

Bluetooth Racer

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1 Design Documentation

2 Introduction

This document describes the design and process of changing a remote control car into a Bluetooth controlled racer. A simple App was developed so that the movement of a smartphone controls the acceleration and steering of the car. The object is to enable the car to turn left and right, and move forward and backward, all controlled by the Bluetooth connection to the phone.

3 Scope

This document discusses, in detail, the electrical and software design for the Bluetooth Racer. It includes the requirements, dependencies and theory of operation. Schematics and code segments are used to give a more thorough explanation of the design. Testing procedures and results of each requirement are included. The complete code is located in Appendix B.

4 Design Overview

4.1 Requirements

The following are the given requirements for Bluetooth Racer:

1. The system shall use the Tiva C Series TM4C123GH6PM microcontroller.
2. The system shall use two external batteries. A 5 volt battery with USB connection to the microcontroller and a 9 volt DC supply for the drive and steering.
3. The system shall use a Bluetooth 4.0 Module.
4. The system shall use a Dual TB6612FNG Motor Driver (H-Bridge).
5. The Racer shall have PWM output to controller variable motor speed.
6. Working LED's should be used for the front and tail lights, as well as an inside light.
7. Upon powering up, the inside light should be turned on.
8. Upon connecting to Bluetooth, the front and tail lights should turn on.
9. The microcontroller will transmit and receive data from the Bluetooth module through UART.
10. The user shall command the Racer with a smartphone over Bluetooth connection. The movement of the phone will control the direction in which the car will move.
11. The Racer shall be able to turn and drive forward and backward on command of the user.

4.2 Materials

The following are dependencies for the Bluetooth Racer:

1. An RC car with working motors for both steering and driving.
2. A 9 volt DC power supply
3. A 5 volt DC power supply with USB connection
4. Dual TB6612FNG Motor Driver

5. Tiva C Series TM4C123GH6PM microcontroller
6. Bluetooth 4.0 Module
7. Schmidt Trigger
8. 5 LEDs
9. Spray Paint
10. NPN Transistor
11. Assorted resistors and capacitors

5 Testing

As specified before, the car is controlled via Bluetooth. The iOS app sends a 1 byte command that the UART module on the micro-controller receives. This byte of data contains the information necessary to enable the two H-bridges and the data to set the variable speed for PWM. The byte of data is represented in the following format: two bits for H-bridge drive followed by two bits to set the variable speed, these four bits are followed by two bits for H-bridge turn followed by two bits to set the variable speed

