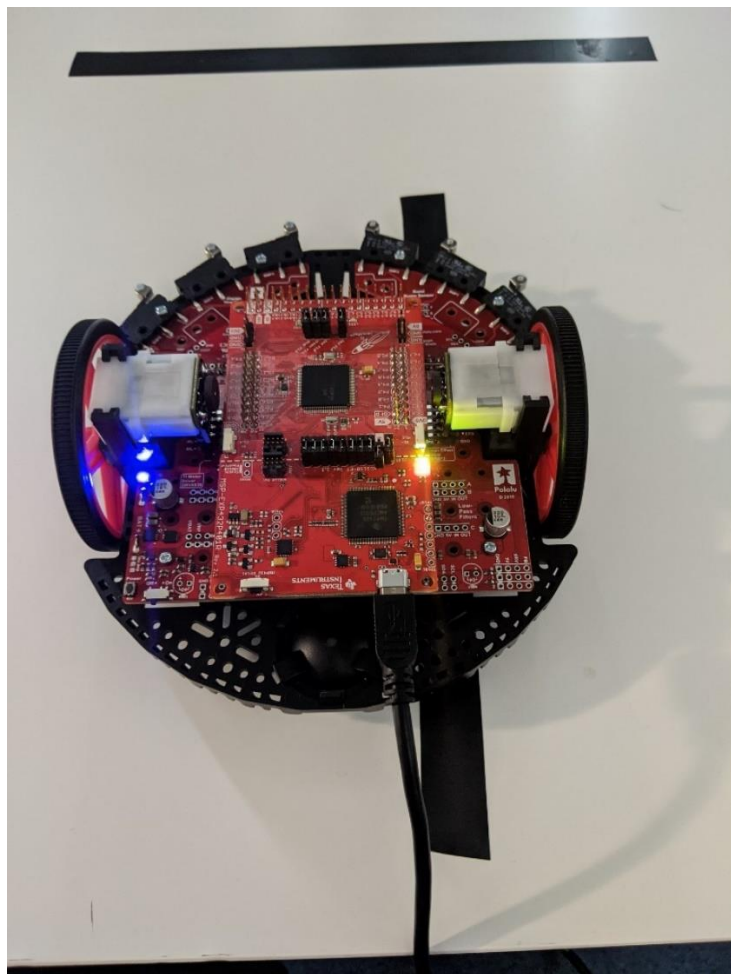
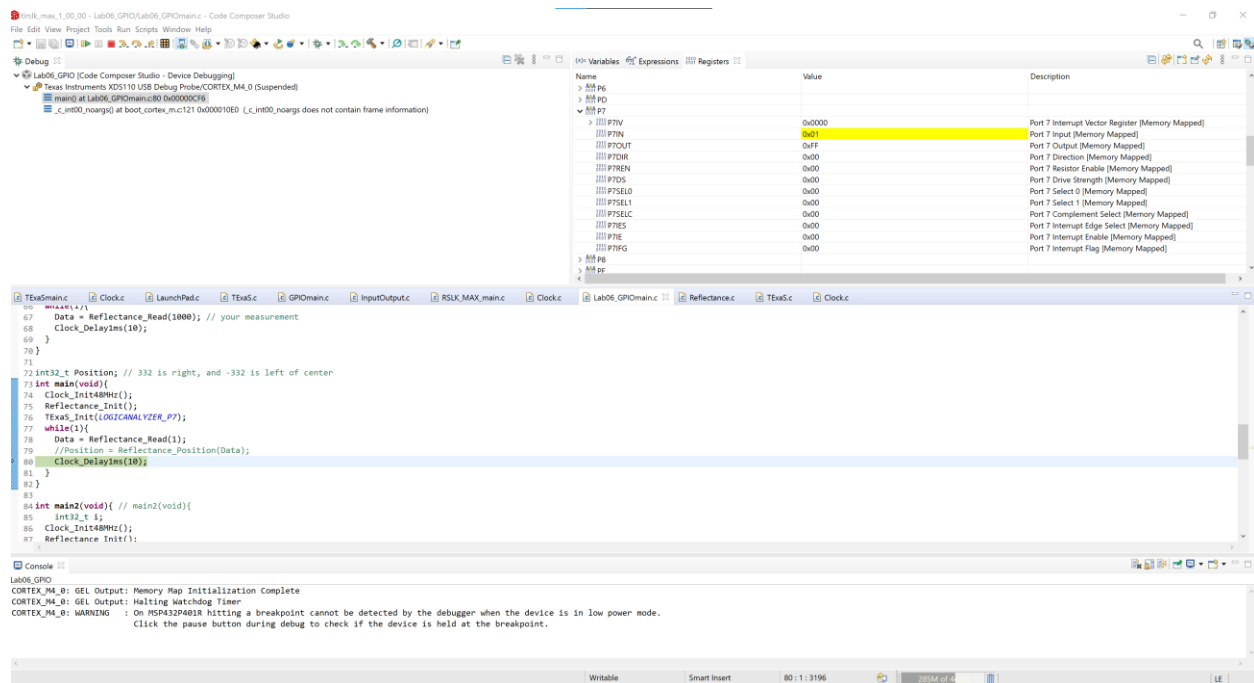
```

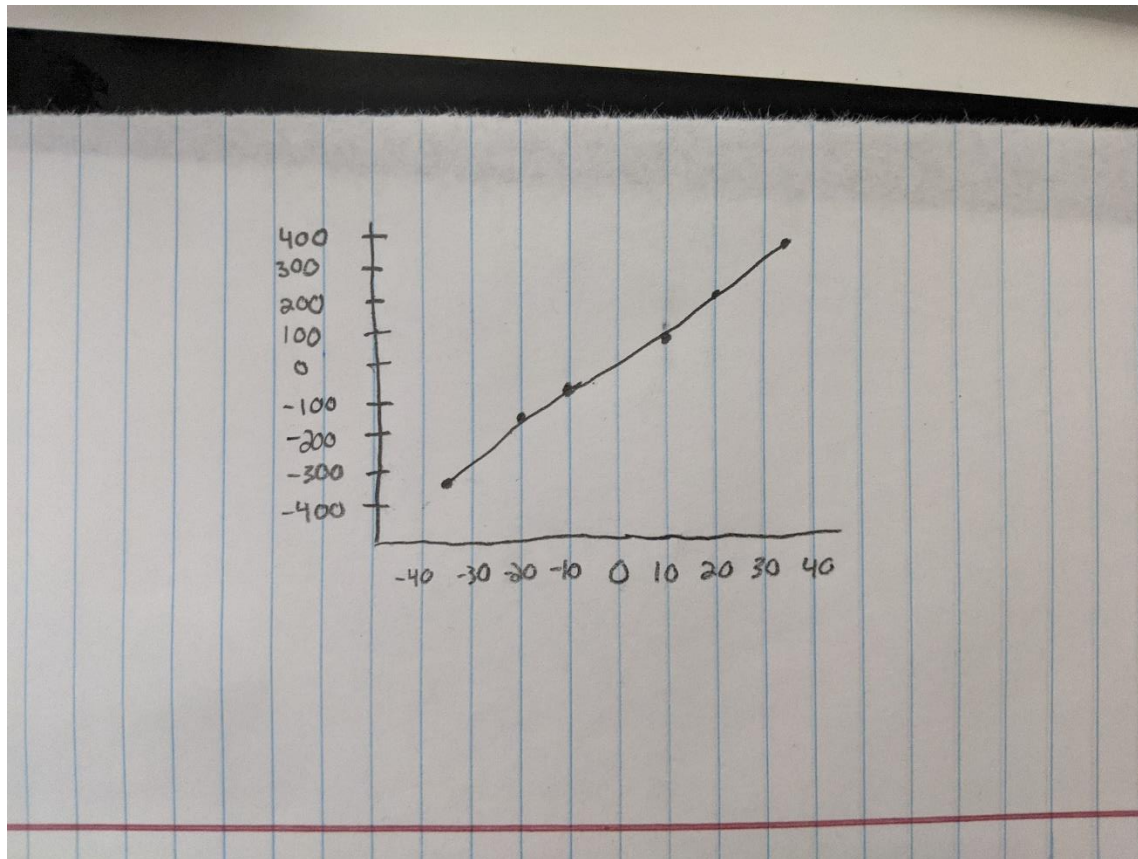












The response is monotonic, and this is important for this sensor because if it was not monotonic, as we make the adjustments to get closer to the middle, it would not respond as we want it to. The stabilization would cause hard turns and over compensation, followed by harder ones until it was thrown so far off track that it couldn't find the line again.

In my experiment, it did not seem like there was any regions of noise, but it was obvious that the sensor was rounding to its data points and not giving perfectly accurate data. This was seen when I measured 10 and 20mm from the center and was getting 9.5 and 19.0 respectively. Whenever I tried at different angles, it seemed to pick up on 2 or 3 sensors, but that will be able to be adjusted when we are driving the motors. The reason that I feel that this should be tackled later, is because if we are traveling at a hard angle, the next reading to the sensor will be further out and we will have more data points to verify that it is going a direction that is not perpendicular to the line. It is much easier to tell this with 2 data sets than just 1.