

Ch NXT Package User's Guide

Version 1.0.7



Contents

1	Introduction	1
2	Configuraing Lego Mindstorms NXT for Remote Control	2
2.1	Getting Bluetooth Addresses of NXTs	2
2.2	Adding Bluetooth Addresses of NXTs in ChNXT Controller	4
2.3	Connecting and Disconnecting to NXTs from the ChNXT Controller	6
3	Getting Started with Ch NXT Package	8
3.1	A Basic Ch NXT Program	8
3.2	Setting the Zero Positions for NXT Joints	10
3.3	Controlling the Speed of NXT Joints	11
3.4	Making NXT Joints Move	12
3.4.1	A Demo Program for Movement Functions	12
3.4.2	Blocking and Non-Blocking Functions	14
3.5	Retrieving a Joint Angle	15
3.6	Setting Sensors for NXT	16
4	Controlling a NXT Vehicle	20
4.1	How to make your NXT move forward	21
4.1.1	Initialization	21
4.1.2	Connect the NXT and Checking Connection Status	21
4.1.3	Moving the Robot Forward	22
4.1.4	Ending your program	22
4.2	How to make your NXT move backward	23
4.3	How to make your NXT turn in place left/right	23
4.4	Advance Mindstorm Motor Control	24
4.4.1	Motor Control Functions	24
4.4.2	Turning Using Single Motor Control	25
4.4.3	Manual Real Time Control Program	27
4.5	Using NXT Sensors	35
4.5.1	Using your touch sensor	35
4.5.2	Using your ultrasonic sensor	39
4.5.3	Autonomous Control Program	42
5	Controlling Non-Vehicle NXT Robots	48
5.1	Controlling NXT Machine	48
5.1.1	Manual Real Time Control Program	50
5.1.2	Autonomous Control Program	57
5.2	Controlling NXT Humanoid	62
5.2.1	Manual Real Time Control Program	63
A	ChNXT Class API	70
A.1	Data Types Used in ChNXT Class	70
A.1.1	nxtJointId_t	70
A.1.2	nxtJointState_t	70
A.1.3	nxtSensorPort_t	71
A.1.4	nxtSensorType_t	71

A.1.5 nxtSensorMode_t	71
A.2 ChNXT Class API Overview	72
A.3 ChNXT Class API Details	74
connect()	74
connectWithAddress()	74
disconnect()	75
getJointAngle()	76
getJointSpeedRatio()	77
getJointSpeedRatios()	77
getJointState()	78
getSensor()	79
humanoidWalkBackward()	80
humanoidWalkBackwardNB()	80
humanoidWalkForward()	81
humanoidWalkForwardNB()	81
humanoidMotionWait()	82
isConnect()	82
isMoving()	83
move()	84
moveNB()	84
moveContinuousNB()	85
moveContinuousTime()	86
moveJoint()	87
moveJointNB()	87
moveJointTo()	88
moveJointToNB()	88
moveJointWait()	89
moveJointContinuousNB()	90
moveTo()	90
moveToNB()	90
moveToZero()	92
moveToZeroNB()	92
moveWait()	93
resetToZero()	93
setSensor()	94
setJointSpeedRatio()	95
setJointSpeedRatios()	96
stopOneJoint()	97
stopTwoJoints()	97
stopAllJoints()	98
vehicleRollBackward()	99
vehicleRollBackwardNB()	99
vehicleRollForward()	100
vehicleRollForwardNB()	100
vehicleRotateLeft()	101
vehicleRotateLeftNB()	101
vehicleRotateRight()	102
vehicleRotateRightNB()	102

vehicleMotionWait()	103
B Miscellaneous Utility Functions	105
B.1 Overview	105
B.2 Function Details	105
angle2distance()	105
deg2rad()	106
delay()	106
distance2angle()	107
rad2deg()	108

1 Introduction

Ch Mindstorms NXT Control Package brings the inherent functionality of the Ch programming language to the intelligence and versatility found in the LEGO Mindstorms NXT robotic design system.

The Ch Mindstorms NXT Control Package consists of a set of API functions enabling programmers to write programs in C or C++ that can access and control the many features of the LEGO Mindstorms NXT controller. The API converts the complex messaging tasks required to communicate with the NXT into easy to use functions; allowing the user to focus their efforts on their robotic application, rather than the details of communication. The API of the Ch Mindstorms NXT Control Package was designed to support and augment all of the functionality found in the LEGO Mindstorms NXT controller. The Ch package further enhances the capabilities of the NXT controller by adding data collection and plotting capabilities. Additionally an NXT control program, written in C source code can be directly run from any platform in Ch without tedious compile/link/execute/debug cycles.

The communication between the user, the computer, the NXT controller, the sensors, and the motors can be described in Figure 1. Once NXT is connected to the computer and a NXT program has started, the program instructions are sent from the computer to the NXT. The NXT controller will process these instructions perform appropriate tasks by sending commands to the motors or receiving data from the sensors. The NXT can collect sensor data and motor encoder counts, and the data can be sent back to the computer for further manipulation, display, or stored in the computer for the user.

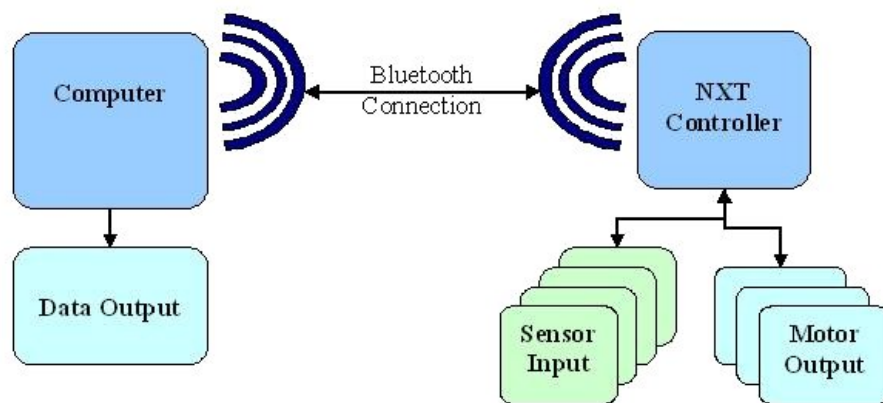


Figure 1: Communication Diagram of NXT

With Ch Mindstorms NXT Control Package, you can quickly develop an NXT robotic application and log your results. The ease of design and added functionality makes the Ch NXT Control Package a good candidate for any NXT programming application.

In this guide, we will go over the basics of a Ch Mindstorms NXT program. We will also discuss about how to control a NXT vehicle's motion. Lastly we will describe how to control non-vehicle NXT robots. After reading this guide, you will be ready to write your own Ch NXT program to control your NXT robot.

2 Configuraing Lego Mindstorms NXT for Remote Control

Before using the Ch NXT package to control NXTs, we need to configure the NXTs' bluetooth addresses. Firstly, the NXT modules need to be paired with the PC, which tells the computer the device is able to connect to. After successfully paired with the computer, we need to add the bluetooth addresses of NXTs to the configuration files, which allows the `ChNXT API connect()` to access those devices. The detailed information about paring part will be described in another documentation and in the next part will introduce you how to setup the bluetooth addresses of NXTs to the Ch NXT configuration file step by step.

2.1 Getting Bluetooth Addresses of NXTs

Firstly, we need to get the Bluetooth address of a NXT. As Figure 2 shown, right click the Bluetooth icon in the right buttom corner.



Figure 2: Right click the Bluetooth icon.

Then, choose the option "Show Bluetooth Devices", in Figure 3, to find the NXT which has already paired with the computer.

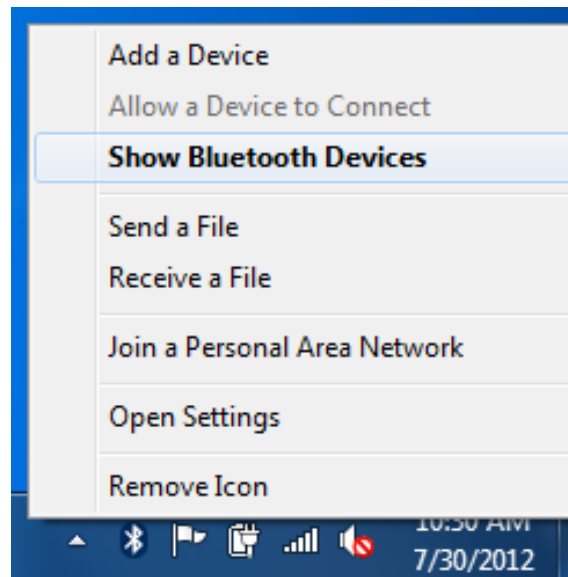


Figure 3: Choose "Show Bluetooth Devices" option.

Then, a dialog with all paired Bluetooth devices in this dialog will appear on the screen. Find the NXT icon and right click on the icon. Then choose "Properties" option as shown in Figure 4.

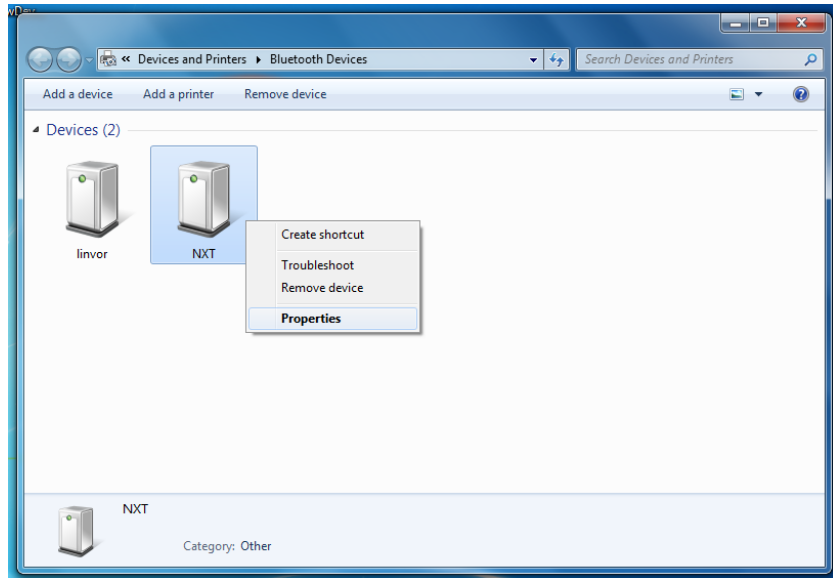


Figure 4: Right click the NXT icon then choose "Properties" option.

In the dialog of NXT properties as shown in Figure 5, click "Bluetooth" tab on the top and the bluetooth address will show as "Unique identifier" with the format as "xx:xx:xx:xx:xx:xx".

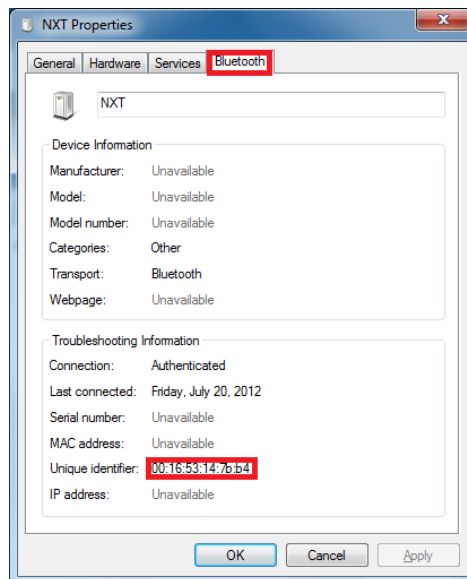


Figure 5: The properties dialog.

Now that we have already learned how to get the Bluetooth addresses of our NXTs, we can begin next section, which will introduce you how to add the Bluetooth address we have gotten into the ChNXT package.

2.2 Adding Bluetooth Addresses of NXTs in ChNXT Controller

The configuration is performed through the ChNXT Controller program. Start the provided ChNXT Control Program by clicking on the icon labeled "ChNXTController" on your desktop, as shown in Figure 6.



Figure 6: The icon for the ChNXT Controller.

Then the main dialog of ChNXT Controller will appear on your screen as shown in Figure 7 below.

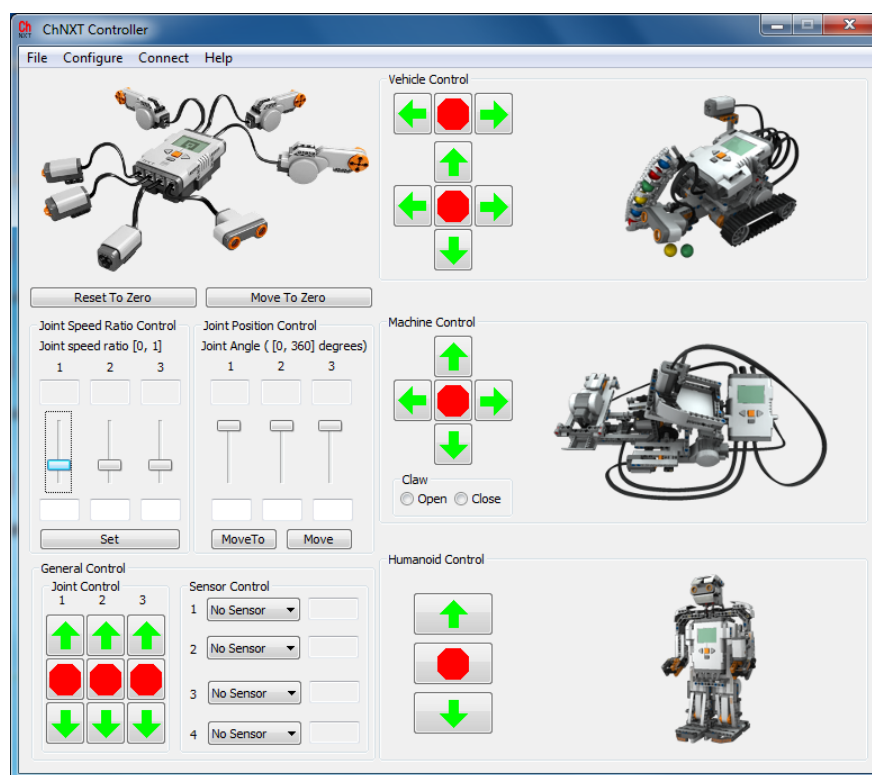


Figure 7: The main dialog of the ChNXT Controller.

Then click the menu item "Configure → Configure Robot Bluetooth", as shown in Figure 8.

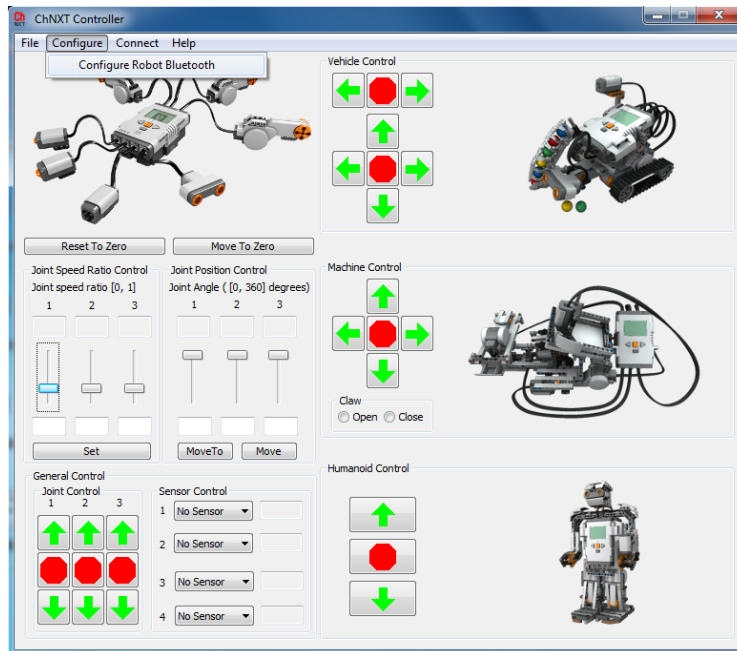


Figure 8: Configuring robot bluetooth connection.

Now, the configuration dialog will appear on your screen, which is titled as "Configure Robot Bluetooth", as shown in Figure 9.

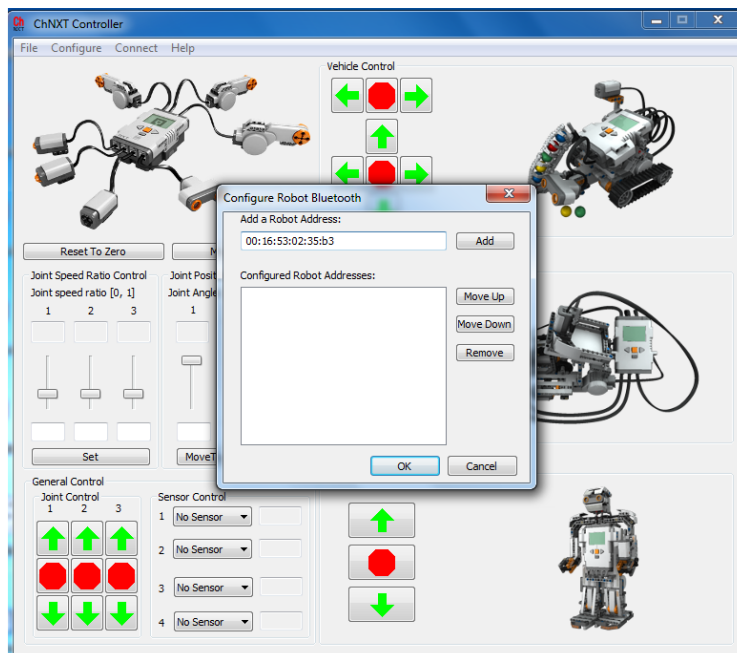


Figure 9: The bluetooth configuration dialog.

In this configuration dialog, we can add robot bluetooth addresses to the list of currently know robot bluetooth addresses. To add an address, first type in the address in the text box on the top

of the dialog, as shown in Figure 10.

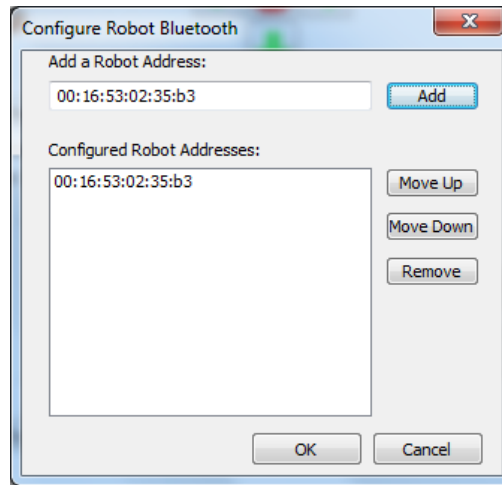


Figure 10: Adding the robot bluetooth address in the dialog window.

Then, click the "Add" button. The newly added address will appear in the list of known addresses and click "Ok" button to exit the configuration dialog. With this method, you can add more bluetooth addresses. Also, the "Move Up" button, "Move Down" button, and the "Remove" button can be used to manage your bluetooth address list.

2.3 Connecting and Disconnecting to NXTs from the ChNXT Controller

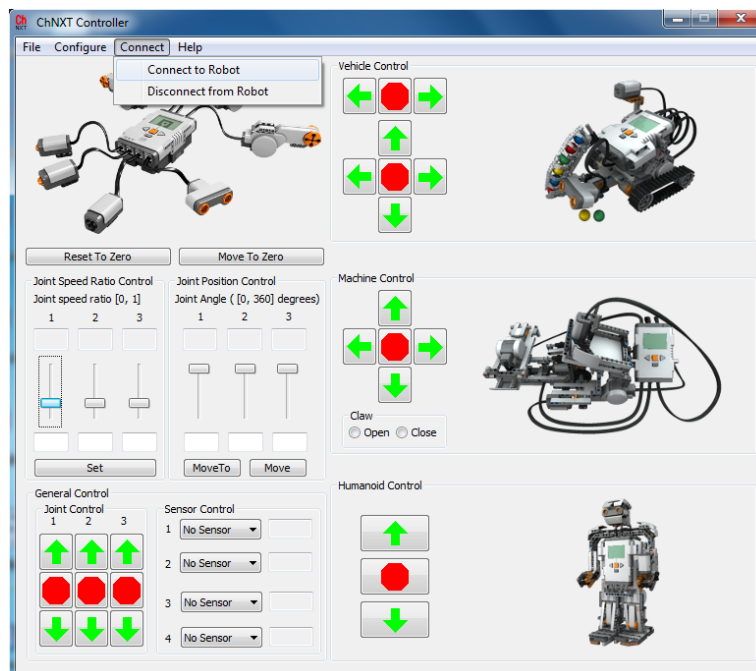


Figure 11: Connecting to and disconnecting from an NXT.

Once bluetooth addresses are added to the ChNXT Controller, you are now able to connect to a NXT device by clicking on the "Connect → Connect to Robot" menu item. Then the first NXT on the bluetooth address list will be connected and please make sure the NXT is turned on, otherwise the connection will fail. Also, by clicking "Connect → Disconnect from Robot" menu item, the computer will disconnect from the remote device. Those two menu items are as shown in Figure 11.

Please note that in order to run a Ch program that controls NXTs, the NXTs should not currently be connected to any other application, including the ChNXT Controller, other Ch Programs, and other programs on other devices.

Furthermore, the Bluetooth devices have a maximum limit of connected devices. The maximum limit is 7 devices connected simultaneously.

3 Getting Started with Ch NXT Package

In this chapter, the basics of controlling an NXT via Ch program will be discussed. The basics are including control an NXT joints, setup an NXT sensor, and also get information from joints and sensors. The basic structure of a Ch NXT robot program is shown in the flow diagram in Figure 12 below.

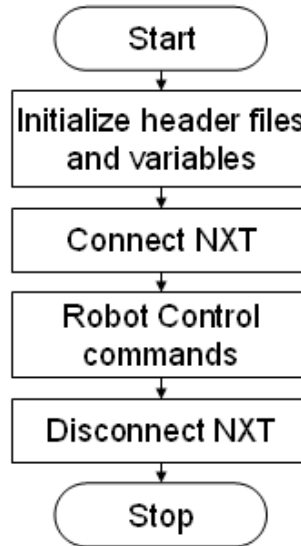


Figure 12: Flow Diagram of a basic NXT program

Also, to successfully control the Mindstorm NXT using Ch, it is important to practice good coding habits. The format of the Ch Mindstorm code is very similar to how a normal C code would be written, with the inclusion of some Ch specific functions and header files that are used to connect and control the NXT. To help the user become acquainted with the Ch NXT programs, sample programs will be presented in this section to illustrate the basics and minimum requirements of a Ch NXT control program. The sample programs are located at `CHHOME/package/chnxt/demos`, where `CHHOME` is the Ch home directory, such as `C:\Ch` for Windows. Therefore, for Windows, the demos are located at `C:\Ch\package\chnxt\demos` by default.

3.1 A Basic Ch NXT Program

The first demo presents a minimal program which connects to a Lego Mindstorms NXT and moves joints 2 and 3.

Source Code

```
/* File name: start.ch
 *
 * Move the NXT all joints by 360 degrees.*/
```

Program 1: `start.ch` Source Code

```

#include <nxt.h>

ChNXT nxt;

/* Connect to the paired NXT */
nxt.connect();

/* Set the robot to "home" position,
 * where all joint angles are 0 degrees.*/
nxt.moveToZero();

/* Rotate joint 2 and 3 by 360 degrees */
nxt.move(360, 360, 360);

```

Program 1: `start.ch` Source Code (Continued.)

Header files

The beginning of every program will include related header files. Each header file imports functions used for a number of tasks, such as displaying message on the screen or controlling the Lego Mindstorms NXT. The header file `nxt.h`, which contains all `ChNXT` class and other related functions for controlling the NXT, should be included in each Ch NXT program.

```
#include <nxt.h>
```

Initialization

The following line initializes a new variable named `nxt` which represents the remote Lego Mindstorm NXT which we wish to control. The special variable is actually an instance of the `ChNXT` class, which contains its own set of functions called "methods", "member functions", or simply "functions".

```
ChNXT nxt;
```

The next line,

```
nxt.connect();
```

will connect our computer to the remote NXT, which is related to the new variable `nxt`.

Another way to get connected with the NXT is using the function `connectWithAddress()`, and the usage is as following:

```
nxt.connectWithAddress("11:22:33:44:55:66");
```

The string "11:22:33:44:55:66" represents the Bluetooth address of the Lego Mindstorms NXT you wish to connect. Detailed documentation for `connect()` `connectWithAddress()` are presented in Appendix A on page 70. The next line,

```
nxt.moveToZero();
```

uses the function `moveToZero()` which is a member function of class `ChNXT`. The function causes all joints of the connected NXT move to zero position, which means the absolute angle will be all zero.