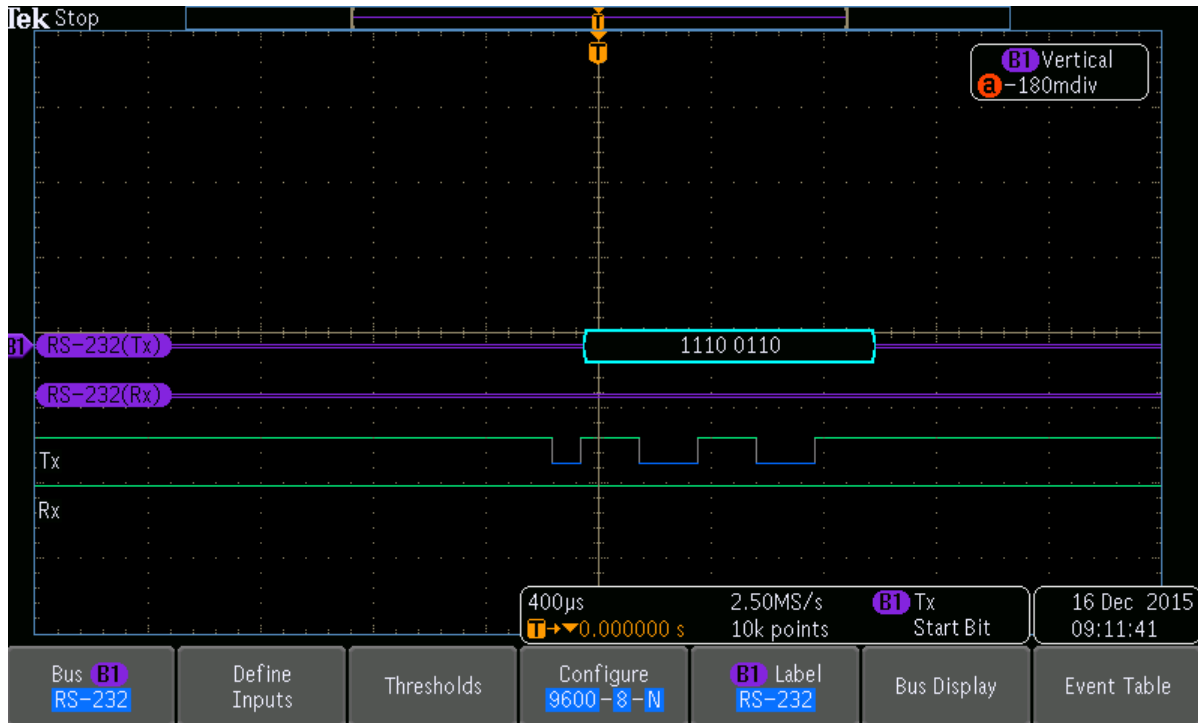


Figure 1

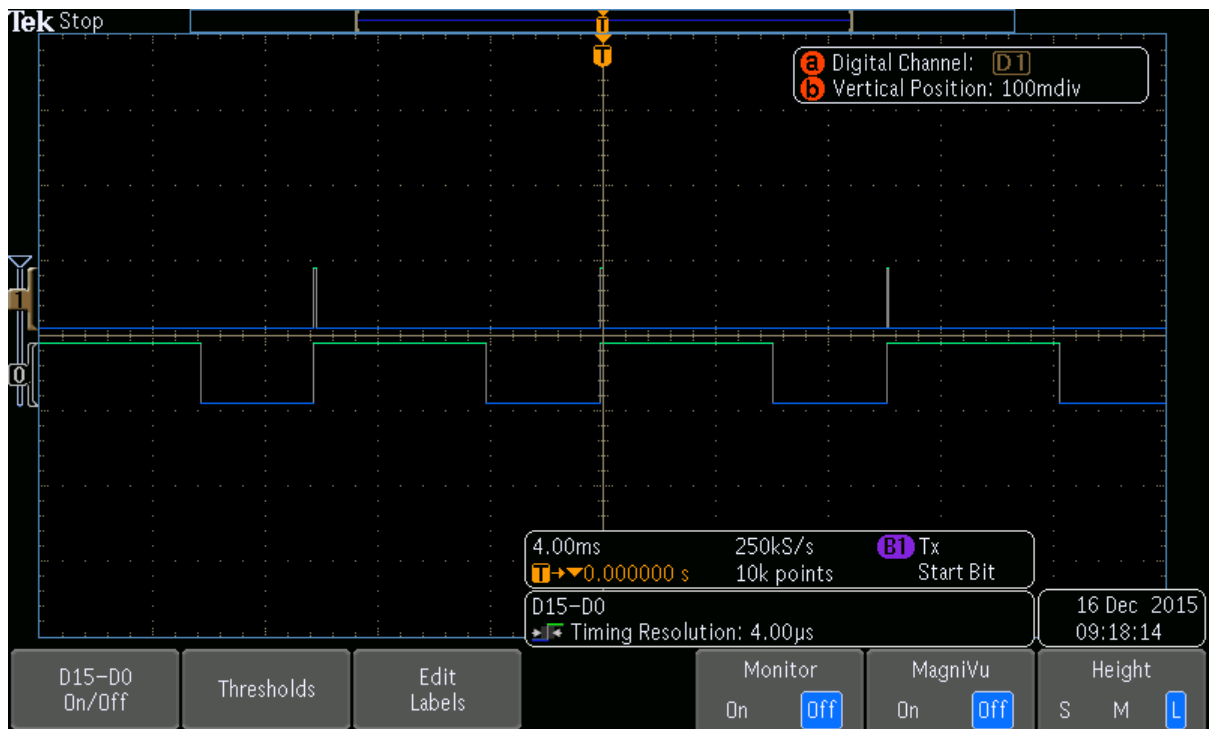


Figure 2

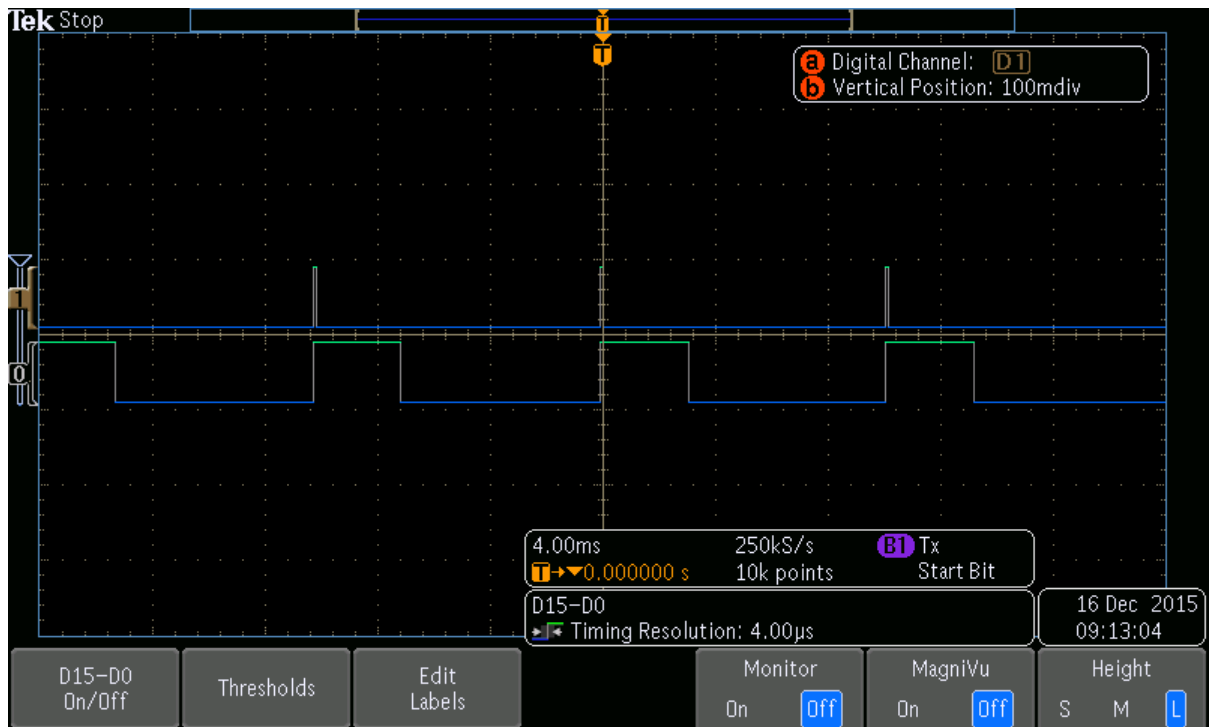


Figure 3

6 Apendix A

6.1 Main.c

```
#include "GPIO.h"

volatile int UART2_NVIC_R __attribute__((at(0xE000E104)));

int PWM0Count = 0, PWM1Count = 0, PWM0Duty = 0, PWM1Duty = 0;
char turningRight = 0, turningLeft = 0;
char inData, hBridge1, hBridge2, drive1, drive2;

void PWM_init() {//page 1233
    SYSCTL_RCGC2_R |= 0x2;
    SYSCTL_RCGCPWMR = 0x1;
    //enable PWM clock in RCGC0 register
    __nop();
    __nop();
    __nop();

    while((SYSCTL_PRGPIO_R&SYSCTL_PRGPIO_R1) == 0){};//wait for clock to stabl

    //Setup GPIO port B
    GPIO_PORTB_LOCK_R = 0x4C4F434B;
    GPIO_PORTB_PUR_R = 0xC0;
    GPIO_PORTB_DIR_R = 0xC0;
    GPIO_PORTB_DEN_R = 0xC0;
}

void UART2_INIT() {
    //UART2 D6,D7
    SYSCTL_RCGCUART_R = 0x4;
    SYSCTL_RCGCGPIO_R |= 0x8;
    __nop();
    __nop();
    __nop();//clock needs some time to initialize
    GPIO_PORTD_LOCK_R = 0x4C4F434B;//unlock port c
    GPIO_PORTD_CR_R |= 0xC0;//enable control register, i dont think we need thi
    GPIO_PORTD_AFSEL_R |= 0xC0;//alternative functionality enabled
    GPIO_PORTD_DEN_R |= 0xC0;//digital enable enabled
    GPIO_PORTD_PCTL_R = 0x11000000;//page 686 PD6 (1), PD7 (1)
    UART2_CTL_R = 0x0;//disable uart