The next line of code will cause all joints of the connected NXT rotate 360 degrees.

```
nxt.move(360, 360, 360);
```

The member function `move()` expects input angles in degrees. If you want to use angles in radians, the conversion need to be done via the function `rad2deg()`. The function is implemented in Ch with code

```
#include <math.h> /* For M_PI */
double rad2deg(double radians){
    double degrees;
    degrees = radians * 180.0 / M_PI;
    return degrees;
}
```

If desired, values in radians may also be converted to degrees using the counterpart function, `deg2rad()`. Detailed information for function `rad2deg()` and function `deg2rad()` can be found in Appendix B on page 105.

3.2 Setting the Zero Positions for NXT Joints

In last section, we introduced a very basic demo of Ch NXT programs. In this section, another simple demo will be presented to illustrate how to set absolute zero positions for joints.

Source Code

```
/* File name: setZero.ch
 * presents how to set zero positions for NXT joints. */

#include <nxt.h>

ChNXT nxt;

/* Connect to the NXT */
nxt.connect();

/* Set new zero positions */
nxt.setJointZero(NXT_JOINT1);

/* Move to zero */
nxt.moveToZero();
```

Program 2: `setZero.ch` Source Code

Explanation

The first several lines of the code,

```
#include <nxt.h>

ChNXT nxt;

/* Connect to the NXT */
nxt.connect();
```

initializes the program, declares the variable and connects to the remote device. The next line,

```
/* Set new zero positions */
nxt.setJointZero(NXT_JOINT1);
```

sets NXT_JOINT1 to the new zero position. In order to set new zero positions, user should move the desired position before calling the function `setJointZero()`. The function `setJointZero()` can only set zero position for one joint. The argument it takes is the target joint. Another function called `setJointZeros()`, which takes no arguments, can set new zero positions for all joints. The next line,

```
/* Move to zero */
nxt.moveToZero();
```

makes all joints move to new zero positions. The last part of the code,

```
/* Disconnect from NXT */
nxt.disconnect();
```

disconnects from the NXT.

3.3 Controlling the Speed of NXT Joints

Now that we have already discussed how to include related header files, define variables for the program, get connected with/disconnect from the NXT and also set zero positions NXT joints. In this section, we will present a demo program, `setSpeedRatios.ch`, to illustrate how to set speed ratios for the joints of NXT.

Source Code

```
/* File name: setSpeedRatios.ch
 * set speed ratios for joints of NXT. */

#include <nxt.h>
ChNXT nxt;

/* Connect to the paired NXT */
nxt.connect();

/* set speed ratios */
nxt.setJointSpeedRatios(0, 0.4, 0.4);
nxt.setJointSpeedRatio(NXT_JOINT1, 0.5);

/* make NXT joints move */
nxt.move(360, 360, 360);

/* disconnect */
nxt.disconnect();
```

Program 3: `setSpeedRatios.ch` Source Code

Explanation

The first several lines,

```
#include <nxt.h>
ChNXT nxt;
```

```
/* Connect to the paired NXT */
nxt.connect();
```

initializes the program, variable, and connect to the NXT. The next three lines,

```
/* set speed ratios */
nxt.setJointSpeedRatios(0, 0.4, 0.4);
nxt.setJointSpeedRatio(NXT_JOINT1, 0.5);
```

sets the speed ratios setting for all joints on the NXT. The function `setJointSpeedRatios()` sets the speed ratio for `NXT_JOINT1` as 0 and sets the speed ratios for `NXT_JOINT2` and `NXT_JOINT3` as 0.4. The function `setJointSpeedRatio()`, which can only set speed ratio for one joint, sets the speed ratio for `NXT_JOINT1` as 0.5.

The next two lines,

```
/* make NXT joints move */
nxt.move(360, 360, 360)
```

makes three joints of NXT move at setted speed ratios. The usage of the function `move()` is just as the demo discussed in section 3.1 on page 8.

The last part of the code,

```
/* disconnect */
nxt.disconnect();
```

disconnects from the NXT.

3.4 Making NXT Joints Move

Now that we have already discussed connect/disconnect and set speed ratios for joints, this section will presents a full series of moving functions.

3.4.1 A Demo Program for Movement Functions

In this section, a simple demo program will be presented to illustrate the series functions of moving NXT joints.

Source Code

```
/* File name: move.ch
 *
 * illustrate the full series of moving function */
```

Program 4: `move.ch` Source Code


```

#include <nxt.h>

ChNXT nxt;

/* Connect to the NXT */
nxt.connect();

/* Set speed ratios */
nxt.setJointSpeedRatios(0.5, 0.5, 0.5);

/* move joint to zero position */
nxt.moveToZero();

/* move a joint by user specified angle */
nxt.moveJoint(NXT_JOINT1, 360);

/* move a joint to absolute angle */
nxt.moveJointTo(NXT_JOINT1, 360);

/* move all joints by specified angles */
nxt.move(180, 360, 360);

/* move all joints to absolute angles */
nxt.moveTo(360, 360, 360);

/* disconnect from NXT */
nxt.disconnect();

```

Program 4: (Continued.)

Explanation

The first part of code,

```

#include <nxt.h>
ChNXT nxt;

/* Connect to the NXT */
nxt.connect();

/* Set speed ratios */
nxt.setJointSpeedRatios(0.5, 0.5, 0.5);

```

initializes the program, connects to the NXT and sets speed ratios for joints. The next couple lines,

```

/* move joint to zero position */
nxt.moveToZero();

```

moves the joint to the absolute zero positions for all joints. The function `setJointZero()` and `setJointZeros()` are used to set joints absolute positions. Detailed information for these two functions can be found in Appendix A . The next four lines,

```

/* move a joint by user specified angle */
nxt.moveJoint(NXT_JOINT1, 360);

```

```
/* move a joint to absolute angle */
nxt.moveJointTo(NXT_JOINT1, 360);
```

includes two functions `moveJoint()` and `moveJointTo`, which makes one joint move a specified angle relatively and absolutely respectively. Similarly, the next four lines,

```
/* move all joints by specified angles */
nxt.move(180, 360, 360);
```

```
/* move all joints to absolute angles */
nxt.moveTo(360, 360, 360);
```

includes functions `move()` and `moveTo`, which makes all joints move specified angles relatively and absolutely respectively. The last part,

```
/* disconnect from NXT */
nxt.disconnect();
```

disconnects from an NXT device as all demos described in previous sections.

3.4.2 Blocking and Non-Blocking Functions

The movement functions described in previous demo are all blocking ones. Once the blocking movement functions are called, the functions will hang, or "blocking", until all the joints have stopped moving. However, the movement functions also have "non-blocking" version, which means the function returns immediately and the function `moveWait()` can be used to wait for the movement stopping. NB at the end of non-blocking functions indicates that the functions are non-blocking version, such as `moveNB()`. A simple example will be presented in the following.

Example

```
#include <nxt.h>

ChNXT nxt;

/* Connect to the NXT */
nxt.connect();

/* Non-blocking Function */
nxt.moveJointNB(NXT_JOINT1, 360);
printf("This message will be printed on \
      the screen when joint1 is moving.\n");
nxt.moveWait();

/* Blocking Function */
nxt.moveJoint(NXT_JOINT1, 360);
printf("This message will be printed on \
      the screen after joint1 stopped moving.\n");

/* Disconnect from the NXT */
nxt.disconnect();
```

Explanation

The first several lines,

```
#include <nxt.h>
```

```
ChNXT nxt;
```

```
/* Connect to the NXT */
nxt.connect();
```

just like all NXT programs, initializes the program and connects to the NXT. Then the next part,

```
/* Non-blocking Function */
nxt.moveJointNB(NXT_JOINT1, 360);
printf("This message will be printed \
      on the screen when joint1 is moving.\n");
nxt.moveWait();
```

is showing the non-blocking function `moveJointNB()`. The function `printf()` will print a message onto the screen during the joint1 is moving. However, the blocking part below,

```
/* Blocking Function */
nxt.moveJoint(NXT_JOINT1, 360);
printf("This message will be printed on \
      the screen after joint1 stopped moving.\n");
```

will print out the message after the function `moveJoint()` finished, which means the joint1 stops moving. Most moving functions have both blocking and non-blocking version. However, there are still some exceptions. The function `moveJointContinuousNB()` and function `moveContinuousNB()` have only non-blocking version and the function `moveContinuousTime()` only has blocking version. In table 1, we list all blocking functions and their corresponding non-blocking functions.

Table 1: Block and Non-block Functions

Block Functions	Non-block Functions
<code>moveJoint()</code>	<code>moveJointNB()</code>
<code>moveJointTo()</code>	<code>moveJointToNB()</code>
<code>move()</code>	<code>moveNB()</code>
<code>moveTo()</code>	<code>moveToNB()</code>
<code>moveToZero()</code>	<code>moveToZeroNB()</code>
<code>vehicleRollForward()</code>	<code>vehicleRollForwardNB()</code>
<code>vehicleRollBackward()</code>	<code>vehicleRollBackwardNB()</code>
<code>vehicleRotateLeft()</code>	<code>vehicleRotateLeftNB()</code>
<code>vehicleRotateRight()</code>	<code>vehicleRotateRightNB()</code>

Also, detailed information for both blocking and non-blocking versions of movement functions can be found in Appendix A on page 70.

3.5 Retrieving a Joint Angle

This demo presents how to get a joint current angle in a Ch NXT program. The angle is the absolute position in degrees.

Source Code

```
/* Filename: getJointAngle.ch
 * Find the current joint angle of a joint */

#include <nxt.h>
ChNXT nxt;

/* Connect to a NXT */
nxt.connect();

/* Get the joint angle of the first joint */
double angle;
nxt.getJointAngle(NXT_JOINT1, angle);

/* Print out the joint angle */
printf("The current joint angle for joint 1 is %lf degrees.\n", angle);

/* Disconnect from NXT */
nxt.disconnect();
```

Program 5: getJointAngle.ch Source Code

Explanation

As all programs, the first part of this program,

```
#include <nxt.h>
ChNXT nxt;
```

```
/* Connect to a NXT */
nxt.connect();
```

is to include the related header files, which is `nxt.h` in this program, to initialize variable and to connect to the remote NXT device. The next three lines of the code,

```
/* Get the joint angle of the first joint */
double angle;
nxt.getJointAngle(NXT_JOINT1, angle)
```

retrieves the current angle of joint 1. `NXT_JOINT1` is an enumerated value defined in the header file `nxt.h`. Detailed information for all enumerated values defined in `nxt.h` can be found in Appendix A.1 on page 70. Finally, the last part of the program,

```
/* Print out the joint angle */
printf("The current joint angle for joint 1 is %lf degrees.\n", angle)
```

prints the value of the variable onto the screen.

3.6 Setting Sensors for NXT

We have finished discussing the connection and movement functions in previous sections and In this section, we will start to discuss how to use sensors of NXT. The following demo code will present how to setup a sensor for NXT and how to get values collected by the sensor from the NXT.

Source Code

```
/* File name: sensor.ch
 * A breif introduction of using sensors of NXT.*/

#include <nxt.h>

ChNXT nxt;

/* Setup sensors and check sensor connection */
int status1=2, status2=2;

/* Variables to store values gotten from NXT */
int touchValue, ultraValue;

/* Connect to NXT */
nxt.connect();

/* Save status of NXT_SENSORPORT1, and NXT_SENSORPORT4 */
status1 = nxt.setSensor(NXT_SENSORPORT1,
                       NXT_SENSORTYPE_TOUCH, NXT_SENSORMODE_BOOLEANMODE);

status2 = nxt.setSensor(NXT_SENSORPORT4,
                       NXT_SENSORTYPE_ULTRASONIC, NXT_SENSORMODE_RAWMODE);

/* Check connection status sensors connection */
if(status1) {
    printf("Fail to setup sensors.\n");
    exit(-1);
}

if(status2) {
    printf("Fail to setup sensors.\n");
    exit(-1);
}

/* get values collected by sensors from NXT */
nxt.getSensor(NXT_SENSORPORT1, touchValue);
nxt.getSensor(NXT_SENSORPORT4, ultraValue);

/* display the values we got onto the screen */
printf("Touch sensor: %d\n", touchValue);
printf("Ultrasonic sensor: %d\n", ultraValue);

/* disconnect */
//nxt.disconnect();
```

Program 6: `sensor.ch` Source Code

Explanation

The first part of the code,

```
#include <nxt.h>
```

```
ChNXT nxt;
```

```
/* Setup sensors and check sensor connection */  
int status1=2, status2=2;
```

```
/* Variables to store values gotten from NXT */  
int touchValue, ultraValue;
```

```
/* Connect to NXT */  
nxt.connect();
```

initializes the program, declares the variables and connects to the NXT. Here, we declared two more sets of variables, where one set is used to check the connection status of sensors and another set is used to store the values collected by sensors. The next part of code,

```
/* Save status of NXT_SENSORPORT1, and NXT_SENSORPORT4 */  
status1 = nxt.setSensor(NXT_SENSORPORT1,  
    NXT_SENSORTYPE_TOUCH, NXT_SENSORMODE_BOOLEANMODE);
```

```
status2 = nxt.setSensor(NXT_SENSORPORT4,  
    NXT_SENSORTYPE_ULTRASONIC, NXT_SENSORMODE_RAWMODE);
```

setup two sensors for the connected NXT. The function we used to setup sensors is `setSensor()`, which takes three arguments. The first argument represents the port number on the NXT, which is in type `nxtSensorPort_t`. The second argument the function takes is the type of a sensor, which is in type `nxtSensorType_t`. And the last argument is the working mode of a sensor, which is in type `nxtSensorMode_t`. Detailed information for the three variable types can be found in Appendix A.1. The next several lines,

```
/* Check connection status sensors connection */  
if(status1) {  
    printf("Fail to setup sensors.\n");  
    exit(-1);  
}  
  
if(status2) {  
    printf("Fail to setup sensors.\n");  
    exit(-1);  
}
```

checks the status of each sensor to see if they were setup correctly. If fail to setup sensors, the program will exit automatically. The function `setSensor()` returns 1 means success. The next part of code,

```
/* get values collected by sensors from NXT */  
nxt.getSensor(NXT_SENSORPORT1, touchValue);  
nxt.getSensor(NXT_SENSORPORT4, ultraValue);
```

gets the collected values from the NXT by using the function `getSensor()`. In order to use the function, two arguments are necessary. One is the sensor port in type `nxtSensorType_t`. Another argument is the address of the variable used to store value gotten from the NXT. The last part,

```
/* display the values we got onto the screen */  
printf("Touch sensor: %d\n", touchValue);  
printf("Ultrasonic sensor: %d\n", ultraValue);
```

```
/* disconnect */  
nxt.disconnect();
```

displays the values gotten from the NXT onto the screen and the disconnects from the NXT.

4 Controlling a NXT Vehicle



Figure 13: NXT Vehicle

The NXT comes with three actuator output ports and the actuators available are the NXT motors. Normally, you can only control the speed and direction of the connected motors. For a two wheeled NXT vehicle, there are two ways that the NXT vehicle can be controlled. In addition to moving the NXT by controlling the individual motors as shown in Figure 13, you can also use a set of Ch mindstorm functions written specifically to control an NXT vehicle. The diagram of the vehicle and the motor ports is shown in Figure 14. When controlling the individual motors, you would need to define the speed and direction of each motor. The functions in the following examples require only a speed. In this section, we will show a basic Ch NXT program to move the robot forward. Please make sure your NXT vehicle are configured according to to Figure 14 to run our demonstration programs.

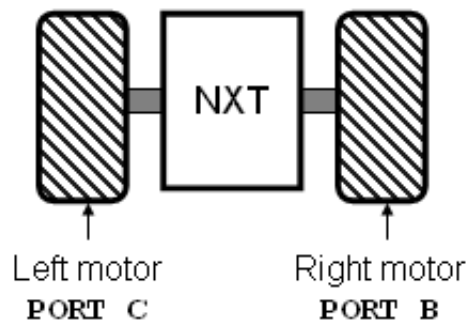


Figure 14: Motor configuration of the NXT Vehicle

4.1 How to make your NXT move forward

To help user become acquainted with the Ch NXT package, the example `vehicleRollForward.ch` will be presented in the following section to illustrate the basics and minimum requirements of a Ch NXT control program. The code can be written using C or Ch syntax. For simplicity, the following code is presented as a Ch program.

```
/******  
forward.ch  
Created by Michael Schirle  
Modified by Binsen Qian  
  
The purpose of this demo is to introduce the CH Mindstorms  
Control Package syntax to new users by moving the robot  
forward.  
*****/  
#include <nxt.h>  
  
ChNXT nxt;  
  
/* Connect to NXT */  
if (nxt.connect()) {  
    printf("Error: Cannot connect to Lego Mindstorm NXT.\n");  
    exit(-1);  
}  
  
/* Set Speed Ratio */  
nxt.setJointSpeedRatios(0, 0.25, 0.25);  
  
/* Turn the motors on */  
nxt.vehicleRollForward(360);  
  
/* Disconnect NXT */  
nxt.disconnect();
```

Program 7: `forward.ch` Source Code

4.1.1 Initialization

In the beginning of a Ch Mindstorms NXT program or any C program, you must include proper header files to run the program properly. Without proper header files, the program will not have the specific libraries or source codes to run the program. Essential header files for the NXT includes:

```
#include <nxt.h>
```

The `nxt.h` is the essential header file for Ch NXT control functions and variables.

4.1.2 Connect the NXT and Checking Connection Status

The NXT status, sensor/encoder data, and input/output protocols are stored in a C++ class called `ChNXT`. This class must be created in every NXT program in order to connect. Therefore, in the beginning of your code, you must define a `ChNXT` class and use the `connect()` function to connect to the NXT. The `connect()` function will return a 1 if no connection is established, so you will have to terminate your program if no connection is established. An example of how to create the class and how to retrieve data are shown below:

```

ChNXT nxt;

/* Check status of NXT connection */
if (nxt.connect()){
    printf("Error: Cannot connect to Lego Mindstorm NXT.\n");
    exit(-1);
}

```

The line `ChNXT nxt;` creates the class `nxt` that is used to store data and control the NXT robot. The function `nxt.connect()` called in the if statement is used to terminate the program in the event no connection is established. The `printf()` is included to print out an error message if `nxt.connect` fails. To end the program if connection fails, the function `exit()` is used. The use of `exit(-1)` is similar to the C function `return 0`;; that can be used when no `main()` function is present.

4.1.3 Moving the Robot Forward

After establishing the connection between a computer and an NXT, you can move the NXT vehicle forward by using the `vehicleRollForward()`. After using the `vehicleRollForward()` function, the program will wait for the motion stopping. Figure 15 shows the NXT vehicle moving forward by actuating both wheels forward with the same speed ratio, which is how the function `vehicleRollForward()` works. By default, the ports for the two wheels on the NXT are `NXT_JOINT2` and `NXT_JOINT3`.

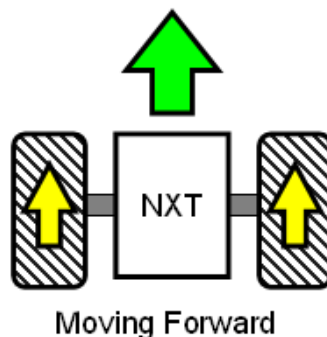


Figure 15: Top-down view of NXT vehicle with two wheels

The following part is the maint code to make the NXT vehicle robot move forward in the program `vehicleRollForward.ch`:

```

/* set speed ratio */
nxt.setSpeedRatios(0, 0.25, 0.25);

/* Move foward */
nxt.vehicleRollForward(360);

```

4.1.4 Ending your program

After you finish your program, you must end your program properly by stopping all the motors and disconnect the NXT from your computer. You can stop the motors using the `stopAllJoints()`

function, which stops all of the NXT motors. To disconnect the nxt, use the `disconnect()` function. For example:

```
/* Stop the motors */
nxt.stopAllJoints();

/* Disconnect NXT */
nxt.disconnect();
```

4.2 How to make your NXT move backward

To make a NXT vehicle move backward, the function `vehicleRollBackward()` can be used. The function works similarly to `vehicleRollForward()`, moving the robot backwards. The function works by actuating both wheels backward at the same speed, as shown in Figure 16.

Using our new function, we can add the following code fragment to our first program to make the

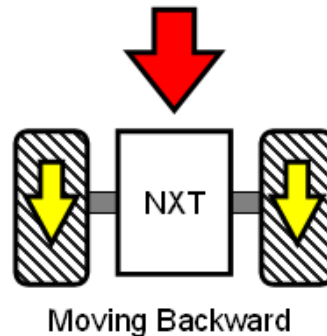


Figure 16: NXT vehicle moving backwards

robot move backwards. The code fragment is shown below:

```
/* set speed ratio */
nxt.setJointSpeedRatios(0, 0.25, 0.25);

/* Move backward */
nxt.vehicleRollBackward(360);
```

The modified program is called: `vehicleRollBackward.ch`.

4.3 How to make your NXT turn in place left/right

To make your NXT vehicle turn or rotate in place, the NXT vehicle wheels must be spun in the opposite direction at the same speed. For example, to rotate the NXT vehicle to the left, the right wheel must be spun forward, while the left wheel spins at the same speed in reverse. Figure 17 shown below shows the NXT vehicle turning in place left or right by actuating the wheels in opposite direction.

To make the NXT rotate in place, we can use the functions `vehicleRotateLeft()` and `vehicleRotateRight()`. An example of how to use the functions are shown below:

```
/* set speed ratio */
nxt.setJointSpeedRatios(0, 0.50, 0.50);
```

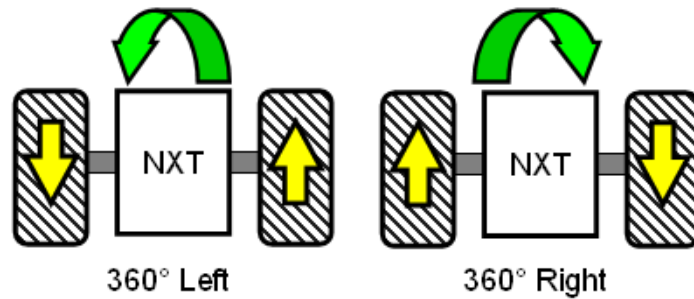


Figure 17: NXT vehicle turning 360 degrees

```
/* rotate left */
nxt.vehicleRotateLeft(360);

// or

/* set speed ratio */
nxt.setJointSpeedRatios(0, 0.50, 0.50);

/* rotate right */
nxt.vehicleRotateRight(360);
```

An example program is called: `vehicleRotate.ch`.

4.4 Advance Mindstorm Motor Control

The previous section showed simplified controls for an NXT vehicle robot. To control alternate NXT designs, or to perform more advance movements with the NXT vehicle, the NXT motors must be controlled individually. The following sections shows how to control the individual motors, and how the previously presented NXT vehicle actions can be done by controlling the individual motors.

4.4.1 Motor Control Functions

The function that is used to control the NXT motors is `moveJointContinuousNB()`. To use the function, you need the motor port and the move direction. The speed of the motors are limited, and can only ranged from 0 to 100. For the direction, the data type `nxtJointState_t` is defined. In the data type, there are two values indicate the move directions. One is call `NXT_FORWARD`, which means the positive direction and the other is called `NXT_BACKWARD` means the negative direction. The function is end with `NB`, which means the function is non-blocking one. Therefore, you will need to use the `delay()` function to leave the motors on for the desired amount of the time. Otherwise, the program will go through the following statements directly. Due to the setup of the NXT vehicle, forward motion can be achieved by turning the motors on to the same speed ratio. For example:

```
/* set speed ratio */
nxt.setJointSpeedRatios(0, speedRatio, speedRatio);

/* Move foward */
```

```
nxt.moveJointContinuousNB(NXT_JOINT2, NXT_FORWARD);
nxt.moveJointContinuousNB(NXT_JOINT3, NXT_FORWARD);
```

```
/* Pause program for a while */
delay(5);
```

This will move the NXT vehicle forward at the value the variable speed was set to. To get the NXT vehicle to move in reverse, the same code can be used by changing the sign on speed in the function `setJointSpeedRatios()`. The following shows the `forwardBackward.ch` rewritten to use the individual motor control.

```

/*****
forwardBackward.ch
Created by Michael Schirle
Modified by Binsen Qian

The purpose of this program is to introduce how to get the
nxt_robot to reverse direction.
*****/
#include <nxt.h>

ChNXT nxt;
double speedRatio = 0.25;

/* Connect to NXT */
if (nxt.connect() != 0) {
    printf("Error: Cannot connect to Lego Mindstorm NXT.\n");
    exit(-1);
}

/* set speed via pass the speed ratio*/
nxt.setJointSpeedRatios(0, speedRatio, speedRatio);

/* Move the Robot Forward */
nxt.vehicleRollForward(360);

/* Move the Robot Backwards */
nxt.vehicleRollBackward(360);

/* Disconnect NXT */
nxt.disconnect();

```

Program 8: forwardBackward.ch Source Code

4.4.2 Turning Using Single Motor Control

Turning and rotation movements can also be achieved using the `moveJointContinuousNB()` functions. As previously discussed, to turn our NXT vehicle, one motor must be rotating at a faster speed than the other, or the motors must be spinning in the opposite direction. For the following discussion, Figures 17 may be useful.