     //(16e6)/(9600*16) = 104.167
    UART2_IBRD_R = 0x68;//104
     //.167 * 64 + .5 = 8.5 rounddown to 11
    UART2_FBRD_R = 0xB;//11
    UART2_LCRH_R |= 0x72;//Set serial parameters: 8-bit word, start/stop/pari
    UART2_CTL_R = 0x301;// Enable rx, tx on uart
    //we can turn off tx if we can somehow link the phone
```

```

//and bluetooth without needing to tx
//INTERRUPT INIT for UART
UART2_IFLS_R = 0x0; //set interrupts rx 1/8 full queue
UART2_RIS_R = 0x10; //page 925
UART2_IM_R = 0x10; //interrupt mask, Rxim page 921
UART2_NVIC_R = 0x2;
}

//Trigger when queue is 3/4 full(12 bytes)
void UART2_Handler() {
    TIMER1_TAILR_R = 0x7A1200; // Reset watchdog timer value
    GPIO_PORTE_DATA_R = 0x0; // Turn on headlights
    if((UART2_FR_R & 0x10) == 0x0) { // RxFE bit Read 1/8 full
        inData = UART2_DR_R;
    }

    //parse incoming data
    hBridge1 = inData & 0x3;
    drive1 = (inData & 0xC) >> 2;
    hBridge2 = (inData & 0x30) >> 4;
    drive2 = (inData & 0xC0) >> 6;

    //Only turn the drive motor if it is not on the stop
    if (hBridge1 == 0x1 && turningRight == 1) {
        hBridge1 = 0x11;
    }
    else if (hBridge1 == 0x10 && turningLeft == 1) {
        hBridge1 = 0x11;
    }

    // Write new command to gpio port
    GPIO_PORTA_DATA_R = (((hBridge1 << 2) | (hBridge2))<<4);
    PWM0Duty = drive1 * 30;