To turn the NXT vehicle left, the right wheel must be moving faster in forward direction than the left wheel. If you want to move forward and turn left, let the left wheel move at 0.7 of the speed

that the right wheel is set to. To implement it with the single motor control functions, you would do the following:

```
/* set speed ratio */
nxt.setJointSpeedRatios(0, speedRatio, 0.7*speedRatio);

/* Move forward-left */
nxt.moveJointContinuousNB(NXT_JOINT2, NXT_FORWARD);
nxt.moveJointContinuousNB(NXT_JOINT3, NXT_FORWARD);

/* Pause program for a while */
delay(5);
```

The value of 0.7 is somewhat arbitrary, and other constant values could be used to test the resulting NXT vehicle response. The function `vehicleRotateLeft()` works similarly, instead setting the left wheel at the negative speed of the right wheel. An example is shown below:

```
/* set speed ratio */
nxt.setJointSpeedRatios(0, speedRatio, speedRatio);

/* Rotate left in place */
nxt.moveJointContinuousNB(NXT_JOINT2, NXT_FORWARD);
nxt.moveJointContinuousNB(NXT_JOINT3, NXT_BACKWARD);

/* Pause program for a while */
delay(5);
```

To make the functions `vehicleRotateLeft()` and `vehicleRotateRight()` work, you need to make the speed ratio opposite. Once you understand how the single motor commands work, more advance movements can be done, such as a move back and left motion. The single motor commands can also be used to add a third motor attachment to the NXT vehicle, or used to control alternate robot designs that move or act differently.

One alternative approach to implementing turning is to increase the speed of a wheel, instead of decreasing a wheel speed. For example, to implement a left turn, we could increase the speed of the right wheel by multiplying by a constant, such as 1.2. The resulting code would look like:

```
/* set speed ratios */
nxt.setJointSpeedRatios(0, 1.2*speedRatio, speedRatio);

/* Move forward-left */
nxt.moveJointContinuousNB(NXT_JOINT2, NXT_FORWARD);
nxt.moveJointContinuousNB(NXT_JOINT3, NXT_FORWARD);

/* Pause program for a while */
delay(5);
```

While this would work for slower motor speeds, a bug would occur if the NXT vehicle speed was set too high. Can you spot why? As previously discussed, the valid motor speed ratio for NXT motors are between 0 to 1. If the speed variable is set to 1, the command to control the left motor (NXT_JOINT3) will function correctly. The right motor (NXT_JOINT2) will receive a command telling it to set the motor speed to $1.2 \times 1 = 1.2$. This is an invalid motor command, and if you tried to run it on the NXT, it will cause the motor to reverse direction, making the NXT vehicle turn right instead of left. It is important to be watchful of these type of errors while writing code to control the NXT.

4.4.3 Manual Real Time Control Program

Manual real time control program allows you to control your NXT vehicle with your keyboard like a remote control. For a manual control program, a user interface is usually used to display all the possible option that a user can input into the program. The user interface allow the user to know how to control the NXT's motion. The NXT vehicle RTC program prints out a user interface for the user to use while executing the program. Figure 18 is the user interface of the NXT vehicle RTC program.

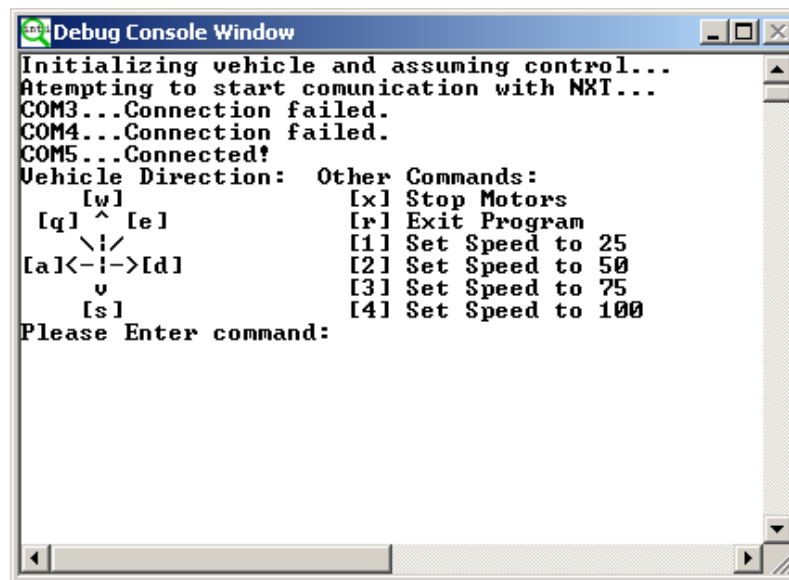


Figure 18: NXT vehicle RTC User Interface

In Figure 18, the user interface of the NXT vehicle RTC program display all the possible key that the user can use. In addition, the user interface also indicate the functionality of the key that is being pressed. When a specific key is pressed during the execution of the NXT vehicle RTC program, the program uses a `if-else if-else` statement to performs a fragment of code that send commands to the NXT. For example:

- The key "w" is to control the NXT to move forward.
- The key "s" is to control the NXT to move backward.
- The key "a" is to control the NXT to turn left.
- The key "d" is to control the NXT to turn right.
- The key "x" is to stop the NXT motors.
- The key "1" is to set the NXT motor speed ratio from 0.25.
- The key "2" is to set the NXT motor speed ratio from 0.5.
- The key "3" is to set the NXT motor speed ratio from 0.75.
- The key "4" is to set the NXT motor speed ratio from 1.

- The key "r" is to exit the manual RTC program.

In the robot control code block, a while loop is implemented to allow the user to control the NXT continuously until the program is terminated. Within the while loop, the program grabs the user's input and decide what to do with it using the **switch** and **case** statements. The whole NXT vehicle RTC program is shown in Program 9. Please make sure your NXT vehicle are configured according to to Figure 14 to run Program 9. In the rest of this section, we are going to explain the whole program in detail.

```
/*File name: vehicle_rtc.ch

The purpose of this demo is to demonstrate the CH Mindstorms
Control Package's ability to control the machine robot model,
As well as demonstrate how to get and use sensor data. */
#include <conio.h>
#include <stdio.h>
#include <nxt.h>

ChNXT nxt;
double speedRatio = 0.25; //speedRatio of the motors. (default to 25)
int quit = 0, //used by quit case to exit the loop
    status1, //used to check for errors
    status2; //used to check for errors
char key = 'x', //stores the input from the user
    movemode = 'x'; //stores the last movement command

/* Connect to NXT */
printf("Initializing vehicle and assuming control...");
if (nxt.connect()) {
    printf("\nPress any key to exit.\n");
    while (!_kbhit()); //wait for keypress
    exit(0);
}

/* GUI display */
printf("Vehicle Direction:  Other Commands:");
printf("\n      [w]                [x] Stop Motors");
printf("\n [q] ^ [e]                [r] Exit Program");
printf("\n  \\|/                [1] Set SpeedRatio to 0.25");
printf("\n[a]<-|->[d]            [2] Set SpeedRatio to 0.50");
printf("\n      v                [3] Set SpeedRatio to 0.75");
printf("\n      [s]            [4] Set SpeedRatio to 1\n");
printf("Please Enter command:");

/* Control loop. Interprets user command and does action*/
while (quit != 1 ) {
    key = _getch();
```

Program 9: vehicle_rtc.ch Source Code


```

if(key == 'w'){//up
    nxt.setJointSpeedRatios(0, speedRatio, speedRatio);
    nxt.moveJointContinuousNB(NXT_JOINT2, NXT_FORWARD);
    nxt.moveJointContinuousNB(NXT_JOINT3, NXT_FORWARD);
    movemode = 'w';
}else if(key == 's'){//down
    nxt.setJointSpeedRatios(0, speedRatio, speedRatio);
    nxt.moveJointContinuousNB(NXT_JOINT2, NXT_BACKWARD);
    nxt.moveJointContinuousNB(NXT_JOINT3, NXT_BACKWARD);
    movemode = 's';
}else if(key == 'd'){//right
    nxt.setJointSpeedRatios(0, speedRatio, speedRatio);
    nxt.moveJointContinuousNB(NXT_JOINT2, NXT_BACKWARD);
    nxt.moveJointContinuousNB(NXT_JOINT3, NXT_FORWARD);
    movemode = 'd';
}else if(key == 'a'){//left
    nxt.setJointSpeedRatios(0, speedRatio, speedRatio);
    nxt.moveJointContinuousNB(NXT_JOINT2, NXT_FORWARD);
    nxt.moveJointContinuousNB(NXT_JOINT3, NXT_BACKWARD);
    movemode = 'a';
}else if(key == 'q'){//forward-left
    nxt.setJointSpeedRatios(0, speedRatio, 0.7*speedRatio);
    nxt.moveJointContinuousNB(NXT_JOINT2, NXT_FORWARD);
    nxt.moveJointContinuousNB(NXT_JOINT3, NXT_FORWARD);
    movemode = 'q';
}else if(key == 'e'){//forward-right
    nxt.setJointSpeedRatios(0, 0.7*speedRatio, speedRatio);
    nxt.moveJointContinuousNB(NXT_JOINT2, NXT_FORWARD);
    nxt.moveJointContinuousNB(NXT_JOINT3, NXT_FORWARD);
    movemode = 'e';
}else if(key == 'x'){//stop
    nxt.stopOneJoint(NXT_JOINT2);
    nxt.stopOneJoint(NXT_JOINT3);
    movemode = 'x';
}else if(key == 'r'){//quit
    printf("\nExiting program.\n");
    quit = 1;
}else if(key == '1'){//speedRatio 0.25
    speedRatio = 0.25;
    ungetch(movemode);
}else if(key == '2'){//speedRatio 0.50
    speedRatio = 0.50;
    ungetch(movemode);
}else if(key == '3'){//speedRatio 0.75
    speedRatio = 0.75;
    ungetch(movemode);
}else if(key == '4'){//speedRatio 1
    speedRatio = 1;
    ungetch(movemode);
}else{
    printf("\nInvalid Input!\n");
}

```

Program 9: vehicle_rtc.ch Source Code (Continued.)

```

    }
}

/* disconnect from NXT */
nxt.disconnect();

```

Program 9: `vehicle_rtc.ch` Source Code (Continued.)

Header files

Similar to any C program, you will have to include necessary header files, which is described in the first four lines.

```

#include <conio.h>
#include <stdio.h>
#include <nxt.h>

```

- The header `conio.h` provides a function for the program to detect a key press for the `-press a key-` command.
- The header `stdio.h` provides input and output function for the program. These input and output function allows the program to display output for the user or ask for the user input.
- The header `nxt.h` provides the program with general functions of the Ch Mindstorm Control Package.

Declaring variables

After including the headers, the C program will start the `main()` program. Like any C programs, you must declare variables before you can use them. On the top few lines of the `main()` program, variables are declared.

```

ChNXT nxt;

double speedRatio = 0.25; //speed ratio of the motors. (default to 0.25)

int quit = 0,           //used by quit case to exit the loop
    status1,           //used to check for errors
    status2;           //used to check for errors

char key = 'x',         //stores the input from the user
    movemode = 'x';     //stores the last movement command

```

- The `ChNXT` class stores the connection status, sensor data, and motor counter data of the NXT. Also, the class includes the functions for controlling the NXT.
- The double variable `speedRatio` stores the speed ratio of the motor.
- The integer variable `quit` is used to check if the user wants to quit the program.
- The integer variable `status1` and `status2` are used to check the sensor connection.
- The character variable `key` stores the input from the user.
- The character variable `movemode` stores the last command that the user used.

Checking connection

After declaring variables, the connection of the NXT needs to be checked. In the next 7 lines of the program, the program checks for the connection of the NXT to the computer. If the NXT connection fails, the program will quit.

```
/* Connect to NXT */
printf("Initializing vehicle and assuming control...");
if (nxt.connect()){
    printf("\nPress any key to exit.\n");
    while (!_kbhit()); //wait for keypress
        exit(-1);
}
```

User interface

Before the beginning of the real time control, the user must be able to know the function of the key they are pressing. To do this, the program print out a user interface for the user to read. In segment of the Program 11 shown below, the NXT vehicle RTC program used `printf()` command is used to display the user interface for the user to read.

```
/* GUI display */
printf("Vehicle Direction:  Other Commands:");
printf("\n      [w]                [x] Stop Motors");
printf("\n [q] ^ [e]                [r] Exit Program");
printf("\n      \\/                [1] Set Speed Ratio to 0.25");
printf("\n[a]<-|->[d]                [2] Set Speed Ratio to 0.50");
printf("\n      v                [3] Set Speed Ratio to 0.75");
printf("\n      [s]                [4] Set Speed Ratio to 1\n");
printf("Please Enter command:");
```

Real time control

After completing the initiation of the code, which include adding header files, declaring variables, checking connection, and displaying the user interface, the real time control of the NXT begins with the robot control code block. In the robot control code block, a while loop is implemented to allow the user to control the NXT continuously until the program is terminated. Within the while loop, the program grabs an input from the user, and then decide what to do with the input using the `if-else if-else` and `case` statement. A basic flow diagram of the control loop for the NXT vehicle RTC program is shown in Figure 19 below.

The program fragment shown below shows the beginning and the end of the while loop for Program 11:

```
while (quit != 1 ) {
    key = _getch();
    if(key == 'w'){
        ...
    }else if(key == 's'){
        ...
    }else{
        ...
    }
}
```

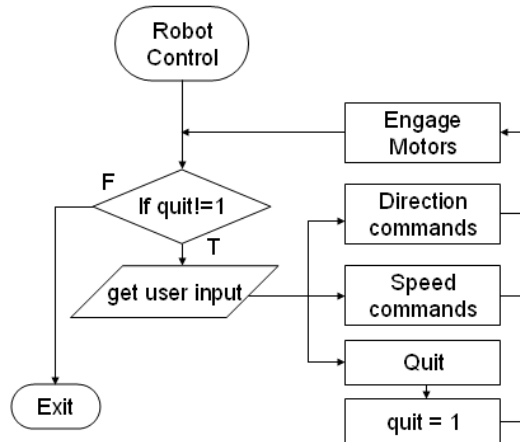


Figure 19: NXT vehicle RTC Control Loop Flow Diagram

When the program reaches this stage, the real time control begins. The while loop allows the program to keep asking the user's input until the 'r' key is pressed. When the 'r' key is pressed, the program will set quit variable is set to 1, which allows the program to exit out of the while loop.

For first line of the while loop, the program use the `_getch()` command to obtain a user input and store the user input to the variable `key`. After obtaining the user's input in a variable, the program use a `if-else if-else` statement to check which key was pressed. Depending on what key was pressed, the program will run a fragment of code that sends commands to the NXT.

Directional commands

The movements are controlled using the 'w', 's', 'a', and 'd' format. In Figure 18, the user interface used arrows to indicate the movement direction and associate each direction with a specific key. The available buttons for movements are 'w', 's', 'a', 'd', 'q', 'e', and 'x'.

When the key 'w' has been pressed, the `if-else if-else` statement will run the codes for the case 'w'. The program fragment for case 'w' is shown below:

```

if(key == 'w'){//up
    nxt.moveJointContinuousNB(NXT_JOINT2, NXT_FORWARD);
    nxt.moveJointContinuousNB(NXT_JOINT3, NXT_FORWARD);
    movemode = 'w';
}

```

In case 'w', the program will run joints `NXT_JOINT2` and `NXT_JOINT3` forward at the velocity `speedRatio`. Next, 'w' key is stored in the variable `movemode`, which will be used to indicate the current mode for NXT vehicle. Basically, the case 'w' will move the NXT vehicle forward at velocity `speedRatio`.

When the key 's' has been pressed, the `if-else if-else` statement will run the codes for the case 's'. The program fragment for case 's' is shown below:

```

else if(key == 's'){//down
    nxt.moveJointContinuousNB(NXT_JOINT2, NXT_BACKWARD);
    nxt.moveJointContinuousNB(NXT_JOINT3, NXT_BACKWARD);
    movemode = 's';
}

```

```
}
```

In case 's', the program will run the joints NXT_JOINT2 and NXT_JOINT3 backward at the velocity `speedRatio`. Next, 's' key is stored in the variable `movemode`, which will be used to indicate the current mode for NXT vehicle. Basically, the case 's' will move the NXT vehicle backward with velocity `speedRatio`.

When the key 'a' has been pressed, the `if-else if-else` statement will run the codes for the case 'a'. The program fragment for case 'a' is shown below:

```
else if(key == 'a'){//left
    nxt.moveJointContinuousNB(NXT_JOINT2, NXT_FORWARD);
    nxt.moveJointContinuousNB(NXT_JOINT3, NXT_BACKWARD);
    movemode = 'a';
}
```

In case 'a', the program will actuate joint NXT_JOINT2 forward at velocity `speedRatio` and actuate joint NXT_JOINT3 backward at velocity `speedRatio`. Next, 'a' key is stored in the variable `movemode`, which will be used to indicate the current mode for NXT vehicle.

When the key 'd' has been pressed, the `if-else if-else` statement will run the codes for the case 'd'. The program fragment for case 'd' is shown below:

```
else if(key == 'd'){//right
    nxt.moveJointContinuousNB(NXT_JOINT2, NXT_BACKWARD);
    nxt.moveJointContinuousNB(NXT_JOINT3, NXT_FORWARD);
    movemode = 'd';
}
```

In case 'd', the program will actuate joint NXT_JOINT2 backward at velocity `speedRatio` and actuate joint NXT_JOINT3 forward at velocity `speedRatio`. Next, 'd' key is stored in the variable `movemode`, which will be used to indicate the current mode for NXT vehicle.

When the key 'q' has been pressed, the `if-else if-else` statement will run the codes for the case 'q'. The program fragment for case 'q' is shown below:

```
else if(key == 'q'){//forward-left
    nxt.setJointSpeedRatios(0, speedRatio, 0.7*speedRatio);
    nxt.moveJointContinuousNB(NXT_JOINT2, NXT_FORWARD);
    nxt.moveJointContinuousNB(NXT_JOINT3, NXT_BACKWARD);
    movemode = 'q';
}
```

In case 'q', the program will actuate joint NXT_JOINT2 forward at velocity `speedRatio` and actuate joint NXT_JOINT3 forward at velocity `0.7*speedRatio`. Next, 'q' key is stored in the variable `movemode`, which will be used to indicate the current mode for NXT vehicle.

When the key 'e' has been pressed, the `if-else if-else` statement will run the codes for the case 'e'. The program fragment for case 'e' is shown below:

```
else if(key == 'e'){//forward-right
    nxt.setJointSpeedRatios(0, 0.7*speedRatio, speedRatio);
    nxt.moveJointContinuousNB(NXT_JOINT2, NXT_BACKWARD);
    nxt.moveJointContinuousNB(NXT_JOINT3, NXT_FORWARD);
    movemode = 'e';
}
```

In case 'e', the program will actuate joint NXT_JOINT2 forward at velocity $0.7 * \text{speedRatio}$ and actuate joint NXT_JOINT3 forward at velocity speedRatio . Next, 'e' key is stored in the variable `movemode`, which will be used to indicate the current mode for NXT vehicle.

When the key 'x' has been pressed, the `if-else if-else` statement will run the codes for the case 'x'. The program fragment for case 'x' is shown below:

```
else if(key == 'x'){//stop
    nxt.stopOneJoint(NXT_JOINT2);
    nxt.stopOneJoint(NXT_JOINT3);
    movemode = 'x';
}
```

In case 'x', the program will set the motor in NXT_JOINT2 and NXT_JOINT3 to zero velocity, and then set the motor to off idle mode. Next, 'x' key is stored in the variable `movemode`, which will be used to indicate the current mode for NXT vehicle. Basically, the case 'x' stops the motor and keep it turned off until another key is pressed.

Speed control

The speed of the motor is controlled by the number key '1', '2', '3', and '4'. In Figure 18, the user interface shows that each key has a specific speed ratio. For example, key '1' indicates 0.25 speed ratio, and key '2' indicate 0.50 speed ratio. As shown below, each of the key has its fragment of code.

```
else if(key == '1'){
    speedRatio = 0.25;
    ungetch(movemode);
}else if(key == '2'){
    speedRatio = 0.50;
    ungetch(movemode);
}else if(key == '3'){
    speedRatio = 0.75;
    ungetch(movemode);
}else if(key == '4'){
    speedRatio = 1;
    ungetch(movemode);
}
```

For each of the case, the fragment of code changes the variable `speedRatio` and performs an `ungetch()` command. The `ungetch()` command allows the program run the mode that it was previously saved in the variable `movemode` before the speed keys are pressed. Basically, the speed keys allow the program to change the speed of the NXT motor without changing the movement mode that it was in.

Functions for other keys

As mentioned before, the while loop allows the program to keep asking the user's input until the variable `quit` is set to 1. To quit the while loop, we must have a special case that sets the variable `quit` to 1. When the key 'r' is pressed, the `if-else if-else` statement will perform a fragment of code for case 'r'. The program fragment for case 'r' is shown below:

```
else if(key == 'r'){//quit
    printf("\nExiting program.\n");
    quit = 1;
}
```

When the 'r' key is pressed, the program will print out the statement 'exiting program' and set `quit` variable is set to 1, which allows the program to exit out of the while loop.

For the keys that is not specified to any cases, a default case is used for the time when the user input a wrong key. The program fragment for the default case is shown below:

```
else{
    printf("\nInvalid Input!\n");
}
```

This fragment prints 'Invalid Input!' to the user to indicate the key they just pressed is an invalid input.

Disconnecting your NXT

After the while loop, the NXT vehicle RTC program ends with the four lines shown below.

```
/* Disconnect from NXT */
nxt.disconnect();
```

These lines of code stop the NXT motors, disconnect the NXT from the computer.

4.5 Using NXT Sensors

Sensors converts a physical quantity and convert it to signals which can be read by the NXT or the computer. Sensors allows the communication between the outside environment to the NXT. The NXT is equipped with four sensor input ports and you can equip each port with a variety of different sensors. In this section, we are going to discuss about how to use the touch sensor and the ultrasonic sensor. In these discussion, two demonstration program will be presented. Please make sure your NXT vehicle are configured according to to Figure 20 to run these demonstration programs.

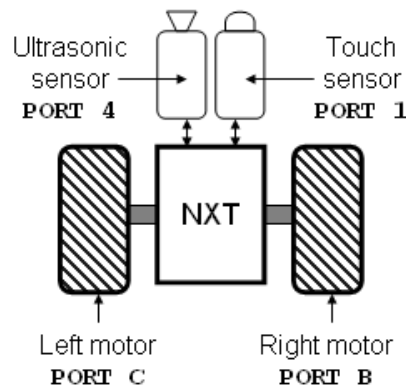


Figure 20: Sensor/Motor configuration of the NXT Vehicle

4.5.1 Using your touch sensor

After you have connected your NXT to your PC, you will need to set up the sensor if you would like to include sensors in your NXT program. For example, if you want to add components like

light sensor, ultrasonic sensor, and/or touch sensor, you will need to set up their connection using the `setSensor()` function. The `setSensor()` function will return 1 if no connection is established, so you can terminate the program if a sensor connection is not established. An example connection check for adding the Touch and Ultrasonic sensors to the NXT vehicle is as follow:

```
ChNXT nxt;

/* Check status of NXT connection */
if (nxt.connect()){
    exit(-1);
}

/* Setup sensors and check sensor connection */
int status1=2, status2=2;

/* Save status of NXT_SENSORPORT1, and NXT_SENSORPORT4 */
status1 = nxt.setSensor(NXT_SENSORPORT1,
    NXT_SENSORTYPE_TOUCH, NXT_SENSORMODE_BOOLEANMODE);

status2 = nxt.setSensor(NXT_SENSORPORT4,
    NXT_SENSORTYPE_ULTRASONIC, NXT_SENSORMODE_RAWMODE);

/* Check connection status of NXT_SENSORPORT1 */
if(status1) {
    exit(-1);
}

/* Check connection status of NXT_SENSORPORT4 */
if(status2) {
    exit(-1);
}
```

As in previous examples, the class `nxt`, is created, and the initial connection to the NXT is made. The next step is to initialize the NXT sensor ports to the correct types and ensure the sensors are working correctly. The int variables `status1` and `status2` are used to check the return value of the function `setSensor()`.

A common application of touch sensors for a vehicle robot is for obstacle detection. In order to demonstrate the use of the touch sensor, consider the touch sensor demo in Program 10.

Source Code

```
/* File name: touchsensor.ch

The purpose of this demo is to demonstrate the CH Mindstorms
Control Package's ability to control the NXT Mindstorm to use
the touch sensor. */
```

Program 10: touchsensor.ch Source Code


```

#include <nxt.h>

ChNXT nxt;
int status;
int touchValue;

/* Connect to NXT */
if (nxt.connect()) {
    printf("Fail to connect!\n");
    exit(-1);
}

/* Set sensor types */
status = nxt.setSensor(NXT_SENSORPORT1,
    NXT_SENSORTYPE_TOUCH, NXT_SENSORMODE_BOOLEANMODE);
if (status) {
    printf("Fail to setup sensors.\n");
    exit(-1);
}

/* set joint speed ratios */
nxt.setJointSpeedRatios(0, 0.25, 0.25);

/* Move Robot Forward */
nxt.moveJointContinuousNB(NXT_JOINT2, NXT_BACKWARD);
nxt.moveJointContinuousNB(NXT_JOINT3, NXT_BACKWARD);

/* Commands: */
while (1) {
    /* Get touch sensor data */
    nxt.getSensor(NXT_SENSORPORT1, touchValue);
    /* If touch sensor is triggered */
    if (touchValue < 0) {
        /* Move backward */
        nxt.moveJointContinuousNB(NXT_JOINT2, NXT_FORWARD);
        nxt.moveJointContinuousNB(NXT_JOINT3, NXT_FORWARD);
        delay(2);
        /* quit the while loop */
        break;
    }
}

/* Stop the motors */
nxt.stopTwoJoints(NXT_JOINT2, NXT_JOINT3);

/* Disconnect NXT */
nxt.disconnect();

```

Program 10: touchsensor.ch Source Code

Checking touch sensor connection

Program 10 is similar to Program 7, the only changes is the addition of the use of the touch sensor. Program 10 makes the NXT move forward until the touch sensor is triggered, after which it will back up and stop. One of the additions that is added in Program 10 is the initialization of the touch sensor. The fragment of the initialization of the touch sensor is shown below.

```
/* Set sensor types */
int status;

status = nxt.setSensor(NXT_SENSORPORT1,
    NXT_SENSORTYPE_TOUCH, NXT_SENSORMODE_BOOLEANMODE);
if (status){
    exit(-1);
}
```

In this fragment, the program use the `setSensor()` command to set the touch sensor to `NXT_SENSORPORT1`. The connection status between the NXT and the sensor is then returned in the variable called `status`. Next, the if statement check if the connection to the sensor is good. If the variable `status` is equal to 1, which means no sensor connection, the program will be exited and the rest of the codes will not be executed.

Using while loop

A while loop is a common method that is used for sensor data gathering. For every iteration of the while loop, the program checks the data gathered by the touch sensor. After gathering the data, the program decide what to do with the data. A simple flow diagram of the while loop of the touch sensor demo program is shown in Figure 21

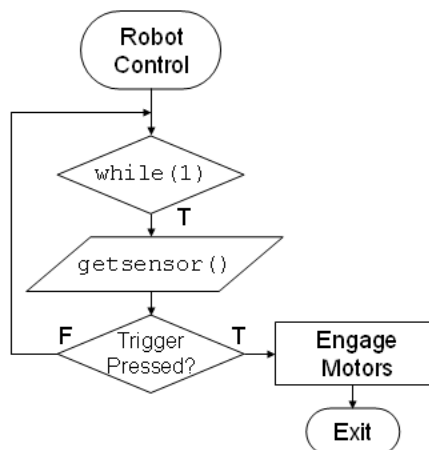


Figure 21: Flow Diagram of the while loop in Program 10

In Program 10, the while loop checks for the data of the touch sensor. If the touch sensor is triggered, the data of the touch sensor will be set to below 500. Then the program will move the NXT backward and disconnect the NXT. The while loop of the touch sensor demonstration program is described below:

```
while(1){
    /* Get touch sensor data and save into a variable*/
```

```

    nxt.getSensor(NXT_SENSORPORT1, touchValue);

    /* If touch sensor is triggered */
    if (touchValue < 0){
        /* Move backward */
        nxt.setJointSpeedRatios(0, 0.25, 0.25);
        nxt.vehicleRollBackward(360);
        break;
    }
}

```

In this while loop, the program uses the `getSensor()` command to get the data from `NXT_SENSORPORT1`, which is the port for the touch sensor according to Figure 20. Next, the program checks the touch sensor if it is pressed with the if statement. If the touch sensor has been triggered, the codes in the if statement will run. The codes inside the if statement is the same command for moving the NXT backward. After moving the NXT backward, the command `break` allows the program to exit out of the while loop. This while loop will never exit until the touch sensor is triggered and the `break` command is used.

4.5.2 Using your ultrasonic sensor

In order to demonstrate the use of the ultrasonic sensor, consider the ultrasonic sensor demo in Program 11. NOTE: If your robot gets stuck, put your hands in front of the ultrasonic sensor to quit the loop.

Source Code

```

/*File name: ultrasonicsensor.ch

The purpose of this demo is to demonstrate the CH Mindstorms
Control Package's ability to control the NXT Mindstorm to use
the ultra sonic sensor.*/

#include <nxt.h>

ChNXT nxt;
int status;
int ultraValue;
double speedRatio;

```

Program 11: `ultrasonicsensor.ch` Source Code

```

/* Connect to NXT */
if (nxt.connect()) {
    printf("Error: Cannot connect to Lego Mindstorm NXT.\n");
    exit(-1);
}

/* Set sensor types */
status = nxt.setSensor(NXT_SENSORPORT4,
    NXT_SENSORTYPE_ULTRASONIC, NXT_SENSORMODE_RAWMODE);
if (status) {
    exit(-1);
}

/* Commands: */
while (1) {
    /* get ultrasonic sensor data */
    nxt.getSensor(NXT_SENSORPORT4, ultraValue);

    /* If obstacle is really close */
    if (ultraValue < 35 && ultraValue > 0) {
        speedRatio = 0.25;
        /* Move backward */
        nxt.moveJointContinuousNB(NXT_JOINT2, NXT_BACKWARD);
        nxt.moveJointContinuousNB(NXT_JOINT3, NXT_BACKWARD);
        sleep(3);
        /* Quit the while loop */
        break;
    } /* Else if the obstacle is close */
    else if (ultraValue < 60) {
        speedRatio = .25;
    } /* Else if the obstacle is not close */
    else if (ultraValue < 100) {
        speedRatio = .50;
    } /* Else if there is no obstacle in sight */
    else if (ultraValue < 200) {
        speedRatio = .75;
    } /* Sensor value larger than 200 */
    else {
        speedRatio = .75;
    }
    /* Move forward (constantly)*/
    nxt.setJointSpeedRatios(0, speedRatio, speedRatio);
    nxt.moveJointContinuousNB(NXT_JOINT2, NXT_FORWARD);
    nxt.moveJointContinuousNB(NXT_JOINT3, NXT_FORWARD);
}

/* Stop the motors*/
nxt.stopTwoJoints(NXT_JOINT2, NXT_JOINT3);

/*Disconnect NXT*/
nxt.disconnect();

```

Program 11: ultrasonicsensor.ch Source Code (Continued.)

Checking touch sensor connection

Like Program 10, Program 11 is meant to be a brief demonstration of one method of using an ultrasonic sensor with a vehicle NXT. Similar to the initialization of the touch sensor, the initialization of the ultrasonic sensor is shown below:

```
/* Set sensor types */
int status;

status = nxt.setSensor(NXT_SENSORPORT4,
                      NXT_SENSORTYPE_ULTRASONIC, NXT_SENSORMODE_RAWMODE);

if (status){
    exit(-1);
}
```

In this program fragment, the `setSensor()` command sets the ultrasonic sensor to `NXT_SENSORPORT4`. Next, it checks the return value of the sensor connection status. The program will quit if the return value is 1, meaning there is no connection between the sensor and the NXT.

Contents in the while loop

In Program 11, the while loop uses the ultrasonic sensor to detect distances between the NXT and the obstacles in front of the NXT. The ultrasonic sensor will detect distances and the program code reacts to the data by slowing down or speeding up. The flow diagram of the while loop of Program 11 is shown in Figure 22.

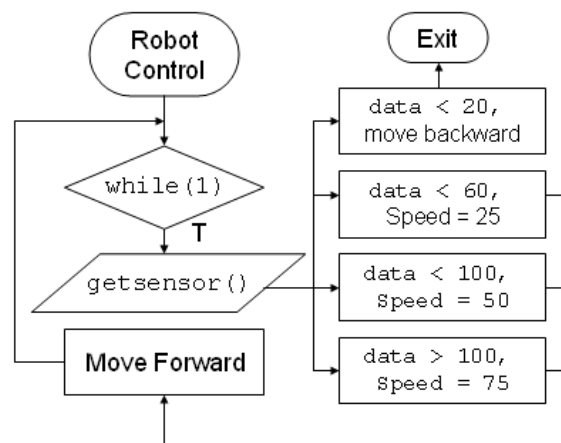


Figure 22: Flow Diagram of the while loop in Program 10

The while loop code block for Program 11 is shown below:

```
/* Commands: */
while(1){
    /* Get ultrasonic sensor data */
    nxt.getSensor(NXT_SENSORPORT4, ultrasonicValue);

    /* If obstacle is really close */
    if (ultrasonicValue < 20){
        speedRatio = 0.25;
    }
}
```

```

        /* Move backward */
        nxt.setJointSpeedRatios(0, speedRatio, speedRatio);
        nxt.vehicleRollBackward(360);
        /* Quit the while loop */
        break;
    }/* Else if the obstacle is close */
    else if(ultrasonicValue < 60){
        speedRatio = 0.25;
    }/* Else if the obstacle is not close */
    else if(ultrasonicValue < 100){
        speedRatio = 0.50;
    }/* Else if there is no obstacle in sight */
    else if(ultrasonicValue < 200){
        speedRatio = 0.75;
    }/* Sensor value larger than 200 */
    else{
        speedRatio = 0.75;
    }
    /* Move forward (constantly) */
    nxt.setJointSpeedRatios(0, speedRatio, speedRatio);
    nxt.moveJointContinuousNB(NXT_JOINT2, NXT_FORWARD);
    nxt.moveJointContinuousNB(NXT_JOINT3, NXT_FORWARD);
}

```

Similar to Program 10, the while loop in Program 11 also gathers the sensor data using the `getSensor()` command to gather data from the ultrasonic sensor in `NXT_SENSORPORT4`. Next, the if-else statement block determine what to do depending on the distance data from ultrasonic sensor.

- If the sensor value is below 20, which means the vehicle is very close to an obstacle, the program tells the vehicle to reverse, and then break out of the while loop.
- If the sensor value is above 20 and below 60, which means the vehicle is close to an obstacle, the program set the speed raio variable to 0.25.
- If the sensor value is above 60 and below 100, which means the vehicle is not close to an obstacle, the program set the speed ratio variable to 0.50.
- If the sensor value is above 100 and below 200, which means there is nothing in front of the vehicle, the program set the speed ratio variable to 0.75.
- If the sensor value is other value that is not mentioned above, the program set the speed variable to 0.75.

After the if-else statement block, the program sets the robot to move forward with velocity set at the speed variable. Then the program returns back to the beginning of the while loop, which is to gather data from the sensor again.

4.5.3 Autonomous Control Program

In the previous sections, we thoroughly covered the manual real time control program, which allows you to remote control your NXT vehicle with your keyboard. In this section, we will talk about the autonomous control program for the NXT vehicle. In an autonomous control program, the robot, which is the NXT, must be able to move around by itself without human commands or interventions. In order to achieve such task, the NXT must be able to detect obstacles using its sensors and steer away from the obstacle using its actuators. A typical autonomous control scheme is to sense, plan, and act, which is shown in Figure 23.

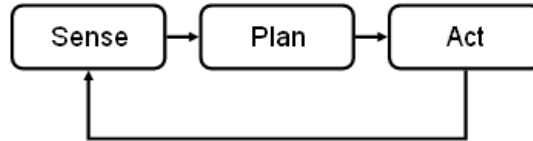


Figure 23: Sense Plan Act Diagram

- Sense is to gather data from the robot's surrounding.
- Plan is to plan the interaction between the robot and its surrounding using gathered data.
- Act is to act with robot's surrounding.

The main difference between the manual RTC program and the autonomous program is the content inside the while loop. In the manual RTC program, the codes inside the while loop scan for user's input and the robot acts on the input that the user provided. In the autonomous program, the codes inside the while loop perform the sense-plan-act cycle similarly to the diagram shown in Figure 23. Every cycle, the information is gathered from the sensor and send back to the computer. The computer will decide what to do depending on the sensor data. The autonomous control program for the NXT vehicle is described in Program 12.

Source Code

```

/* File name: vehicle_auto.ch

    The purpose of this demo is to demonstrate the CH Mindstorms
    Control Package's ability to control the machine robot model
    autonomously, as well as demonstrate how use sensor data from
    the NXT to controle it's actions. */
#include <conio.h>
#include <stdio.h>
#include <nxt.h>

ChNXT nxt;
double speedRatio = 0.25; //speed ratio of the motors. (default to .25)
int status1 = 2; //used to check for errors
int status2 = 2; //used to check for errors
int touchValue, ultraValue; //used to store sensor data
char key = 'x', //stores user input
      movemode = 'x'; //stores last movement command

/* Connect to NXT */
printf("Initializing vehicle and assuming control...");
if (nxt.connect()){
    printf("\nPress any key to exit.\n");
    while (!_kbhit()); //wait for keypress
    exit(-1);
}
  
```

Program 12: vehicle_auto.ch Source Code

```

/* Set sensor types */
status1 = nxt.setSensor(NXT_SENSORPORT1,
    NXT_SENSORTYPE_TOUCH, NXT_SENSORMODE_BOOLEANMODE);
status2 = nxt.setSensor(NXT_SENSORPORT4,
    NXT_SENSORTYPE_ULTRASONIC, NXT_SENSORMODE_RAWMODE);
if ((status1) || (status2)){
    printf("\nError initializing sensors.\nPress any key to exit.\n");
    while (!kbhit()); //wait for keypress
    exit(-1);
}

while (1) {
    /* check user input 'q' to quit */
    if (kbhit()){
        if (getch() == 'q'){
            printf("\nExiting.");
            break;
        }
    }

    /* get touch sensor. If pressed reverse and turn left */
    nxt.getSensor(NXT_SENSORPORT1, touchValue);
    if (touchValue < 0){
        nxt.moveJoint(NXT_JOINT2, 720);
        nxt.moveJoint(NXT_JOINT3, 720);
        delay(1);
        nxt.moveJoint(NXT_JOINT2, -720);
        nxt.moveJoint(NXT_JOINT3, 720);
    }

    /* get distance from UltraSonic sensor,
       set speed according to distance. Turn left if really close.*/
    nxt.getSensor(NXT_SENSORPORT4, ultraValue);
    if (ultraValue < 0){
        nxt.moveJoint(NXT_JOINT2, -720);
        nxt.moveJoint(NXT_JOINT3, -720);
        delay(1);
        nxt.moveJoint(NXT_JOINT2, 720);
        nxt.moveJoint(NXT_JOINT3, -720);
        delay(0.75);
    } else if (ultraValue < 30){
        speedRatio = 0.25;
    } else if (ultraValue < 50){
        speedRatio = 0.50;
    } else if (ultraValue < 100){
        speedRatio = 0.75;
    } else if (ultraValue < 200){
        speedRatio = 1;
    } else{
        speedRatio = 0.75;
    }
}

```

Program 12: vehicle_auto.ch Source Code (Continued.)


```

    /* Turn motors on (drive forward) */
    nxt.setJointSpeedRatios(0, speedRatio, speedRatio);
    nxt.moveJointContinuousNB(NXT_JOINT2, NXT_FORWARD);
    nxt.moveJointContinuousNB(NXT_JOINT3, NXT_FORWARD);
}
/* stop interfacing. This also stops the motors. */
nxt.disconnect();

```

Program 12: `vehicle_auto.ch` Source Code (Continued.)

In Program 12, the sensors that is used are the touch sensor and the ultra sonic sensor. These sensors are located in the front of the vehicle so that when the vehicle encounters an obstacle, the program will control the robot to avoid or steer away from it. A diagram of the vehicle and its sensor and actuators of the program is shown in Figure 20. Please make sure your NXT vehicle are configured according to to Figure 20 to run Program 12.

Exiting the while loop

In the autonomous program, there must be codes that allow the user to quit the autonomous program. Otherwise, the robot will roam forever until the batteries run out or until a deliberate shut down of the program. In the beginning of the while loop, the program checks for the user's input. If the user's input is 'q' to quit, then the program will break out of the while loop and safely disconnects the NXT. If the user's input is not 'q' or if the user did not input anything, the program will continue to the next section of the while loop. The program fragment for exiting the autonomous program is shown below.

```

/* check user input 'q' to quit */
if(kbhit()){
    if (getch()=='q'){
        printf("\nExiting.");
        break;
    }
}

```

In this program fragment, an if statement is used to check if a keyboard key has been hit. Next, if a keyboard key has been hit, another if statement checks if the input is 'q'. If both conditions are satisfied, the break statement will break out of the while loop of the program.

Touch sensor

The next section of the while loop uses the touch sensor to control the NXT vehicle. When the NXT contact some obstacle in the front, the touch sensor will be triggered. The autonomous program will notice that the touch sensor is triggered and command the NXT to steer away from the obstacle. The program fragment of the touch sensor is shown below.

```

/* get touch sensor. If pressed reverse and turn left */
nxt.getSensor(NXT_SENSORPORT1, touchValue);
if (touchValue <500){
    nxt.vehicleRollBackward(180);
    nxt.vehicleRotateLeft(360);
}

```

In the first line of this fragment, the NXT gathers data from `NXT_SENSORPORT1`, which is the port for the touch sensor. Next, it checks the value for the touch sensor data with an if statement.

If the value of the touch sensor data is less than 500, which means the touch sensor has been triggered, the program will execute the obstacle avoidance commands inside the if statement. The commands in the if statement control the NXT vehicle to reverse, then stop, and then steer left.

Ultrasonic sensor

The next part of the while loop uses the ultrasonic sensor to control the speed of the NXT vehicle. The ultrasonic sensor is used to detect the distance between itself to an incoming obstacle. The distance between the ultrasonic sensor and the incoming obstacle will tell the vehicle if it should slow down or speed up. For example, if the sensor senses nothing in front of the vehicle, the program will tell the vehicle to speed up; and if the sensor senses there is an obstacle in front, the program will tell the vehicle to slow down. The program fragment of the ultrasonic sensor is shown below.

```
/*
 * get distance from UltraSonic sensor,
 * set speedRatio according to distance. Turn left
 * if really close.
 */

nxt.getSensor(NXT_SENSORPORT4, ultrasonicValue);
if(ultrasonicValue <10){
    nxt.vehicleRollBackward(360);
    nxt.vehicleRotateRight(180);
    speedRatio=0;
} else if (ultraValue < 30)
    speedRatio = 0.25;
else if (ultraValue < 50)
    speedRatio = 0.50;
else if (ultraValue < 100)
    speedRatio = 0.75;
else if (ultraValue < 200)
    speedRatio = 1;
else
    speedRatio = 0.75;
```

In the first line of this fragment, the NXT gathers data from `NXT_SENSORPORT4`, which is the port for the ultrasonic sensor. Afterwards, there is a block of if-else statement to determine what speed is used for the sensor data gathered. The if-else block changes the speed variable of the vehicle depending on the ultrasonic sensor value. Here is the list of sensor value threshold and its commands.

- If the sensor value is below 10, which means the vehicle is very close to an obstacle, the program tells the vehicle to reverse, stop, and then steer left.
- If the sensor value is above 10 and below 30, which means the vehicle is close to an obstacle, the program set the speed ratio variable to 0.25.
- If the sensor value is above 30 and below 50, which means the vehicle sees an incoming obstacle, the program set the speed ratio variable to 0.50.
- If the sensor value is above 50 and below 100, the program set the speed ratio variable to 0.75.
- If the sensor value is above 100 and below 200, which means there is nothing in front of the vehicle, the program set the speed ratio variable to 1.
- If the sensor value is other value that is not mentioned above, the program set the speed ratio variable to 0.75.

Running forward

The autonomous program does not work if the robot is stationary. The last portion of the while loop sets the robot to be running forward if it is not performing other tasks. The program fragment for running forward is shown below.

```
/* Turn motors on (drive forward) */  
nxt.setJointSpeedRatios(0, speedRatio, speedRatio);  
nxt.moveJointContinuousNB(NXT_JOINT2, NXT_FORWARD);  
nxt.moveJointContinuousNB(NXT_JOINT3, NXT_FORWARD);
```

This program fragment command the vehicle to move forward continuously by setting both motors rotating positively at the variable `speedRatio`.

5 Controlling Non-Vehicle NXT Robots

Previously, the focus has been on controlling vehicle NXT designs. Ch Mindstorms NXT Control Package can also be used to control alternate NXT robot configurations. The following sections demonstrates Ch code that controls the Lego Machine NXT Robot and the Lego Bipedal Robot. These examples should give you a sufficient background using Ch to program the NXT to create codes for any Lego NXT creation you may make.

5.1 Controlling NXT Machine

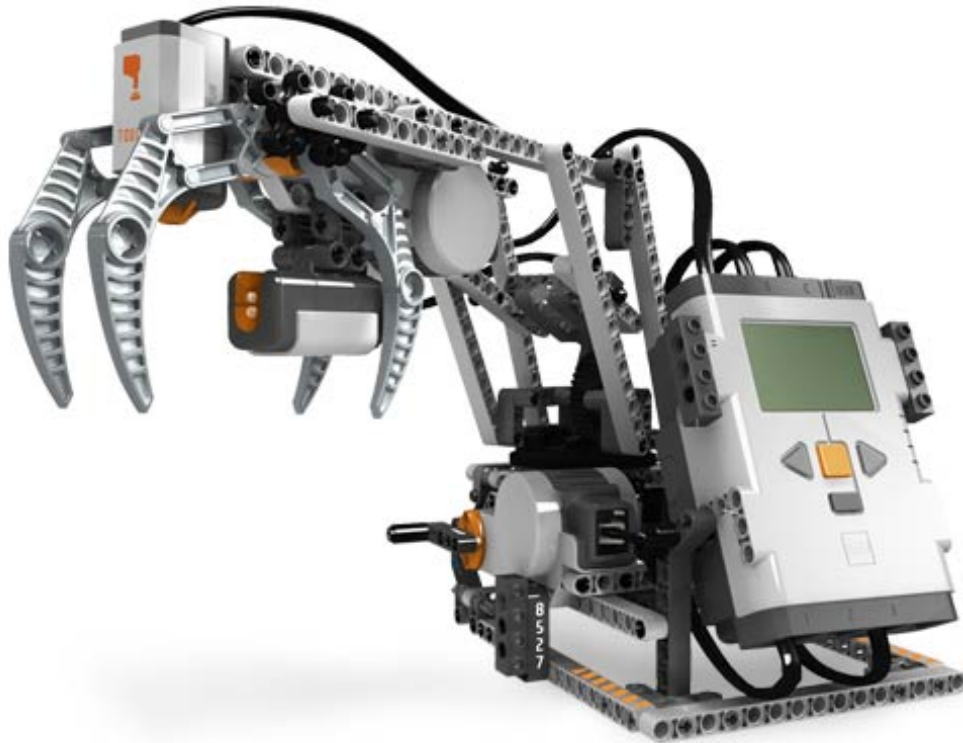


Figure 24: NXT Machine

The NXT mindstorm also comes with two other forms, one of these forms is the machine form as shown in Figure 24. In this section, the NXT machine form and the NXT machine demo program will be discussed. Compared to the NXT vehicle, the NXT machine uses three motors to manipulate its arm and two sensors for detection. The location and description of the components of the NXT machine is shown in Figure 25.

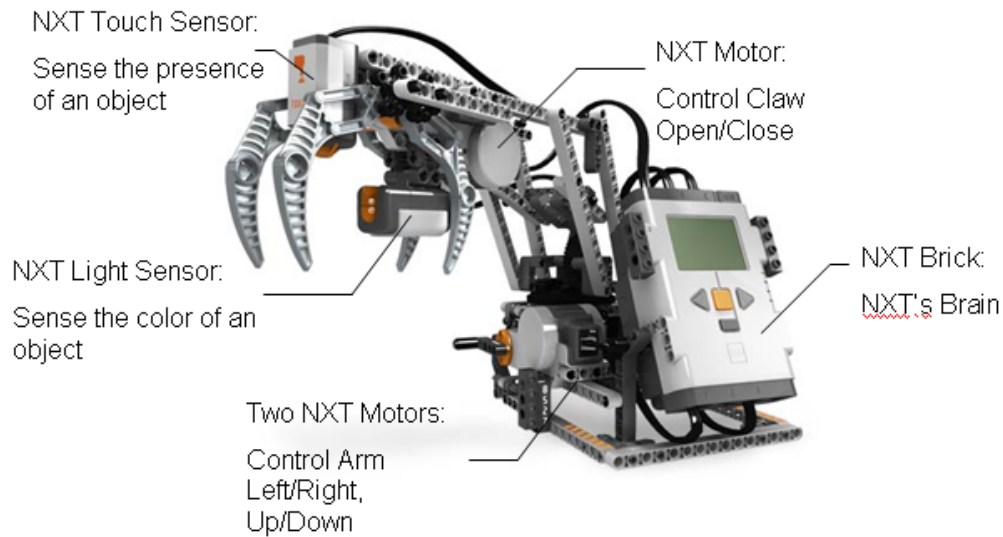


Figure 25: Components of the NXT Machine

As shown in Figure 25, one of its motor is responsible for moving its arm left and right. Another motor is responsible for moving its arm up and down. The last motor is responsible for controlling its claws open and close. There are two sensors mounted on the claw, they are the light sensor and the touch sensor. The NXT machine uses the light sensor to sense the color of the object it is handling. The NXT uses the touch sensor to sense if it has successfully grabbed an object. Please use the sensor/motor port configuration shown in Figure 26 for the Ch NXT machine demos programs described in later in this section.

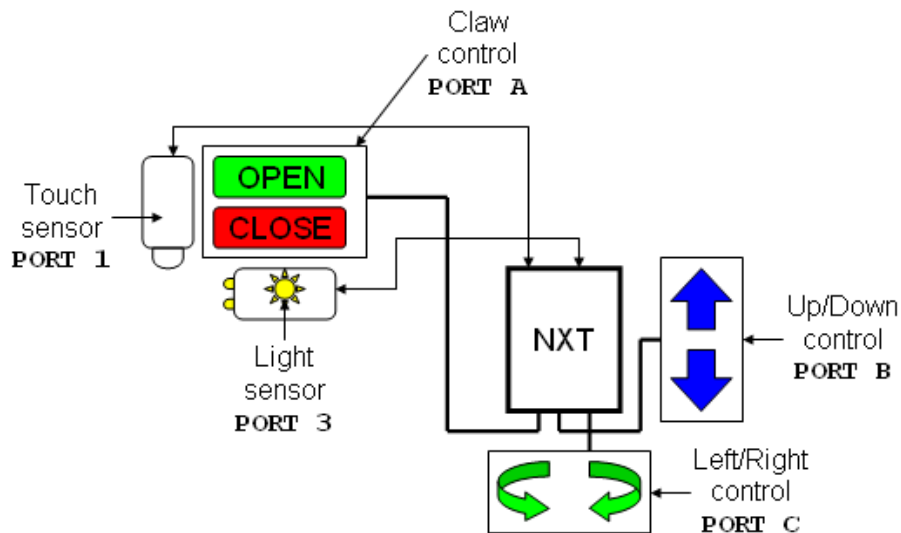


Figure 26: Sensor/Motor configuration of the NXT Machine

5.1.1 Manual Real Time Control Program

In this section the manual real time control for the NXT machine will be introduced and described. The manual RTC for the NXT machine allows the user to control the NXT machine manually via the keyboard. The user interface of the RTC program for the NXT machine is shown in Figure 27. The user interface and the user commands for the NXT machine RTC program is a bit different

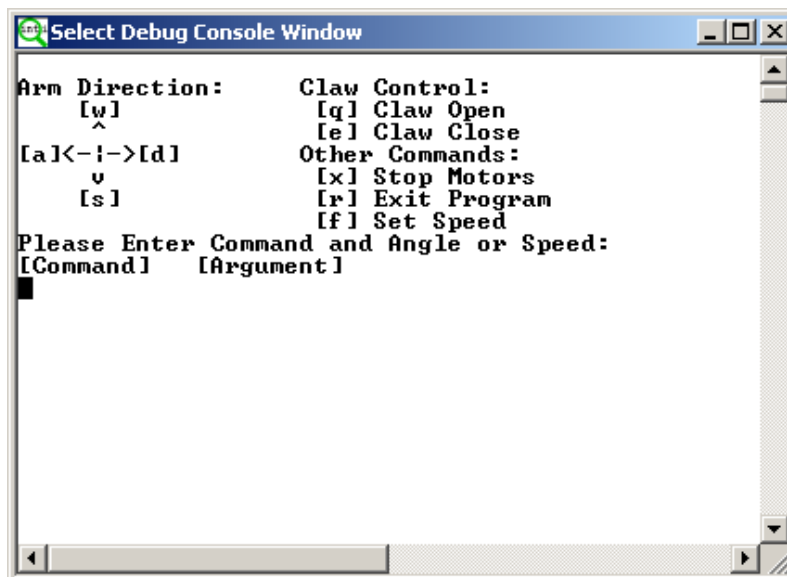


Figure 27: NXT vehicle RTC User Interface

compared to the NXT vehicle RTC program. Instead of controlling the direction by pressing one key, the user will be required to press a key for direction or command, and then enter a number to set the angle or speed. When a specific key is pressed during the execution of the NXT machine RTC program, the program uses a `if-else if-else` statement to perform a fragment of code that sends commands to the NXT to move in a direction or perform a task. If a directional key or a set speed key has been pressed, the program will ask for an user input for a number to set the arm to move at an angle or set the speed. If a discrete task key is pressed, like open or close claw, the program will not ask for an user input for a number. The list below is the list of commands and a short description of each command:

- The key "w" is to control the NXT arm to move up.
- The key "s" is to control the NXT arm to move down.
- The key "a" is to control the NXT arm to turn left.
- The key "d" is to control the NXT arm to turn right.
- The key "q" is to control the NXT claw to open.
- The key "e" is to control the NXT claw to close.
- The key "x" is to stop the NXT motors.
- The key "r" is to exit the manual RTC program.
- The key "f" is to set the NXT motor speed.

The NXT machine RTC program is described in Program 13. In the rest of this section, we are going to explain important parts of the manual rtc program in detail.

Source Code

```
/* File name: machine_rtc.ch

The purpose of this demo is to demonstrate the CH Mindstorms
Control Package's ability to control the machine robot model,
As well as demonstrate how to set up and get sensor data. */
#include <conio.h>
#include <stdio.h>
#include <nxt.h>          //this is the control package.

ChNXT nxt;
double speedRatio = 1;    //used to control the motor speedRatio.
int angle = 0;           //stores the angle input from the user.
int quit = 0;            //used to break out of the control loop
int status = 0;
int touchValue, lightValue;
double gearratio = (8.0 / 56) * (1.0 / 24); //gear ratio on the arm
char dir = 0;            //stores "direction to move" input from user.
char color[5];
char temp[20];
char *temp_loc;
printf("gear ratio: %f", gearratio);

/* call nxt_connect function and check for success */
printf("\nInitializing arm and assuming control...");
status = nxt.connect();
if (status) {
    while (!kbhit()); //wait for key press
    nxt.disconnect(); //stop interfacing. This also stops the motors.
    exit(0);
} //if (status)

/* Initialize sensor and check for success*/
status = nxt.setSensor(NXT_SENSORPORT1,
    NXT_SENSORTYPE_TOUCH, NXT_SENSORMODE_BOOLEANMODE);
if (status) {
    printf("\nSensor Setup failed. Exiting program.");
    while (!kbhit()); //wait for key press
    nxt.disconnect(); //stop interfacing. This also stops the motors.
    exit(0);
} //if (status)

status = nxt.setSensor(NXT_SENSORPORT3,
    NXT_SENSORTYPE_LIGHT_ACTIVE, NXT_SENSORMODE_RAWMODE);
if (status) {
    printf("\nSensor Setup failed. Exiting program.");
    while (!kbhit()); //wait for key press
    nxt.disconnect(); //stop interfacing. This also stops the motors.
    exit(0);
} //if (status == 0)
```

```

/*This is the user input loop, that gets the user input and
sends the commands to the NXT accordingly.
w,s move arm up and down
a,d move arm left and right
q,e open and close the claw
x stops the motor
r quits the program
f sets the speedRatio (default to 100)    */

printf("\nArm Direction:      Claw Control:\n");
printf("      [w]              [q] Claw Open\n");
printf("      ^                  [e] Claw Close\n");
printf("[a]<-|->[d]          Other Commands:\n");
printf("      v                  [x] Stop Motors\n");
printf("      [s]                [r] Exit Program\n");
printf("                        [f] Set Speed\n");
printf("Please Enter Command and Angle or Speed:\n");
printf("[Command]    [Argument]\n");

while (quit != 1)
{
    printf("\nEnter command: ");
    dir = getche();
    if ((dir == 'w') || (dir == 'a') || (dir == 's') ||
        (dir == 'd')) {
        printf("  Enter angle: ");
        scanf("%d", &angle);
    }
    if(dir == 'f'){
        printf("  Enter speed ratio:");
        scanf("%lf", &speedRatio);
    }

    if(dir == 'a'){ //Arm rotate left.
        nxt.moveJoint(NXT_JOINT3, (int)(angle / gearratio));
    }else if(dir == 'd'){ //Arm rotate right.
        nxt.moveJoint(NXT_JOINT3, (int)(-angle / gearratio));
    }else if(dir == 'w'){
        nxt.moveJoint(NXT_JOINT2, (int)(angle / gearratio));
    }else if(dir == 's'){//lowdder arm down
        nxt.moveJoint(NXT_JOINT2, (int)(-angle / gearratio));
    }else if(dir == 'q'){//claw open
        nxt.moveJointContinuousNB(NXT_JOINT1, NXT_BACKWARD);
        delay(1);
        nxt.stopOneJoint(NXT_JOINT1);
    }else if(dir == 'e'){//claw close
        nxt.moveJointContinuousNB(NXT_JOINT1, NXT_FORWARD);
        delay(1);
        nxt.stopOneJoint(NXT_JOINT1);
    }
}

```

Program 13: machine_rtc.ch Source Code (Continued.)


```

}else if(dir == 'x'){//stop
    nxt.stopAllJoints();
}else if(dir == 'r'){//quit
    printf("\nQuit.");
    quit = 1;
}else if(dir == 'f'){
    nxt.setJointSpeeds(speedRatio, speedRatio, speedRatio);
    printf("\nSpeed ratio set to %lf.", speedRatio);
}else
    printf("\n");

delay(0.2);
nxt.getSensor(NXT_SENSORPORT1, touchValue);
if (touchValue < 0) {
    printf("    The Ball was grabbed ");
    nxt.getSensor(NXT_SENSORPORT3, lightValue);
    if (lightValue < 500) {
        printf("and the color is red\n");
    }else {
        printf("and the color is blue\n");
    }
}
}

/* Disconnect from NXT */
nxt.disconnect();

```

Program 13: machine_rtc.ch Source Code (Continued.)

How does it work?

The initialization and the termination of the NXT machine RTC program is very similar to the NXT vehicle RTC program. The biggest difference between the two programs is in the while loop of the program. In this section, we will focus on how the `while()` loop of the NXT machine RTC program work internally.

While loop

Similar to the while loop of the NXT vehicle RTC program, the while loop of the NXT machine RTC program scans for the variable `quit` to see if it is set to 1. If the 'r' key has been pressed, the variable `quit` will be set to 1 and the while loop will terminate and the machine RTC program will be terminated. In the while loop, the user will be required to enter different types of command. Some commands are directional command, where the user needs to enter a number after the command. Some commands are discrete command, where the user does not need to enter another number. Instead of simply scanning for a key, the while loop has an additional if statement that scans for which key was pressed. If the key is a directional key, the program ask for the user to input an angle using the `scanf()` command. The fragment of the while loop is shown below:

```

while (quit != 1 ) {
    printf("\nEnter command: ");
    dir = _getch();
    if ((dir == 'w') || (dir == 'a') || (dir == 's')
        || (dir == 'd')){

```

```

        printf("  Enter angle: ");
        scanf("%d", &angle);
    }
    if(key == 'a'){
        ...
    }else if(key == 'd'){
        ...
    }else{
        ...
    }
}

```

Depending on what key was pressed, the program will run a fragment of code that sends commands to the NXT using the `if-else if-else` command.

Directional commands

The directional movements are controlled using the 'w', 's', 'a', and 'd' keys. In Figure 27, the user interface used arrows to indicate the movement direction and associate each direction with a specific key.

When the key 'a' has been pressed, the `if-else if-else` statement will run the codes for the case 'a'. The program fragment for case 'a' is shown below:

```

if(key == 'a'){
    nxt.moveJoint(NXT_JOINT3, (int)(angle / gearratio));
}

```

In case 'a', the program will run the joint `NXT_JOINT3` at velocity `speedRatio`, and to an `angle` divided by the gear ratio that the user has entered. Basically, for case 'a' the program will rotate the NXT machine arm left to an adjusted angle that the user has entered.

When the key 'd' has been pressed, the `if-else if-else` statement will run the codes for the case 'd'. The program fragment for case 'd' is shown below:

```

else if(key == 'd'){
    nxt.moveJoint(NXT_JOINT3, (int)(-angle / gearratio));
}

```

In case 'd', the program will run the joint `NXT_JOINT3` at velocity `-speedRatio`, and to an `angle` divided by the gear ratio that the user has entered. Basically, for case 'd' the program will rotate the NXT machine arm right to an adjusted angle that the user has entered.

When the key 'w' has been pressed, the `if-else if-else` statement will run the codes for the case 'w'. The program fragment for case 'w' is shown below:

```

else if(key == 'w'){
    nxt.moveJoint(NXT_JOINT2, angle);
}

```

In case 'w', the program will run the joint `NXT_JOINT2` at velocity `speedRatio`, and to a prescribed `angle` that the user has entered. Basically, for case 'w' the program will move the NXT machine arm upward to a prescribed angle that the user entered to an angle at a set speed ratio.

When the key 's' has been pressed, the `if-else if-else` statement will run the codes for the case 's'. The program fragment for case 's' is shown below:

```

else if(key == 's'){
    nxt.moveJoint(NXT_JOINT2, -angle);
}

```

In case 's', the program will run the joint NXT_JOINT2 at velocity `-speedRatio`, and to a prescribed `angle` that the user has entered. Basically, for case 'w' the program will move the NXT machine arm downward to a prescribed angle that the user entered to an angle at a set speed ratio.

Discrete commands

The discrete commands are commands that performs a specific task that can either be on or off. For example, open or close the claw, turn on or off the motors, or quit the program. For this program, the discrete commands does not require another parameter, so the user does not need to input another number for using these commands. These commands are accessed by entering the 'q', 'e', 'x', 'r' keys.

When the key 'q' has been pressed, the `if-else if-else` statement will run the codes for the case 'q'. The program fragment for case 'q' is shown below:

```

else if(key == 'q'){
    nxt.moveJointContinuousNB(NXT_JOINT1, NXT_BACKWARD);
    delay(1);
    nxt.stopOneJoint(NXT_JOINT1);
}

```

In case 'q', the program will run the joint NXT_JOINT1 at velocity `speedRatio` for 1 seconds. Next, the program will hold the position of the joint at that spot, thus keeping the machine claw open. Basically, for case 'q' the program will open the machine claw.

When the key 'e' has been pressed, the `if-else if-else` statement will run the codes for the case 'e'. The program fragment for case 'e' is shown below:

```

else if(key == 'e'){
    nxt.moveJointContinuousNB(NXT_JOINT1, NXT_FORWARD);
    delay(1);
    nxt.stopOneJoint(NXT_JOINT1);
}

```

In case 'e', the program will run the joint NXT_JOINT1 at velocity `speedRatio` for 1 seconds. Next, the program will hold the position of the motor at that spot, thus keeping the machine claw close. Basically, for case 'e' the program will close the machine claw.

When the key 'x' has been pressed, the `if-else if-else` statement will run the codes for the case 'x'. The program fragment for case 'x' is shown below:

```

else if(key == 'x'){
    nxt.stopAllJoints();
}

```

In case 'x', the program will stop all the motors, and turn the mode to off.

When the key 'r' has been pressed, the `if-else if-else` statement will run the codes for the case 'r'. The program fragment for case 'r' is shown below:

```

else if(key == 'r'){
    printf("\nQuit.");
    quit = 1;
}

```

In case 'x', the program will print the string "Quit." and set the variable `quit` to 1. By setting the variable `quit` to 1, the while loop will be terminated, thus quitting the program.

Speed ratio setup

To set the speed ratio of the movement of the arm, the user can enter the key 'f' and enter the speed ratio. The speed ratio of joints are in the range of 0 to 1. The program fragment of case 'f' is shown below:

```

else if(key == 'f'){
    printf("    Enter the speed ratio (0 to 1):");
    scanf("%lf", &speedRatio);
    printf("\nSpeed ratio set to %lf.", speedRatio);
}

```

Using the sensors

After the switch cases, the while loop will use the sensors to detect if the claw has grabbed an object or not. If the object has been detected, the program will also try to determine the color of the object using its light sensor. In this program, the object that is grabbed is assumed to be a ball, and the color of the ball is assumed to be red or blue. The program fragment for this task is described below:

```

delay(0.200);
nxt.getSensor(NXT_SENSORPORT1, touchValue);
if (touchValue < 0){
    printf("    The Ball was grabbed ");
    nxt.getSensor(NXT_SENSORPORT3, colorValue);
    if (colorValue < 500){
        printf("and the color is red\n");
    }else{
        printf("and the color is blue\n");
    }
}
}

```

In this fragment, the program will delay for 200 milliseconds and then grab the sensor value stored in `NXT_SENSORPORT1` using the `getSensor()` command, which is the touch sensor. Afterward, the if statement checks if the claw has grabbed an object. If the sensor value for the touch sensor is greater than 500, the touch sensor is not triggered, so there is the NXT detected that there is no object in its claw. If the sensor value for the touch sensor is less than 500, the touch sensor is triggered and the NXT detected that the claw has grabbed an object.

When the touch sensor is triggered, the program will continue in the if statement, and the program will print out that "The Ball was grabbed" in the screen and it get the sensor value stored in `NXT_SENSORPORT3`, which is the light sensor. Next, the program will determine the color of the ball using the light sensor value. If the light sensor value is less than 500, the NXT will detect that the ball that was grabbed is red and program will print out "and the color is red". If the light sensor value is greater than 500, the NXT will detect that the ball that was grabbed is blue and program will print out "and the color is blue".

5.1.2 Autonomous Control Program

In this section, the autonomous control program for the NXT machine will be introduced. This autonomous program uses the NXT machine arm to scan it's surrounding. It performs this task by rotating its arm by an angle step and collect distance data with an ultrasonic sensor as it is rotating. At the end of the program, the collected data will be stored in a data file called 'output.csv', and a polar diagram of the data will be display for the user. The NXT machine automatic control program is described in Program 14. In the rest of this section, we are going to explain important parts of the automatic control program in detail.

Source Code

```
/*File name: machine_auto.ch

The purpose of this demo is to demonstrate the CH Mindstorms
Control Package's ability to control the machine robot model
autonomously, as well as demonstrate how to collect and plot
sensor data from the NXT.*/
#include <conio.h>
#include <stdio.h>
#include <chplot.h>
#include <nxt.h>

CPlot plot;
ChNXT nxt;
double speedRatio = 0.30;
int quit = 0,      //used to exit for loop
    i,             //counter variable
    status;        //stores status of function
int ultraValue, position;
double gearratio = (8.0 / 56) * (1.0 / 24);
enum {numpoints = 20}; //desired number of data points
const int anglestep = 2; //angle moved between steps
double angle[numpoints]; //angle calculated from the tachometer
double distance[numpoints]; //data received from the ultrasonic sensor

/* Connect to NXT exit if failure */
if (nxt.connect()) {
    printf("\nPress any key to quit.");
    while (!_kbhit()); //wait for key press
    exit(-1);
}

/* Initialize arm. (Set sensor types and initialize variables) */
printf("\nInitializing arm for autonomous control...\n");
status = nxt.setSensor(NXT_SENSORPORT4,
    NXT_SENSORTYPE_ULTRASONIC, NXT_SENSORMODE_RAWMODE);
if (status) {
    printf("\nSensor Setup failed. Exiting program.");
}
```

Program 14: machine_auto.ch Source Code

```

    while (!_kbhit()); //wait for key press
    nxt.disconnect(); //stop interfacing. This also stops the motors.
    exit(-1);
}

for (i = 0; i < numpoints; i++) {
    angle[i] = 0;
    distance[i] = 0;
}

/* print usage information to the user*/
printf("\n%d Data points will be collected with a"
       "step size of %d.", numpoints, anglestep);
printf("\nPlease ensure that the arm can rotate"
       "%d degrees from its current position.",
       (numpoints*anglestep));
printf("\nPress any key to continue. Press q at any time to quit.");

if (getch() == 'q') {
    printf("\nQuitting program.");
    delay(1.5);
    exit(0);
}

/* begin Autonomous loop*/
for (i = 0; i < numpoints; i++) {
    printf("hello\n");
    /* get sensor data, if success print data, else print error*/
    if ((nxt.getSensor(NXT_SENSORPORT4, ultraValue)) == 0) {
        distance[i] = ultraValue;
        if ((nxt.getJointAngle(NXT_JOINT1, angle[i])) == 0) {
            printf("\nSample: %d, distance: %d, Angle: %lf",
                   i, distance[i], angle[i]);
        }
    }
    else
        printf("\nError!");

    /* check if q was pressed and if so exit program*/
    if (!_kbhit) {
        if (getch() == 'q') {
            printf("\nQuitting program.");
            break;
        }
    }

    /* rotate arm by anglestep (rotate motor anglestep/gear ratio)*/
    nxt.moveJoint(NXT_JOINT1, (anglestep / gearratio));
    delay(1);
} //end of for(i=0;i<numpoints-1;i++)

```

Program 14: machine_auto.ch Source Code (Continued.)

```

/* Stop interfacing. This also stops the motors and sensors.*/
nxt.disconnect();
printf("\n");

//plot data in CH
plot.data2DCurve(angle, distance, numpoints);
plot.grid(PLOT_ON);
plot.plotting();

```

Program 14: `machine_auto.ch` Source Code (Continued.)

Please use the Figure 28 to connect your NXT devices for the autonomous control program.

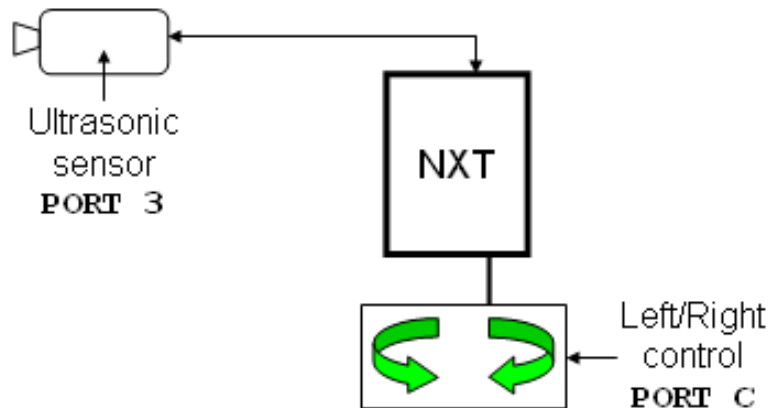


Figure 28: NXT vehicle RTC User Interface

How does it work?

In this autonomous program, a for loop is used instead of a while loop. The for loop will collect data, print out data, and rotate the arm at an angle step for every loop. Some of the parameters are hardcoded in the program, for example, number of loops and angle steps, so the user cannot change them as the autonomous program is executed. These parameters are shown in the program fragment below:

```

enum {numpoints=90};    //desired number of data points
const int anglestep=2; //angle moved between steps
double angle[numpoints]; //angle calculated from the tachometer
int distance[numpoints]; //data received from the ultrasonic sensor

```

The variable `numpoints` determines how many number of times the for loop will run and the variable `angles` determines how much the arm rotates in degrees of angle. Another feature this program has is the usage information printout described in the program fragment below.

```

printf("\n%d Data points will be collected with a"
      "step size of %d.",numpoints,anglestep);

printf("\nPlease ensure that the arm can rotate"
      "%d degrees from its current position.",(numpoints*anglestep));

printf("\nPress any key to continue. Press q at any time to quit.");

if(getch()=='q'){
    printf("\nQuitting program.");
    delay(1.500);
    exit(-1);
}

```

In this program fragment, the program will print out how many data point will be collected with the angle step size. Next, it will calculate and print out the full rotation angle of the robot arm and ask the user to ensure that the arm can rotate that amount of angle. Lastly, the program asks the user to continue or quit the program.

For loop

The for loop is the main part of the autonomous program for the NXT machine. The for loop uses a series of if-else statements to perform data collection and arm movement. There are three sections for this for loop. The first section is to collect, store, and print ultrasonic data and angle rotation data. The second section scans for user input to see if the user has pressed 'q' to quit the program. The last section is to rotate the arm by an angle step. The program fragment below is the for loop for the autonomous program for the NXT machine.

```

for(i=0;i<numpoints;i++){
    /* get sensor data, if success print data, else print error*/
    if((nxt.getSensor(NXT_SENSORPORT4, ultraValue))){
        distance[i]= ultraValue;
        if (nxt.getJointAngle(NXT_SENSORPORT3, angle[i] == 0)){
            printf("\nSample: %d, distance: %d, Angle: %lf",
                  i, distance[i],angle[i]);
        }
    }else
        printf("\nError!");

    /* check if q was pressed and if so exit program */
    if (!_kbhit){
        if(getch()=='q'){
            printf("\nQuitting program.");
            break;
        }
    }

    /* rotate arm by anglestep (rotate motor
       anglestep/gear ratio)*/
    nxt.moveJoint(NXT_JOINT3, (anglestep/gearratio));
    delay(1);
}

```

The first section of the for loop begins at the line after the first comment and ends at the line before the second comment. The first section begins by getting the ultrasonic sensor data and

store it in an array. If the program is able to retrieve the data, the program will also get the data from the tachometer and convert it to angle. The calculated angle will be stored in another array. Next, the program will print the sample number, distance detected by ultrasonic sensor, and angle rotated by the motor. If the program is unable to retrieve the data, the program will print error.

The second section of the for loop begins at the line after the second comment and ends at the line before the third comment. In this section, the program checks if a key has been hit by the user, if no key has been hit, this section is skipped. If a key has been hit and it happened to be the 'q' key, the program will print 'Quitting program' and the program will be aborted.

The third section of the for loop begins at the line after the third comment and ends at the end of the for loop. In this section, the program controls the motor to rotate at a given angle using the `moveJoint()` command. Lastly, the program freezes for 1 second by using the `delay()` command.

Plotting data

In addition to creating and storing a data file, the program also plots a polar diagram for the user to visualize the data. The program fragment below are the commands for plotting the data in a polar diagram.

```
//plot data in CH using a polar graph
plot.polarPlot(PLOT_ANGLE_DEG);
plot.data2DCurve(angle, distance, numpoints);
plot.sizeRatio(1);
plot.grid(PLOT_ON);
plot.plotting();
```

In this fragment, the program uses the CPlot class commands to do its plotting. First, the program use the function `polarPlot()` to set the plot to polar and degrees in angle. Next, the program use the function `data2DCurve()` to insert the collected data onto the polar plot. Afterward, the program uses the function `sizeRatio()` function and `grid()` command to correct the size of the plot and to add grid to the plot. Finally, the program creates the plot by using the function `plotting()`.

5.2 Controlling NXT Humanoid



Figure 29: NXT Humanoid

The third form of the NXT mindstorm is the humanoid form as shown in Figure 29. The NXT humanoid uses two of its motors to perform the walking motion. Also, the NXT humanoid uses its last motor to control the rotation of its head. The NXT humanoid is equipped with four sensors, a sound sensor on its right hand, a touch sensor on its left hand, a light sensor in the back, and an ultrasonic sensor on its head. In the next section, the real time control program for the NXT humanoid will be discussed. Please configure your NXT sensors and motors according to Figure 30.

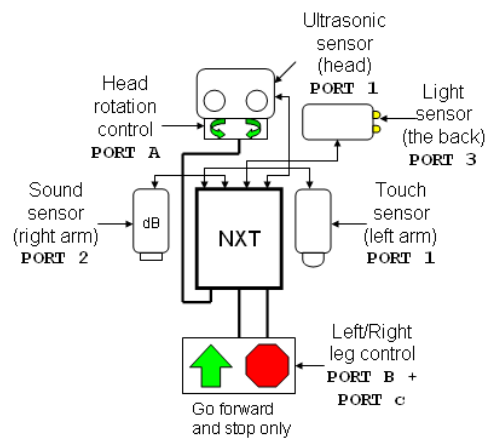


Figure 30: Sensor/Motor configuration of the NXT Humanoid

5.2.1 Manual Real Time Control Program

The real time control program of the NXT humanoid is similar to the real time control program of the NXT vehicle. The RTC program of the NXT humanoid allows the user to control the robot's leg movement and head rotation using the keyboard. In addition, the RTC program allow the user to print out data that has been collected by the NXT sensor. Figure 31 shows the user interface of the NXT humanoid.

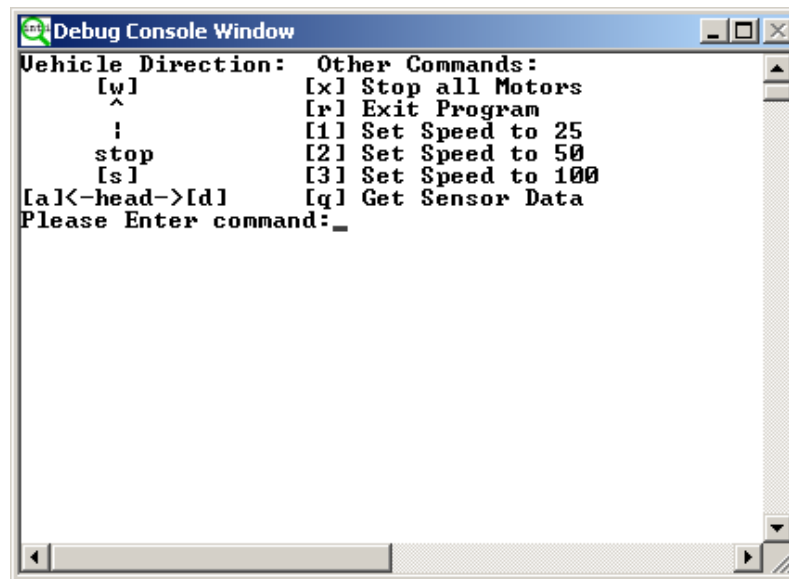


Figure 31: NXT Humanoid RTC User Interface

The list below is the list of commands:

- The key "w" is to control the NXT humanoid to walk forward.
- The key "s" is to control the NXT humanoid to stop.
- The key "a" is to control the NXT humanoid head to turn left.
- The key "d" is to control the NXT humanoid head to turn right.
- The key "q" is to print out sensor data.
- The key "x" is to stop all of the NXT motors.
- The key "r" is to exit the RTC program.
- The number key is to set the NXT motor speed.

The NXT humanoid real time control program is described in Program 15. In the rest of this section, we are going to explain important parts of the manual RTC program in detail.

Source Code

```
/* File name: humanoid_rtc.ch

The purpose of this demo is to demonstrate the CH Mindstorms
Control Package's ability to control the Humanoid Robot Model,
as well as demonstrate how to get sensor data. */
#include <conio.h>
#include <stdio.h>
#include <nxt.h>

ChNXT nxt;
double speedRatio = 0.25;//speedRatio of the motors. (default to 25)
int quit = 0, //used by quit case to exit the loop
    status1, //used to check for errors
    status2, //used to check for errors
    status3, //used to check for errors
    status4; //used to check for errors
char key = 'x', //stores the input from the user
    movemode = 'x'; //stores the last movement command

/* Connect to NXT */
printf("Initializing vehicle and assuming control...");
if (nxt.connect()) {
    printf("\nPress and key to exit.\n");
    while (!kbhit()); //wait for keypress
    exit(0);
}

/* Set sensor types */
status1 = nxt.setSensor(NXT_SENSORPORT1,
    NXT_SENSORTYPE_TOUCH, NXT_SENSORMODE_BOOLEANMODE);
status2 = nxt.setSensor(NXT_SENSORPORT2,
    NXT_SENSORTYPE_SOUND_DB, NXT_SENSORMODE_RAWMODE);
status3 = nxt.setSensor(NXT_SENSORPORT3,
    NXT_SENSORTYPE_LIGHT_INACTIVE, NXT_SENSORMODE_RAWMODE);
status4 = nxt.setSensor(NXT_SENSORPORT4,
    NXT_SENSORTYPE_ULTRASONIC, NXT_SENSORMODE_RAWMODE);
if ((status1) || (status2) || (status3)
    || (status4)) {
    printf("\nError initializing sensors.\nPress any key to exit.\n");
    while (!kbhit()); //wait for key press
    exit(0);
}

/* GUI display */
printf("Vehicle Direction:  Other Commands:");
printf("\n      [w]                [x] Stop all Motors");
printf("\n      ^                  [r] Exit Program");
printf("\n      |                  [1] Set Speed Ratio to 0.25");
```

Program 15: humanoid_rtc.ch Source Code

```

printf("\n      stop      [2] Set Speed Ratio to 0.50");
printf("\n      [s]      [3] Set Speed Ratio to 0.75");
printf("\n[a]<-head->[d]      [q] Get Sensor Data\n");
printf("Please Enter command:");

/* Control loop. Interprets user command and does action*/
while (quit != 1){
    nxt.setJointSpeedRatios(0.3, speedRatio, speedRatio);
    key = _getch();
    if(key == 'w'){//up
        nxt.moveJointContinuousNB(NXT_JOINT2, NXT_FORWARD);
        nxt.moveJointContinuousNB(NXT_JOINT3, NXT_FORWARD);
        movemode = 'w';
    }else if(key == 's'){ //down
        nxt.moveJointContinuousNB(NXT_JOINT2, NXT_BACKWARD);
        nxt.moveJointContinuousNB(NXT_JOINT3, NXT_BACKWARD);
        movemode = 's';
    }else if(key == 'd'){//right
        nxt.moveJointContinuousNB(NXT_JOINT1, NXT_FORWARD);
    }else if(key == 'a'){//left
        nxt.moveJointContinuousNB(NXT_JOINT1, NXT_BACKWARD);
    }else if(key == 'q'){//print sensor
        printSensor(&nxt);
    }else if(key == 'x'){//stop
        nxt.stopAllJoints();
        movemode = 'x';
    }else if(key == 'r'){//quit
        printf("\nExiting program.\nPress any key to exit.");
        quit = 1;
    }else if(key == '1'){//speedRatio .25
        speedRatio = 0.25;
        ungetch(movemode);
    }else if(key == '2'){//speedRatio .50
        speedRatio = 0.50;
        ungetch(movemode);
    }else if(key == '3'){//speedRatio .75
        speedRatio = 0.75;
        ungetch(movemode);
    }else if(key == '4'){//speedRatio 1
        speedRatio = 1;
        ungetch(movemode);
    }else{
        printf("\nInvalid Input!\n");
    }
}

/* Disconnect from NXT */
nxt.disconnect();

```

Program 15: humanoid_rtc.ch Source Code (Continued.)

```

int printSensor(ChNXT *nxt) {
    int touchValue = 0;
    int ultraValue = 0;
    int soundValue = 0;
    int lightValue = 0;

    /* get values from NXT */
    nxt->getSensor(NXT_SENSORPORT1, touchValue);
    nxt->getSensor(NXT_SENSORPORT2, soundValue);
    nxt->getSensor(NXT_SENSORPORT3, lightValue);
    nxt->getSensor(NXT_SENSORPORT4, ultraValue);

    /* display the values */
    if (touchValue < 0)
        printf("\n\nThe touch sensor has been activated.\n",
            touchValue);
    else
        printf("\nThe touch sensor has not been activated.\n");

    printf("The distance reported by the ultrasonic sensor is %d.\n",
        ultraValue);
    /*
    if (light<500) printf("\nThe touch sensor has been activated\n");
    else printf("\nThe touch sensor has been activated\n");
    */
    printf("The light level is %d.\n", lightValue);
    printf("The Sound level is %dB\n\n\n", soundValue);

    /* GUI display */
    printf("Vehicle Direction:  Other Commands:");
    printf("\n      [w]          [x] Stop all Motors");
    printf("\n      ^          [r] Exit Program");
    printf("\n      |          [1] Set Speed to 25");
    printf("\n      stop       [2] Set Speed to 50");
    printf("\n      [s]        [3] Set Speed to 75");
    printf("\n[a]<-head->[d]    [q] Get Sensor Data\n");
    printf("Please Enter command:");
    return 0;
}

```

Program 15: humanoid_rtc.ch Source Code (Continued.)

How does it work?

The the main difference between the RTC program for the NXT humanoid and the NXT vehicle is the content in the switch cases. Other than the switch cases, the while loop of the RTC program is the same as the previous RTC program. When the key 'r' has been pressed, the **if-else if-else** statement will run the codes for the case 'r'. In the case 'r', the variable quit will be to 1, which will allow the program to exit the while loop, thus quitting the program.

When the key 'w' has been pressed, the **if-else if-else** statement will run the codes for the case 'w'. The program fragment for case 'w' is shown below:

```

if(key == 'w')//up
    nxt.moveJointContinuousNB(NXT_JOINT2, NXT_FORWARD);
    nxt.moveJointContinuousNB(NXT_JOINT3, NXT_FORWARD);
    movemode='w';
    break;

```

In case 'w', the program will run joints NXT_JOINT2 and NXT_JOINT3 at velocity `speedRatio`. Basically, for case 'w' the program will control the NXT humanoid to walk forward at a speed ratio.

When the key 's' has been pressed, the `if-else if-else` statement will run the codes for the case 's'. The program fragment for case 's' is shown below:

```

else if(key == 's'){//down
    nxt.stopOneJoint(NXT_JOINT2);
    nxt.stopOneJoint(NXT_JOINT3);
    movemode='s';
}

```

In case 's', the program will stop joints NXT_JOINT2 and NXT_JOINT3 and turn them to off. Basically, for case 's' the program will stop the NXT humanoid from walking forward.

When the key 'a' has been pressed, the `if-else if-else` statement will run the codes for the case 'a'. The program fragment for case 'a' is shown below:

```

else if(key == 'a'){//left
    nxt.setJointSpeedRatio(NXT_JOINT1, 0.3);
    nxt.moveJointContinuousNB(NXT_JOINT1, NXT_BACKWARD);
}

```

In case 'a', the program will run joints NXT_JOINT1 at a speed ratio of 0.3. Basically, for case 'a' the program will rotate the NXT humanoid head left.

When the key 'd' has been pressed, the `if-else if-else` statement will run the codes for the case 'd'. The program fragment for case 'd' is shown below:

```

else if(key == 'd'){//right
    nxt.setJointSpeedRatio(NXT_JOINT1, 0.3);
    nxt.moveJointContinuousNB(NXT_JOINT1, NXT_FORWARD);
}

```

In case 'd', the program will run the joint NXT_JOINT1 at a speed ratio of 0.3. Basically, for case 'd' the program will rotate the NXT humanoid head right.

When the key 'q' has been pressed, the `if-else if-else` statement will run the codes for the case 'q'. The program fragment for case 'q' is shown below:

```

else if(key == 'q'){//print sensor
    printSensor();
}

```

In case 'q', the program will run the function `printSensor()`, which will get sensor data from each data and print these data out for the user. The details of the `printSensor()` function will be discussed later in this section.

When the key 'x' has been pressed, the `if-else if-else` statement will run the codes for the case 'x'. The program fragment for case 'x' is shown below:

```
else if(key == 'x'){//stop
    nxt.stopOneJoint(NXT_JOINT2);
    nxt.stopOneJoint(NXT_JOINT3);
    movemode='x';
}
```

In case 'x', the program will stop all the motors connected to the NXT and set them to off idle mode.

Printing sensor data

The function definition for the function `printSensor` is shown in the program fragment below:

```
int printSensor(ChNXT *nxt){
    int touchValue=0;
    int ultraValue=0;
    int soundValue=0;
    int lightValue=0;

    nxt->getSensor(NXT_SENSORPORT1, touchValue);
    nxt->getSensor(NXT_SENSORPORT2, ultraValue);
    nxt->getSensor(NXT_SENSORPORT3, soundValue);
    nxt->getSensor(NXT_SENSORPORT4, lightValue);

    if (touch < 0)
        printf("\n\nThe touch sensor has been activated.\n", touchValue);
    else
        printf("\nThe touch sensor has not been activated.\n");

    printf("The distance reported by the ultrasonic sensor is %d.\n",
           ultraValue);

    /*
    if (light<500)
        printf("\nThe touch sensor has been activated\n");
    else
        printf("\nThe touch sensor has been activated\n");
    */
    printf("The light level is %d.\n",lightValue);
    printf("The Sound level is %dDb\n\n",soundValue);

    //GUI display
    printf("Vehicle Direction:  Other Commands:");
    printf("\n      [w]          [x] Stop all Motors");
    printf("\n      ^           [r] Exit Program");
    printf("\n      |           [1] Set Speed Ratio to 0.25");
    printf("\n      stop        [2] Set Speed Ratio to 0.50");
    printf("\n      [s]         [3] Set Speed Ratio to 0.75");
```



```

    printf("\n[a]<-head->[d]      [q] Get Sensor Data\n");
    printf("Please Enter command:");
    return 0;
}

```

In the beginning of this function, the program get sensor data from each sensor and store them in its corresponding variable. Next, if else statements are used to print the correct statement if the sensor is triggered or not. For example, if the touch sensor is triggered, the sensor data retrieved is below 500, then the program will print 'The touch sensor has been activated'. Next, the program will print out the distance collected by the ultrasonic sensor, then the light sensor and lastly the sound sensor. Finally, the function prints the user interface again for the user to read.

A ChNXT Class API

The header file `nxt.h` defines all the data types, macros and function prototypes for the Lego Mindstorms NXT API library. The header file declares a class called `ChNXT` which contains member functions which may be used to control the Lego Mindstorms NXT.

A.1 Data Types Used in ChNXT Class

The data types defined in the header file `nxt.h` are described in this appendix. These data types are used by the NXT library to represent certain values, such as joint id's and motor directions.

Data Type	Description
<code>nxtJointId_t</code>	An enumerated value that indicates a nxt joints.
<code>nxtJointState_t</code>	The current state of a nxt joint.
<code>nxtSensorId_t</code>	An enumerate value that indicates a nxt's sensors.
<code>nxtSensorType_t</code>	An enumerate value that indicates the type of a sensor of a nxt.
<code>nxtSensorMode_t</code>	An enumerate value that indicates the mode of a sensor for getting value.

A.1.1 `nxtJointId_t`

This datatype is an enumerated type used to identify a joint on the Lego Mindstorms NXT. Valid values for this type are:

```
typedef enum nxt_joints_e {
    NXT_JOINT1 = 0,
    NXT_JOINT2 = 1,
    NXT_JOINT3 = 2,
} nxtJointId_t;
```

Value	Description
<code>NXT_JOINT1</code>	PortA on the Lego Mindstorms NXT.
<code>NXT_JOINT2</code>	PortB on the Lego Mindstorms NXT.
<code>NXT_JOINT3</code>	PortC on the Lego Mindstorms NXT.

A.1.2 `nxtJointState_t`

This datatype is an enumerated type used to designate the current movement state of a joint. The values may be retrieved from the robot with the `getJointState()` function and may be set with the `moveContinuous()` family of functions. Valid values are:

```
typedef enum nxt_joint_state_e {
    NXT_FORWARD = 1,
    NXT_BACKWARD = -1,
} nxtJointState_t;
```

Value	Description
<code>NXT_FORWARD</code>	This value indicates that the joint is currently moving forward.
<code>NXT_BACKWARD</code>	This value indicates that the joint is currently moving backward.

A.1.3 nxtSensorPort_t

This datatype is an enumerated type used to identify a sensor on the Lego Mindstorms NXT. Valid values for this type are:

```
typedef enum nxt_sensors_e{
    NXT_SENSORPORT1 = 0,
    NXT_SENSORPORT2 = 1,
    NXT_SENSORPORT3 = 2,
    NXT_SENSORPORT4 = 3
} nxtSensorId_t;
```

Value	Description
NXT_SENSORPORT1	Select sensor input PORT 1 on the NXT.
NXT_SENSORPORT2	Select sensor input PORT 2 on the NXT.
NXT_SENSORPORT3	Select sensor input PORT 3 on the NXT.
NXT_SENSORPORT4	Select sensor input PORT 4 on the NXT.

A.1.4 nxtSensorType_t

This data type is used to identify the type of a sensor for the Lego Mindstorms NXT. Valid values for this type are:

```
typedef enum nxt_sensor_type_e{
    NXT_SENSORTYPE_TOUCH           = 0x01,
    NXT_SENSORTYPE_TEMPERATURE     = 0x02,
    NXT_SENSORTYPE_LIGHT_ACTIVE    = 0x05,
    NXT_SENSORTYPE_LIGHT_INACTIVE  = 0x06,
    NXT_SENSORTYPE_SOUND_DB        = 0x07,
    NXT_SENSORTYPE_SOUND_DBA       = 0x08,
    NXT_SENSORTYPE_LOWSPEED        = 0x0A,
    NXT_SENSORTYPE_ULTRASONIC      = 0x0B // LOWSPEED_9V
} nxtSensorType_t;
```

Value	Description
NXT_SENSORTYPE_TOUCH	Set to Touch sensor.
NXT_SENSORTYPE_TEMPERATURE	Set to Temperature Sensor.
NXT_SENSORTYPE_LIGHT_ACTIVE	Set to Light Sensor in active mode(LED on).
NXT_SENSORTYPE_LIGHT_INACTIVE	Set to Light Sensor in inactive mode(LED off).
NXT_SENSORTYPE_SOUND_DB	Set to Sound Sensor in dB.
NXT_SENSORTYPE_SOUND_DBA	Set to Sound Sensor in dBa.
NXT_SENSORTYPE_LOWSPEED	Set to ISP type sensor.
NXT_SENSORTYPE_ULTRASONIC	Set to Ultrasonic Sensor.

A.1.5 nxtSensorMode_t

This data type is used to identify the mode for a sensor to get value for the Lego Mindstorms NXT. Valid values for this type are:

```
typedef enum nxt_sensor_mode_e{
    NXT_SENSORMODE_RAWMODE         = 0x00,
    NXT_SENSORMODE_BOOLEANMODE     = 0x20
} nxtSensorMode_t;
```

Value	Description
<code>NXT_SENSORMODE_RAWMODE</code>	Get sensor value as raw mode.
<code>NXT_SENSORMODE_BOOLEANMODE</code>	Get sensor value as boolean mode.

A.2 ChNXT Class API Overview

Table 2: Functions for Communication

Function	Description
<code>connect()</code>	Connects to the Mindstorms NXT using bluetooth (Read bluetooth address from the configuration file automaticly).
<code>connectWithAddress()</code>	Connects to the Mindstorms NXT via bluetooth (Read bluetooth address from users' input).
<code>disconnect()</code>	Disconnects from the Mindstorms NXT.

Table 3: Functions for Checking Status

Function	Description
<code>isConnected()</code>	Check the connection to a robot.
<code>isMoving()</code>	Check if any joints are currently in motion.

Table 4: Functions for Sensors

Function	Description
<code>setSensor()</code>	Setup the sensors to collect data from the environment.
<code>getSensor()</code>	Get the data collected by the sensors from the NXT.

Table 5: Functions for Joints

Functions	Description
<code>setJointZero()</code>	Reset the tachometer to zero for a single joint.
<code>setJointZeros()</code>	Reset the tachometer to zero for all joints.
<code>setJointSpeedRatio()</code>	Set up a single joint speed.
<code>setJointSpeedRatios()</code>	Set up all joints' speed.
<code>moveJointContinuousNB()</code>	Make a single joint move continuously.
<code>moveJoint()</code>	Make a single joint move a user-specified angle.
<code>moveJointNB()</code>	Identical to <code>moveJoint()</code> but non-blocking.
<code>moveJointTo()</code>	Make a single joint move to an absolute angle.
<code>moveJointToNB()</code>	Identical to <code>moveJointTo()</code> but non-blocking.
<code>move()</code>	Make all joints move a user-specified angles.
<code>moveNB()</code>	Identical to <code>move()</code> but non-blocking.
<code>moveTo()</code>	Make all joints move to absolute angles.
<code>moveToNB()</code>	Identical to <code>moveTo()</code> but non-blocking.
<code>moveToZero()</code>	Make all joints move to absolute zero positions.
<code>moveToZeroNB()</code>	Identical to <code>moveToZero()</code> but non-blocking.
<code>moveContinuousNB()</code>	Make all joints move continuously.
<code>moveContinuousTime()</code>	Make all joints move continuously for a certain amount of time.
<code>moveWait()</code>	Wait until all motors have stopped moving.
<code>getJointAngle()</code>	Get tachometer counts from NXT.
<code>getJointSpeedRatio()</code>	Get a motor's speed ratio from NXT.
<code>getJointSpeedRatios()</code>	Get all motors' speed ratios from NXT.
<code>stopOneJoint()</code>	Make a single joint stop moving.
<code>stopTwoJoints()</code>	Make two joints stop moving.
<code>stopAllJoints()</code>	Make all joints stop moving.

Table 6: Functions for the Vehicle Configuration

Functions	Description
<code>vehicleRollForward()</code>	Moves the NXT vehicle forward.
<code>vehicleRollForwardNB()</code>	Identical to <code>vehicleRollForward()</code> , but non-blocking.
<code>vehicleRollBackward()</code>	Moves the NXT vehicle backward.
<code>vehicleRollBackwardNB()</code>	Identical to <code>vehicleRollBackward()</code> , but non-blocking.
<code>vehicleRotateLeft()</code>	Rotates the NXT vehicle left.
<code>vehicleRotateLeftNB()</code>	Identical to <code>vehicleRotateLeft()</code> , but non-blocking.
<code>vehicleRotateRight()</code>	Rotates the NXT vehicle right.
<code>vehicleRotateRightNB()</code>	Identical to <code>vehicleRotateRight()</code> , but non-blocking.
<code>vehicleMotionWait()</code>	Wait until vehicle stop moving.

A.3 ChNXT Class API Details

ChNXT::connect()

Synopsis

```
#include <nxt.h>
int ChNXT::connect();
```

Purpose

Connect to a Mindstorms NXT via Bluetooth.

Return Value

The function returns 0 on success, and non-zero otherwise.

Parameters

None.

Description

This function is used to connect to a Mindstorms NXT via Bluetooth. The Bluetooth address is gotten from the configuration file.

Example

```
#include <nxt.h>
#include <stdio.h>

ChNXT nxt;
if (nxt.connect()){
    printf("Connection to NXT has failed.");
    exit(0);
}

nxt.disconnect();
```

See Also

connectWithAddress(), disconnect()

ChNXT::connectWithAddress()

Synopsis

```
#include <nxt.h>
int ChNXT::connectWithAddress(char usr_addr[18]);
```

Purpose

Connect to a Mindstorms NXT via Bluetooth.

Return Value

The function returns 0 on success, and non-zero otherwise.

Parameters

usr_address The Bluetooth address of the Mindstorm NXT.

Description

This function is used to connect to a Mindstorms NXT via Bluetooth. The Bluetooth address is gotten from the configuration file.

Example

```
#include <nxt.h>
#include <stdio.h>

ChNXT nxt;
if (nxt.connectWithAddress("00:16:53:12:e7:80")){
    printf("Connection to NXT has failed.");
    exit(0);
}

nxt.disconnect();
```

See Also

connect(), disconnect()

ChNXT::disconnect()

Synopsis

```
#include <nxt.h>
int ChNXT::disconnect();
```

Purpose

Disconnect from a Lego mindstorms NXT.

Return Value

The function returns 0 on success and non-zero otherwise.

Parameters

None.

Description

This function is used to disconnect from a connected Mindstorms NXT. A call to this function is not necessary before the termination of a program. It is only necessary if another connection will be established within the same program at a later time.

Example

```
#include <nxt.h>
#include <stdio.h>

ChNXT nxt;
if (nxt.connectWithAddress("00:16:53:12:e7:80")){
    printf("Connection to NXT has failed.");
    exit(0);
}

nxt.disconnect();
```

See Also

connect(), connectWithAddress

ChNXT::getJointAngle()

Synopsis

```
#include <nxt.h>
int ChNXT::getJointAngle(nxtJointId_t id, double &angle);
```

Purpose

Retrieve a robot joint's current angle.

Return Value

The function returns 0 on success and non-zero otherwise.

Parameters

<code>id</code>	The joint number. This is an enumerated type discussed in Section A.1.1 on page 70.
<code>angle</code>	A variable to store the current angle of the robot motor. The contents of this variable will be overwritten with a value that represents the motor's angle in degrees.

Description

This function gets the current motor angle of a NXT's motor. The angle returned is in units of degrees and is accurate to roughly ± 1 degrees. The function `getJointAngle()` always returns an angle from 0 to ∞ degrees.

Example

```
#include <nxt.h>
#include <stdio.h>

ChNXT nxt;
double angle;

nxt.connect();

nxt.getJointAngle(ROBOT_JOINT1, angle);

printf("The angle of joint1 is: %lf\n", angle);

nxt.disconnect();
```

See Also

ChNXT::getJointSpeedRatio()

Synopsis

```
#include <nxt.h>
int ChNXT::getJointSpeedRatio(nxtJointId_t id, double &ratio);
```

Purpose

Get the speed ratio settings of a joint on the Lego Mindstorms NXT.

Return Value

The function returns 0 on success and non-zero otherwise.

Parameters

- id** Retrieve the speed ratio setting of this joint. This is an enumerated type discussed in Section A.1.1 on page 70.
- ratio** A variable of type double. The value of this variable will be overwritten with the current speed ratio setting of the joint.

Description

This function is used to find the speed ratio setting of a joint. The speed ratio setting of a joint is the percentage of the maximum joint speed, and the value ranges from 0 to 1. In other words, if the ratio is set to 0.5, the joint will turn at 50% of its maximum angular velocity while moving continuously or moving to a new goal position.

Example

```
#include <nxt.h>
#include <stdio.h>

ChNXT nxt;
double ratio;

nxt.connect();

nxt.getJointSpeedRatio(ROBOT_JOINT1, ratio);

printf("The speed ratio of joint1 is: %lf\n", ratio);

nxt.disconnect();
```

See Also

setJointSpeedRatio(), getJointSpeedRatio()

ChNXT::getJointSpeedRatios()

Synopsis

```
#include <nxt.h>
int ChNXT::getJointSpeedRatios(double &ratio1, double &ratio2, double &ratio3);
```

Purpose

Get the speed ratio settings of all joints on the Lego Mindstorms NXT.

Return Value

The function returns 0 on success and non-zero otherwise.

Parameters

- `ratio1` The address of a variable to store the speed ratio of joint 1.
- `ratio2` The address of a variable to store the speed ratio of joint 2.
- `ratio3` The address of a variable to store the speed ratio of joint 3.

Description

This function is used to retrieve all four joint speed ratio settings of a Lego Mindstorms NXT simultaneously. The speed ratios are as a value from 0 to 1.

Example

```
#include <nxt.h>
#include <stdio.h>

ChNXT nxt;
double ratio1, ratio2, ratio3;

nxt.connect();

nxt.getJointSpeedRatio(ratio1, ratio2, ratio3);

printf("The speed ratio of joint1 is: %lf\n", ratio1);
printf("The speed ratio of joint2 is: %lf\n", ratio2);
printf("The speed ratio of joint3 is: %lf\n", ratio3);

nxt.disconnect();
```

See Also

`getJointSpeedRatio()`, `setJointSpeedRatio()`

ChNXT::getJointState()

Synopsis

```
#include <nxt.h>
int ChNXT::getJointState(nxtJointId_t id, nxtJointState_t &state);
```

Purpose

Determine whether a motor is moving or not.

Return Value

The function returns 0 on success and non-zero otherwise.

Parameters

- `id` The joint number. This is an enumerated type discussed in Section A.1.1 on page 70.
- `state` An integer variable which will be overwritten with the current state of the motor. This is an enumerated type discussed in Section A.1.2 on page 70.

Description

This function is used to determine the current state of a motor. Valid states are listed below.

Value	Description
ROBOT_FORWARD	This value indicates that the joint is currently moving forward.
ROBOT_BACKWARD	This value indicates that the joint is currently moving backward.

Example

```
#include <nxt.h>
#include <stdio.h>

ChNXT nxt;
nxtJointState_t status;

nxt.connect();

nxt.getJointState(ROBOT_JOINT1, status);
if(status == 0)
    printf("Joint1 is not moving.\n");
else
    printf("Joint1 is moving.\n");

nxt.disconnect();
```

See Also

isMoving()

ChNXT::getSensor()

Synopsis

```
#include <nxt.h>
int ChNXT::getSensor(nxtSensorId_id, double &value);
```

Purpose

Retrieve a NXT sensor's current value.

Return Value

The function returns 0 on success and non-zero otherwise.

Parameters

- id** The sensor port. This is an enumerated type discussed in Section ?? on page ??.
- value** A variable to store the current value of the NXT sensor. The contents of this variable will be overwritten with the sensor's value.

Description

This function gets the current sensor's value of a NXT.

Example

```
#include <nxt.h>
#include <stdio.h>

ChNXT nxt;
```

```

int value;

nxt.connect();

nxt.setSensor(NXT_SENSORPORT4, NXT_SENSORTYPE_ULTRASONIC,
NXT_SENSORMODE_RAWMODE);

nxt.getSensor(NXT_SENSORPORT4, value);

printf("The value of sensor 4 is: %d\n", value);

nxt.disconnect();

```

See Also

ChNXT::humanoidWalkBackward() ChNXT::humanoidWalkBackwardNB()

Synopsis

```

#include <mobot.h>
int ChNXT::humanoidWalkBackward(double angle);
int ChNXT::humanoidWalkBackwardNB(double angle);

```

Purpose

Make the Lego Mindstorms NXT in the humanoid configuration walk backward.

Return Value

The function returns 0 on success and non-zero otherwise.

Parameters

angle The angle to turn the joints, specified in degrees.

Description

ChNXT::humanoidWalkBackward()

This function is used to make the Lego Mindstorms walk backward in the humanoid configuration. The amount to roll the joints is specified by the argument, **angle**.

ChNXT::humanoidWalkBackwardNB()

This function is used to make the Lego Mindstorms walk backward in the humanoid configuration. The amount to roll the joints is specified by the argument, **angle**.

This function has both a blocking and non-blocking version. The blocking version, **humanoidWalkBackward()**, will block until the robot motion has completed. The non-blocking version, **humanoidWalkBackwardNB()**, will return immediately, and the motion will be performed asynchronously.

Example

```

#include <nxt.h>

ChNXT nxt;

```

```

nxt.connect();

/* Blocking function */
nxt.humanoidWalkBackward(360);

/* Non-blocking function */
nxt.humanoidWalkBackwardNB(360);
nxt.humanoidMotionWait();

nxt.disconnect();

```

See Also

humanoidWalkBackward()

ChNXT::humanoidWalkForward()
ChNXT::humanoidWalkForwardNB()

Synopsis

```

#include <mobot.h>
int ChNXT::humanoidWalkForward(double angle);
int ChNXT::humanoidWalkForwardNB(double angle);

```

Purpose

Make the Lego Mindstorms NXT in the humanoid configuration walk forward.

Return Value

The function returns 0 on success and non-zero otherwise.

Parameters

angle The angle to turn the joints, specified in degrees.

Description

ChNXT::humanoidWalkForward()

This function is used to make the Lego Mindstorms walk forward in the humanoid configuration. The amount to roll the joints is specified by the argument, **angle**.

ChNXT::humanoidWalkForwardNB()

This function is used to make the Lego Mindstorms walk forward in the humanoid configuration. The amount to roll the joints is specified by the argument, **angle**.

This function has both a blocking and non-blocking version. The blocking version, **humanoidWalkForward()**, will block until the robot motion has completed. The non-blocking version, **humanoidWalkForwardNB()**, will return immediately, and the motion will be performed asynchronously.

Example

```

#include <nxt.h>

ChNXT nxt;

nxt.connect();

```

```

/* Blocking function */
nxt.humanoidWalkForward(360);

/* Non-blocking function */
nxt.humanoidWalkForwardNB(360);
nxt.humanoidMotionWait();

nxt.disconnect();

```

See Also

humanoidWalkBackward()

ChNXT::humanoidMotionWait()

Synopsis

```

#include <nxt.h>
int ChNXT::humanoidMotionWait();

```

Purpose

Wait for a motion to complete execution in humanoid configuration.

Return Value

The function returns 0 on success and non-zero otherwise.

Description

This function is used to wait for a motion function to fully complete its cycle.

Example

```

#include <nxt.h>

ChNXT nxt;

nxt.connect();

/* Non-blocking function */
nxt.humanoidRotateRightNB(360);

/* wait until non-blocking motion stops */
nxt.humanoidMotionWait();

nxt.disconnect();

```

See Also

humanoidWalkForward(), humanoidWalkBackward()

ChNXT::isConnected()

Synopsis

```

#include <nxt.h>
int ChNXT::isConnected(void);

```

Purpose

Check to see if currently connected to a Lego Mindstorms NXT via Bluetooth.

Return Value

The function returns zero if it is not currently connected to a Lego Mindstorms NXT or if an error has occurred, or 1 if the Lego Mindstorms NXT is connected.

Parameters

None.

Description

This function is used to check if the software is currently connected to a Lego Mindstorms NXT.

Example

```
#include <nxt.h>

ChNXT nxt;
int connectStatus;

nxt.connect();
connectStatus = nxt.isConnected();

if(connectStatus)
    printf("Connected!\n");
else
    printf("Not connected!\n");

nxt.disconnect();
```

See Also

ChNXT::isMoving()**Synopsis**

```
#include <nxt.h>
int ChNXT::isMoving(void);
```

Purpose

Check to see if a Lego Mindstorms NXT is currently moving any of its joints.

Return Value

This function returns 0 if none of the joints are being driven or if an error has occurred, or 1 if any joint is being driven.

Parameters

None.

Description

This function is used to determine if a robot is currently moving any of its joints.

Example

```
#include <nxt.h>
#include <stdio.h>

ChNXT nxt;
int moveStatus;
```

```

nxt.connect();
moveStatus = isMoving(ROBOT_JOINT1);

if(moveStatus)
    printf("Joint1 is moving!\n");
else
    printf("Joint1 is not moving!\n");

nxt.disconnect();

```

See Also
getJointState()

ChNXT::move() ChNXT::moveNB()

Synopsis

```

#include <nxt.h>
int ChNXT::move(double degrees1, double degrees2, double degrees3);
int ChNXT::moveNB(double degrees1, double degrees2, double degrees3);

```

Purpose

Move all joints of Lego Mindstorms NXT by specified degrees.

Return Value

The function returns 0 on success and non-zero otherwise.

Parameters

angle1	The amount to move joint 1 relative to the current position.
angle2	The amount to move joint 2 relative to the current position.
angle3	The amount to move joint 3 relative to the current position.

Description

ChNXT::move()

This function moves all of the joints of a Lego Mindstorms NXT by the specified number of degrees from their current positions.

ChNXT::moveNB()

This function moves all of the joints of a Lego Mindstorms NXT by the specified number of degrees from their current positions.

The function `moveNB()` is the non-blocking version of the `move()` function, which means that the function will return immediately and the physical robot motion will occur asynchronously. For more information on blocking and non-blocking functions, please refer to Section 3.4.2 on page 14.

Example

```

#include <nxt.h>
#include <stdio.h>

ChNXT nxt;

```



```

if (nxt.connectWithAddress("00:16:53:12:e7:80")){
    printf("Connection to NXT has failed.");
    exit(0);
}

/* setup speed for all three joints */
nxt.setJointSpeeds(60, 40, 40);

/* move by the non-blocking function*/
nxt.moveNB(360, 360, 360);
nxt.moveWait();

/* move by the blocking function*/
nxt.move(360, 360, 360);

nxt.disconnect();

```

See Also

ChNXT::moveContinuousNB()

Synopsis

```

#include <nxt.h>
int ChNXT::moveContinuousNB(nxtJointState_t dir1,
                             nxtJointState_t dir2,
                             nxtJointState_t dir3);

```

Purpose

Move the joints of a robot continuously in the specified directions.

Return Value

The function returns 0 on success and non-zero otherwise.

Parameters

Each parameter specifies the direction the joint should move. The types are enumerated in `mobot.h` and have the following values:

Value	Description
ROBOT_FORWARD	This value indicates that the joint is currently moving forward.
ROBOT_BACKWARD	This value indicates that the joint is currently moving backward.

More documentation about these types may be found at Section A.1.2 on page 70.

Description

This function causes joints of a robot to begin moving at the previously set speed. The joints will continue moving until the joint hits a joint limit, or the joint is stopped by setting the speed to zero. This function is a non-blocking function.

Example

```

#include <nxt.h>
#include <stdio.h>

ChNXT nxt;

```

```

if (nxt.connectWithAddress("00:16:53:12:e7:80")){
    printf("Connection to NXT has failed.");
    exit(0);
}

/* setup speed for all three joints */
nxt.setJointSpeeds(60, 40, 40);

/* move all joints on the Mindstorm NXT */
nxt.moveContinuousNB(ROBOT_FORWARD, ROBOT_FORWARD, ROBOT_FORWARD);

nxt.disconnect();

```

See Also

ChNXT::moveContinuousTime()

Synopsis

```

#include <nxt.h>
int ChNXT::moveContinuousTime(nxtJointState_t dir1,
                               nxtJointState_t dir2,
                               nxtJointState_t dir3,
                               double seconds);

```

Purpose

Move the joints of a robot continuously in the specified directions for some amount of time.

Return Value

The function returns 0 on success and non-zero otherwise.

Parameters

Each direction parameter specifies the direction the joint should move. The types are enumerated in `nxt.h` and have the following values:

Value	Description
ROBOT_FORWARD	This value indicates that the joint is currently moving forward.
ROBOT_BACKWARD	This value indicates that the joint is currently moving backward.

The `seconds` parameter is the time to perform the movement, in seconds.

Description

This function causes joints of a robot to begin moving. The joints will continue moving until the joint hits a joint limit, or the time specified in the `seconds` parameter is reached. This function will block until the motion is completed.

Example

```

#include <nxt.h>
#include <stdio.h>

ChNXT nxt;

if (nxt.connectWithAddress("00:16:53:12:e7:80")){
    printf("Connection to NXT has failed.");
    exit(0);
}

```

```

}

/* setup speed for all three joints */
nxt.setJointSpeedRatios(0.4, 0.4, 0.4);

/* move all joints on the Mindstorm NXT in 10 seconds*/
nxt.moveContinuousTime(ROBOT_FORWARD, ROBOT_FORWARD,
                      ROBOT_FORWARD, 10);

nxt.disconnect();

```

See Also

ChNXT::moveJoint()
ChNXT::moveJointNB()

Synopsis

```

#include <nxt.h>
int ChNXT::moveJoint(nxtJointId_t id, double angle);
int ChNXT::moveJointNB(nxtJointId_t id, double angle);

```

Purpose

Move a joint on the robot by a specified angle with respect to the current position.

Return Value

The function returns 0 on success and non-zero otherwise.

Parameters

<code>id</code>	The joint number to move.
<code>angle</code>	The desired angle the joint need to move.

Description

ChNXT::moveJoint()

This function commands the motor to move by an angle relative to the joint's current position at the joints current speed setting. The current motor speed ratio may be set with the `setJointSpeedRatio()` member function. Please note that if the motor speed is set to zero, the motor will not move after calling the `moveJoint()` function.

ChNXT::moveJointNB()

This function commands the motor to move by an angle relative to the joint's current position at the joints current speed setting. The current motor speed ratio may be set with the `setJointSpeedRatio()` member function. Please note that if the motor speed is set to zero, the motor will not move after calling the `moveJointNB()` function.

The function `moveJointNB()` is the non-blocking version of the `moveJoint()` function, which means that the function will return immediately and the physical robot motion will occur asynchronously. For more details on blocking and non-blocking functions, please refer to Section 3.4.2 on page 14.

Example

```

#include <nxt.h>
#include <stdio.h>

```

```

ChNXT nxt;

if (nxt.connectWithAddress("00:16:53:12:e7:80")){
    printf("Connection to NXT has failed.");
    exit(0);
}

/* setup speed for joint1 */
nxt.setJointSpeedRatio(ROBOT_JOINT1, 40);

/* move joint1 360 degrees */
nxt.moveJointNB(ROBOT_JOINT1, 360);
nxt.moveJointWait();

/* move joint1 360 degrees */
nxt.moveJoint(ROBOT_JOINT1, 360);

nxt.disconnect();

```

See Also

ChNXT::moveJointTo()
ChNXT::moveJointToNB()

Synopsis

```

#include <nxt.h>
int ChNXT::moveJointTo(nxtJointId_t id, double angle);
int ChNXT::moveJointToNB(nxtJointId_t id, double angle);

```

Purpose

Move a joint on the Lego Mindstorms NXT to an absolute position.

Return Value

The function returns 0 on success and non-zero otherwise.

Parameters

id The joint number to move.
angle The absolute angle in degrees to move the motor to.

Description

ChNXT::moveJointTo()

This function commands the motor to move to a position specified in degrees at the current motor's speed. The current motor speed may be set with the **setJointSpeedRatio()** member function. Please note that if the motor speed is set to zero, the motor will not move after calling the **moveJointTo()** function.

ChNXT::moveJointToNB()

This function commands the motor to move to a position specified in degrees at the current motor's speed. The current motor speed may be set with the **setJointSpeedRatio()** member function. Please note that if the motor speed is set to zero, the motor will not move after calling the **moveJointToNB()** function.

The function `moveJointToNB()` is the non-blocking version of the `moveJointTo()` function, which means that the function will return immediately and the physical robot motion will occur asynchronously. For more details on blocking and non-blocking functions, please refer to Section 3.4.2 on page 14.

Example

```
#include <nxt.h>
#include <stdio.h>

ChNXT nxt;

if (nxt.connectWithAddress("00:16:53:12:e7:80")){
    printf("Connection to NXT has failed.");
    exit(0);
}

/* setup speed for all three joints */
nxt.setJointSpeedRatio(ROBOT_JOINT1, 40);

/* move joint1 360 degrees with the non-blocking function */
nxt.moveJointToNB(ROBOT_JOINT1, 360);
nxt.moveJointWait(ROBOT_JOINT1);

/* move joint1 360 degrees with the blocking function */
nxt.moveJointTo(ROBOT_JOINT1, 360);

nxt.disconnect();
```

See Also

ChNXT::moveJointWait()

Synopsis

```
#include <nxt.h>
int ChNXT::moveJointWait(nxtJointId_t id);
```

Purpose

Wait for a joint to stop moving.

Return Value

The function returns 0 on success and non-zero otherwise.

Parameters

`id` The joint number to wait for.

Description

This function is used to wait for a joint motion to finish. Functions such as `moveNB()` and `moveJointNB()` do not wait for a joint to finish moving before continuing to allow multiple joints to move at the same time. The `moveJointWait()` function is used to wait for a robotic joint motion to complete.

Please note that if this function is called after a motor has been commanded to turn indefinitely, this function may never return and your program may hang.

Example

See Also

`moveWait()`

ChNXT::moveJointContinuousNB()

Synopsis

```
#include <nxt.h>
int ChNXT::moveJointContinuousNB(robotJointId_t id, int dir);
```

Purpose

Move the specific joint on the Mindstorm NXT continuously in a direction.

Return Value

The function returns 0 on success and non-zero otherwise.

Parameters

<code>id</code>	The joint of the Mindstorm NXT.
<code>dir</code>	The move direction of the joint. 1 means positive and 0 means negative direction.

Description

This function is used to rotate the specific joint of the Mindstorm NXT. The joint will move continuously until the function `stopOneJoint()` is called. The variable `dir` indicates the move direction of the joint.

Example

```
#include <nxt.h>
#include <stdio.h>

ChNXT nxt;

if (nxt.connectWithAddress("00:16:53:12:e7:80")){
    printf("Connection to NXT has failed.");
    exit(0);
}

/* setup speed for all three joints */
nxt.setJointSpeeds(60, 40, 40);

/* move the joint 1 on the Mindstorm NXT */
nxt.moveJointContinuousNB(ROBOT_JOINT1, 1);

nxt.disconnect();
```

See Also

`ChNXT::moveTo()`
`ChNXT::moveToNB()`

Synopsis

```
#include <nxt.h>
int ChNXT::moveTo(double angle1, double angle2, double angle3, double angle4);
int ChNXT::moveToNB(double angle1, double angle2, double angle3, double angle4);
```

Purpose

Move all joints of Lego Mindstorms NXT to the specified position.

Return Value

The function returns 0 on success and non-zero otherwise.

Parameters

<code>angle1</code>	The absolute position to move joint 1, expressed in degrees.
<code>angle2</code>	The absolute position to move joint 2, expressed in degrees.
<code>angle3</code>	The absolute position to move joint 3, expressed in degrees.

Description

ChNXT::moveTo()

This function moves all of the joints of a robot to the specified absolute positions.

ChNXT::moveToNB()

This function moves all of the joints of a robot to the specified absolute positions.

The function `moveToNB()` is the non-blocking version of the `moveTo()` function, which means that the function will return immediately and the physical robot motion will occur asynchronously. For more details on blocking and non-blocking functions, please refer to Section 3.4.2 on page 14.

Example

```
#include <nxt.h>
#include <stdio.h>

ChNXT nxt;

if (nxt.connectWithAddress("00:16:53:12:e7:80")){
    printf("Connection to NXT has failed.");
    exit(0);
}

/* setup speed for all three joints */
nxt.setJointSpeeds(40, 40, 40);

/* move by the non-blocking function*/
nxt.moveToNB(360, 360, 360);
nxt.moveWait();

/* move by the blocking function*/
nxt.moveTo(360, 360, 360);

nxt.disconnect();
```

See Also

ChNXT::moveToZero()

ChNXT::moveToZeroNB()

Synopsis

```
#include <nxt.h>
int ChNXT::moveToZero();
int ChNXT::moveToZeroNB();
```

Purpose

Move all joints of Lego Mindstorms NXT to their absolute zero position.

Return Value

The function returns 0 on success and non-zero otherwise.

Parameters

None.

Description

ChNXT::moveToZero()

This function moves all of the joints of a NXT to their zero position.

ChNXT::moveToZeroNB()

This function moves all of the joints of a NXT to their zero position.

The function `moveToZeroNB()` is the non-blocking version of the `moveToZero()` function, which means that the function will return immediately and the physical robot motion will occur asynchronously. For more details on blocking and non-blocking functions, please refer to Section 3.4.2 on page 14.

Example

```
#include <nxt.h>
#include <stdio.h>

ChNXT nxt;

if (nxt.connectWithAddress("00:16:53:12:e7:80")){
    printf("Connection to NXT has failed.");
    exit(0);
}

/* setup speed for all three joints */
nxt.setJointSpeeds(60, 40, 40);

/* move to zero by the non-blocking function*/
nxt.moveToZeroNB();
nxt.moveWait();

/* move to zero by the blocking function*/
nxt.moveToZero();

nxt.disconnect();
```

See Also

ChNXT::moveWait()

Synopsis

```
#include <nxt.h>
int ChNXT::moveWait();
```

Purpose

Wait for all joints to stop moving.

Return Value

The function returns 0 on success and non-zero otherwise.

Description

This function is used to wait for all joint motions to finish. Functions such as `move()` and `moveTo()` do not wait for a joint to finish moving before continuing to allow multiple joints to move at the same time. The `moveWait()` function is used to wait for robotic motions to complete.

Please note that if this function is called after a motor has been commanded to turn indefinitely, this function may never return and your program may hang.

Example

```
#include <nxt.h>
#include <stdio.h>

ChNXT nxt;

if (!nxt.connectWithAddress("00:16:53:12:e7:80")){
    printf("Connection to NXT has failed.");
    exit(0);
}

/* setup speed for all three joints */
nxt.setJointSpeeds(60, 40, 40);

/* move by the non-blocking function*/
nxt.moveNB(360, 360, 360);

/* wait until motors stop moving */
nxt.moveWait();

nxt.disconnect();

See Also
moveJointWait()
```

ChNXT::resetToZero()

Synopsis

```
#include <nxt.h>
int ChNXT::resetToZero(void);
```

Purpose

Reset the tachometer count for all motors.

Return Value

The function returns 0 on success and non-zero otherwise.

Parameters

None.

Description

This function is used to reset the tachometer count for all joints of the Mindstorms NXT.

Example

```
#include <nxt.h>
#include <stdio.h>

ChNXT nxt;

if (nxt.connectWithAddress("00:16:53:12:e7:80")){
    printf("Connection to NXT has failed.");
    exit(0);
}

nxt.resetToZero();

nxt.disconnect();
```

See Also

setJointZero()

ChNXT::setSensor()**Synopsis**

```
#include <nxt.h>
int ChNXT::setSensor(nxtSensorId_t id,
                    nxtSensorType type,
                    nxtSensorMode mode);
```

Purpose

Set up a sensor of Lego mindstorms NXT.

Return Value

The function returns 0 on success and non-zero otherwise.

Parameters

id	The port of the sensor locate on the Mindstorm NXT.
type	The type of the sensor.
mode	The mode of the sensor.

Description

This function is used to set up a sensor on the Mindstorm with a specific type and mode of the sensor. See the Macros section for the details of ports, types and modes.

Example

```

#include <nxt.h>
#include <stdio.h>

ChNXT nxt;
int status_1=2;
int status_2=2;

if (nxt.connectWithAddress("00:16:53:12:e7:80")){
    printf("Connection to NXT has failed.");
    exit(0);
}

/* setup port 1 as touch sensor */
status_1=nxt.setSensor(SENSOR_PORT1,
    SENSOR_TYPE_TOUCH, SENSOR_MODE_BOOLEANMODE);
if(status_1){
    printf("Connection to touch sensor has failed");
}

/* setup port4 as ultrasonic sensor */
status_2=nxt.setSensor(SENSOR_PORT4,
    SENSOR_TYPE_ULTRASONIC, SENSOR_MODE_RAWMODE);
if(status_2){
    printf("Connection to ultrasonic sensor has failed");
}

nxt.disconnect();

```

See Also

ChNXT::setJointSpeedRatio()

Synopsis

```

#include <nxt.h>
int ChNXT::setJointSpeedRatio(nxtJointId_t id, double ratio);

```

Purpose

Set the speed ratio setting of a joint on the Lego Mindstorms NXT.

Return Value

The function returns 0 on success and non-zero otherwise.

Parameters

id	The port of the sensor locate on the Mindstorm NXT.
ratio	A variable of type double with a value from 0 to 1.

Description

This function is used to set the speed ratio setting of a joint on the Lego Mindstorms NXT. The speed ratio setting of a joint is the percentage of the maximum joint speed, and the value ranges from 0 to 1. In other words, if the ratio is set to 0.5, the joint will turn at 50% of its maximum angular velocity while moving continuously or moving to a new goal position.

Example

```
#include <nxt.h>
#include <stdio.h>

ChNXT nxt;

if (nxt.connectWithAddress("00:16:53:12:e7:80")){
    printf("Connection to NXT has failed.");
    exit(0);
}

/* set the speed ratio setting for joint1 on port0 */
nxt.setJointSpeedRatio(ROBOT_JOINT1, 0.5);

nxt.disconnect();
```

See Also

setJointSpeedRatios()

ChNXT::setJointSpeedRatios()

Synopsis

```
#include <nxt.h>
int ChNXT::setJointSpeedRatios(double ratio1, double ratio2, double ratio3);
```

Purpose

Set the speed ratio setting of all joints on the Lego Mindstorms NXT.

Return Value

The function returns 0 on success and non-zero otherwise.

Parameters

ratio1	The speed ratio setting for the first joint.
ratio2	The speed ratio setting for the second joint.
ratio3	The speed ratio setting for the third joint.

Description

This function is used to simultaneously set the speed ratio settings of all joints on the Lego Mindstorms NXT. The speed ratio setting of a joint is the percentage of the maximum joint speed, and the value ranges from 0 to 1.

Example

```
#include <nxt.h>
#include <stdio.h>

ChNXT nxt;

if (nxt.connectWithAddress("00:16:53:12:e7:80")){
    printf("Connection to NXT has failed.");
    exit(0);
}

/* set the speed ratio settings for all joints*/
nxt.setJointSpeedRatios(0.5, 0.4, 0.4);
```

```
nxt.disconnect();
```

See Also

```
setJointSpeedRatio()
```

ChNXT::stopOneJoint()

Synopsis

```
#include <nxt.h>
int ChNXT::stopOneJoint(nxtJointId_t id);
```

Purpose

Stop a joint moving.

Return Value

The function returns 0 on success and non-zero otherwise.

Parameters

id The joint of the Mindstorm NXT.

Description

This function is used to stop the specific joint on the Mindstorm NXT.

Example

```
#include <nxt.h>
#include <stdio.h>

ChNXT nxt;

if (nxt.connectWithAddress("00:16:53:12:e7:80")){
    printf("Connection to NXT has failed.");
    exit(0);
}

/* setup speed for all three joints */
nxt.setJointSpeeds(60, 40, 40);

/* move joint1 360 degrees */
nxt.moveJointContinuousNB(ROBOT_JOINT1, ROBOT_FORWARD);
sleep(5);

/* stop joint1 */
nxt.stopOneJoint(ROBOT_JOINT1);

nxt.disconnect();
```

See Also

```
stopTwoJoints(), stopAllJoints()
```

ChNXT::stopTwoJoints()

Synopsis

```
#include <nxt.h>
int ChNXT::stopTwoJoints(nxtJointId_t id1, nxtJointId_t id2);
```

Purpose

Stop two joints moving.

Return Value

The function returns 0 on success and non-zero otherwise.

Parameters

id1	A joint of the Mindstorm NXT.
id2	Another joint of the Mindstorm NXT.

Description

This function is used to stop two specific joints on the Mindstorm NXT.

Example

```
#include <nxt.h>
#include <stdio.h>

ChNXT nxt;

if (nxt.connectWithAddress("00:16:53:12:e7:80")){
    printf("Connection to NXT has failed.");
    exit(0);
}

/* setup speed for all three joints */
nxt.setJointSpeeds(60, 40, 40);

/* move joint2 and joint3 forward */
nxt.moveJointContinuousNB(ROBOT_JOINT2, ROBOT_FORWARD);
nxt.moveJointContinuousNB(ROBOT_JOINT3, ROBOT_FORWARD);
sleep(5);

/* stop joint2 and joint3 */
nxt.stopTwoJoints(ROBOT_JOINT2, ROBOT_JOINT3);

nxt.disconnect();
```

See Also

stopOneJoint(), stopAllJoints()

ChNXT::stopAllJoints()

Synopsis

```
#include <nxt.h>
int ChNXT::stopAllJoints(void);
```

Purpose

Stop all joints moving.

Return Value

The function returns 0 on success and non-zero otherwise.

Parameters

None.

Description

This function is used to stop all joints on the Mindstorm NXT.

Example

```
#include <nxt.h>
#include <stdio.h>

ChNXT nxt;

if (nxt.connectWithAddress("00:16:53:12:e7:80")){
    printf("Connection to NXT has failed.");
    exit(0);
}

/* setup speed for all three joints */
nxt.setJointSpeeds(60, 40, 40);

/* move all joints forward */
nxt.moveJointContinuousNB(ROBOT_JOINT1, ROBOT_FORWARD);
nxt.moveJointContinuousNB(ROBOT_JOINT2, ROBOT_FORWARD);
nxt.moveJointContinuousNB(ROBOT_JOINT3, ROBOT_FORWARD);
sleep(5);

/* stop all joints */
nxt.stopAllJoints();

nxt.disconnect();
```

See Also

stopOneJoint(), stopTwoJoints()

**ChNXT::vehicleRollBackward()
ChNXT::vehicleRollBackwardNB()****Synopsis**

```
#include <nxt.h>
int ChNXT::vehicleRollBackward(double angle);
int ChNXT::vehicleRollBackwardNB(double angle);
```

Purpose

Make the Lego Mindstorms NXT in the vehicle configuration roll backward.

Return Value

The function returns 0 on success and non-zero otherwise.

Parameters

angle The angle to turn the wheels, specified in degrees.

Description

ChNXT::vehicleRollBackward()

This function is used to roll the Lego Mindstorms NXT backward in the vehicle configuration. The amount to roll the wheels is specified by the argument, **angle**.

ChNXT::vehicleRollBackwardNB()

This function is used to roll the Lego Mindstorms NXT backward in the vehicle configuration. The amount to roll the wheels is specified by the argument, **angle**.

This function has both a blocking and non-blocking version. The blocking version, **vehicleRollBackward()**, will block until the robot motion has completed. The non-blocking version, **vehicleRollBackwardNB()**, will return immediately, and the motion will be performed asynchronously.

Example

```
#include <nxt.h>

ChNXT nxt;

nxt.connect();

/* Blocking function */
nxt.vehicleRollBackward(360);

/* Non-blocking function */
nxt.vehicleRollBackwardNB(360);
nxt.vehicleMotionWait();

nxt.disconnect();
```

See Also

vehicleRollForward()

ChNXT::vehicleRollForward() **ChNXT::vehicleRollForwardNB()**

Synopsis

```
#include <mobot.h>
int ChNXT::vehicleRollForward(double angle);
int ChNXT::vehicleRollForwardNB(double angle);
```

Purpose

Make the Lego Mindstorms NXT in the vehicle configuration roll forward.

Return Value

The function returns 0 on success and non-zero otherwise.

Parameters

angle The angle to turn the wheels, specified in degrees.

Description

ChNXT::vehicleRollForward()

This function is used to roll the Lego Mindstorms forward in the vehicle configuration. The amount to roll the wheels is specified by the argument, **angle**.

ChNXT::vehicleRollForwardNB()

This function is used to roll the Lego Mindstorms forward in the vehicle configuration. The amount to roll the wheels is specified by the argument, **angle**.

This function has both a blocking and non-blocking version. The blocking version, **vehicleRollForward()**, will block until the robot motion has completed. The non-blocking version, **vehicleRollForwardNB()**, will return immediately, and the motion will be performed asynchronously.

Example

```
#include <nxt.h>

ChNXT nxt;

nxt.connect();

/* Blocking function */
nxt.vehicleRollForward(360);

/* Non-blocking function */
nxt.vehicleRollForwardNB(360);
nxt.vehicleMotionWait();

nxt.disconnect();
```

See Also

vehicleRollBackward()

ChNXT::vehicleRotateLeft()
ChNXT::vehicleRotateLeftNB()
Synopsis

```
#include <nxt.h>
int ChNXT::vehicleRotateLeft(double angle);
int ChNXT::vehicleRotateLeftNB(double angle);
```

Purpose

Rotate the Lego Mindstorms NXT left in vehicle configuration.

Return Value

The function returns 0 on success and non-zero otherwise.

Parameters

angle The angle in degrees to turn the wheels. The wheels will turn in opposite directions by the amount specified by this argument in order to rotate the robot to the left.

Description

ChNXT::vehicleRotateLeft()

This function is used to rotate the wheels of the Lego Mindstorms NXT in vehicle configuration in opposite directions to cause the robot to rotate counter-clockwise.

ChNXT::vehicleRotateLeftNB()

This function is used to rotate the wheels of the Lego Mindstorms NXT in vehicle configuration in opposite directions to cause the robot to rotate counter-clockwise.

This function has both a blocking and non-blocking version. The blocking version, `vehicleRotateLeft()`, will block until the robot motion has completed. The non-blocking version, `vehicleRotateLeftNB()`, will return immediately, and the motion will be performed asynchronously.

Example

```
#include <nxt.h>

ChNXT nxt;

nxt.connect();

/* Blocking function */
nxt.vehicleRotateLeft(360);

/* Non-blocking function */
nxt.vehicleRotateLeftNB(360);
nxt.vehicleMotionWait();

nxt.disconnect();
```

See Also

`vehicleRotateRight()`

ChNXT::vehicleRotateRight() ChNXT::vehicleRotateRightNB()

Synopsis

```
#include <mobot.h>
int ChNXT::vehicleRotateRight(double angle);
int ChNXT::vehicleRotateRightNB(double angle);
```

Purpose

Rotate the Lego Mindstorms NXT right in vehicle configuration.

Return Value

The function returns 0 on success and non-zero otherwise.

Parameters

angle The angle in degrees to turn the wheels. The wheels will turn in opposite directions by the amount specified by this argument in order to turn the robot to the right.

Description

ChNXT::vehicleRotateRight()

This function causes the robot to rotate the wheels of the Lego Mindstorms NXT in vehicle configuration in opposite directions to cause the robot to rotate clockwise.

ChNXT::vehicleRotateRightNB()

This function causes the robot to rotate the wheels of the Lego Mindstorms NXT in vehicle configuration in opposite directions to cause the robot to rotate clockwise.

This function has both a blocking and non-blocking version. The blocking version, `vehicleRotateRight()`, will block until the robot motion has completed. The non-blocking version, `vehicleRotateRightNB()`, will return immediately, and the motion will be performed asynchronously.

Example

```
#include <nxt.h>

ChNXT nxt;

nxt.connect();

/* Blocking function */
nxt.vehicleRotateRight(360);

/* Non-blocking function */
nxt.vehicleRotateRightNB(360);
nxt.vehicleMotionWait();

nxt.disconnect();
```

See Also

`vehicleRotateRight()`

ChNXT::vehicleMotionWait()**Synopsis**

```
#include <nxt.h>
int ChNXT::vehicleMotionWait();
```

Purpose

Wait for a motion to complete execution in vehicle configuration.

Return Value

The function returns 0 on success and non-zero otherwise.

Description

This function is used to wait for a motion function to fully complete its cycle.

Example

```
#include <nxt.h>

ChNXT nxt;
```

```
nxt.connect();

/* Non-blocking function */
nxt.vehicleRotateRightNB(360);

/* wait until non-blocking motion stops */
nxt.vehicleMotionWait();

nxt.disconnect();

See Also
vehicleRotateRight(), vehicleRotateLeft(),
vehicleRollForward(), vehicleRollBackward()
```

B Miscellaneous Utility Functions

Besides the control functions described in Appendix A, some utility functions are also very useful when you are programming, such as convert a certain angle to distance with the corresponding radius of wheel. Therefore, we will introduce you some useful utility functions in this section.

B.1 Overview

Table 7: NXT Utility Functions.

Function	Description
<code>angle2distance()</code>	Calculates the angle a wheel has turned from the radius and distance traveled.
<code>deg2rad()</code>	Converts degrees to radians.
<code>delay()</code>	Puts a delay into a program.
<code>distance2angle()</code>	Calculates the distance traveled by a wheel from the wheel's radius and angle turned.
<code>rad2deg()</code>	Converts radians to degrees.

B.2 Function Details

`angle2distance()`

Synopsis

```
#include <mobot.h>
double angle2distance(double radius, double angle);
array double angle2distance(double radius, array double angle[:])[:];
```

Purpose

Calculate the distance a wheel has traveled from the radius of the wheel and the angle the wheel has turned.

Return Value

The value returned is the distance traveled by the wheel. If the angle argument is an array of angles, then the value returned is an array of distances. Each element of the distance array returned is the distance calculated from the respective element in the angle array.

Parameters

radius The radius of the wheel.
angle This value is the angle the wheel has turned. This parameter may be of **double** type, or a Ch computational array.

Description

This function calculates the angle a wheel has turned given the wheel radius and distance traveled. The equation used is

$$d = r\theta$$

where d is the distance traveled, r is the radius of the wheel, and θ is the angle the wheel has turned in radians.

Example

See Also

distance2angle()

deg2rad()

Synopsis

```
#include <mobot.h>
double deg2rad(double degrees);
array double deg2rad(double degrees[:])[:];
```

Purpose

Convert degrees to radians.

Return Value

The angle parameter converted to radians.

Parameters

degrees The angle to convert, in degrees.

Description

This function converts an angle expressed in degrees into radians. Degrees and radians are two popular ways to express an angle, though they are not interchangeable. The following equation is used to convert degrees to radians:

$$\theta = \delta * \frac{\pi}{180}$$

where θ is the angle in radians and δ is the angle in degrees.

Example

See Also

rad2deg()

delay()

Synopsis

```
#include <mobot.h>
void delay(double seconds);
```

Purpose

Pause a program for a set amount of time.

Return Value

None.

Parameters

seconds The number of seconds to delay.

Description

This function delays or pauses a program for a number of seconds. For instance, the code

```
delay(0.5);
printf("Hello.\n");
delay(2);
printf("Goodbye.\n");
```

will pause for half a second, print the text `Hello.`, delay for 2 seconds, and then print the text `Goodbye.`.. **Example**

See Also

distance2angle()

Synopsis

```
#include <mobot.h>
double distance2angle(double radius, double distance);
array double distance2angle(double radius, array double distance[:])[:];
```

Purpose

Calculate the angle a wheel has turned from the radius of the wheel and the distance the wheel has traveled.

Return Value

The value returned is the angle turned by the wheel in degrees. If the distance argument is an array of distances, then the value returned is an array of angles. Each element of the angle array returned is the angle calculated from the respective element in the distance array.

Parameters

- radius** The radius of the wheel.
- distance** This value is the distance the wheel has traveled. This parameter may be of **double** type, or a Ch computational array.

Description

This function calculates the distance a wheel has turned given the wheel radius and angle turned. The equation used is

$$\theta = \frac{d}{r}$$

where d is the distance traveled, r is the radius of the wheel, and θ is the angle the wheel has turned in radians. A further conversion is done in the code to convert the angle from radians into degrees before returning the value.

Example

See Also

`angle2distance()`

rad2deg()

Synopsis

```
#include <mobot.h>
double rad2deg(double radians);
array double rad2deg(double radians[:])[:];
```

Purpose

Convert radians to degrees.

Return Value

The angle parameter converted to degrees.

Parameters

radians The angle to convert, in radians.

Description

This function converts an angle expressed in radians into degrees. Degrees and radians are two popular ways to express an angle, though they are not interchangeable. The following equation is used to convert radians to degrees:

$$\delta = \theta * \frac{180}{\pi}$$

where θ is the angle in radians and δ is the angle in degrees.

Example

See Also

deg2rad()

Index

angle2distance(), 105

ChNXT::connect(), 74
ChNXT::connectWithAddress(), 74
ChNXT::disconnect(), 75
ChNXT::getJointAngle(), 76
ChNXT::getJointSpeedRatio(), 77
ChNXT::getJointSpeedRatios(), 77
ChNXT::getJointState(), 78
ChNXT::getSensor(), 79
ChNXT::humanoidMotionWait(), 82
ChNXT::humanoidWalkBackward(), 80
ChNXT::humanoidWalkBackwardNB(), 80
ChNXT::humanoidWalkForward(), 81
ChNXT::humanoidWalkForwardNB(), 81
ChNXT::isConnected(), 82
ChNXT::isMoving(), 83
ChNXT::move(), 84
ChNXT::moveContinuousNB(), 85
ChNXT::moveContinuousTime(), 86
ChNXT::moveJoint(), 87
ChNXT::moveJointContinuousNB(), 90
ChNXT::moveJointNB(), 87
ChNXT::moveJointTo(), 88
ChNXT::moveJointToNB(), 88
ChNXT::moveJointWait(), 89
ChNXT::moveNB(), 84
ChNXT::moveTo(), 90
ChNXT::moveToNB(), 90
ChNXT::moveToZero(), 91
ChNXT::moveToZeroNB(), 92
ChNXT::moveWait(), 93
ChNXT::resetToZero(), 93
ChNXT::setJointSpeedRatio(), 95
ChNXT::setJointSpeedRatios(), 96
ChNXT::setSensor(), 94
ChNXT::stopAllJoints(), 98
ChNXT::stopOneJoint(), 97
ChNXT::stopTwoJoints(), 97
ChNXT::vehicleMotionWait(), 103
ChNXT::vehicleRollBackward(), 99
ChNXT::vehicleRollBackwardNB(), 99
ChNXT::vehicleRollForward(), 100
ChNXT::vehicleRollForwardNB(), 100
ChNXT::vehicleRotateLeft(), 101
ChNXT::vehicleRotateLeftNB(), 101
ChNXT::vehicleRotateRight(), 102
ChNXT::vehicleRotateRightNB(), 102

deg2rad(), 106

delay(), 106

distance2angle(), 107

NXT_BACKWARD, 70
NXT_FORWARD, 70
NXT_JOINT1, 70
NXT_JOINT2, 70
NXT_JOINT3, 70
nxt_joints_t, 70
NXT_SENSORMODE_BOOLEANMODE, 72
NXT_SENSORMODE_RAWMODE, 72
NXT_SENSORPORT1, 71
NXT_SENSORPORT2, 71
NXT_SENSORPORT3, 71
NXT_SENSORPORT4, 71
NXT_SENSORTYPE_LIGHT_ACTIVE, 71
NXT_SENSORTYPE_LIGHT_INACTIVE, 71
NXT_SENSORTYPE_SOUND_DB, 71
NXT_SENSORTYPE_SOUND_DBA, 71
NXT_SENSORTYPE_TEMPERATURE, 71
NXT_SENSORTYPE_TOUCH, 71
NXT_SENSORTYPE_ULTRASONIC, 71
nxtJointState_t, 70
nxtSensorId_t, 71
nxtSensorMode_t, 72
nxtSensorType_t, 71

rad2deg(), 108