    PWM1Duty = drive2 * 30;

    UART2_ICR_R = 0x1;
}

//Systick initialization. Used for PWM output
void SysTickConfig() {
    NVIC_ST_CTRL_R = 0;
    NVIC_ST_RELOAD_R = 0x640;
    NVIC_ST_CTRL_R = 0x7;
}

//Output PWM when systick expires
void SysTick_Handler(){
    PWM0Count++;
    PWM1Count++;
}

```

```

    if (PWM0Count > 100) {
        PWM0Count = 0;
    }

    if (PWM1Count > 100) {
        PWM1Count = 0;
    }

    if (PWM0Count > PWM0Duty) {
        GPIO_PORTB_DATA_R &= ~0x40;
    }
    else {
        GPIO_PORTB_DATA_R |= 0x40;
    }

    if (PWM1Count > PWM1Duty) {
        GPIO_PORTB_DATA_R &= ~0x80;
    }
    else {
        GPIO_PORTB_DATA_R |= 0x80;
    }

    NVIC_ST_CTRL_R = 0x7;
}

//Initialize port A, used for controlling the motors
void GPIOA_INIT() {
    //A2, A3, A4, A5, A6, A7
    SYSCCTL_RCGC2_R |= 0x1;    //Enable clock for PortA
    GPIO_PORTA_DIR_R = 0xF0;    //Set direction to output
    GPIO_PORTA_PUR_R = 0xC;    //Pull up resistor
    GPIO_PORTA_DEN_R = 0xFC;    //Digital enable
    GPIO_PORTA_IS_R = 0x1;    //Edge triggering
    GPIO_PORTA_IBE_R = 0x1;    //Trigger both edges
    GPIO_PORTA_IM_R = 0xC;    //Pin interrupt
    NVIC_EN0_R = 0x1;    //NVIC
}

//One of the interrupts from the turning feedback was triggered
void GPIOA_Handler() {
    char PORTA_DATA = GPIO_PORTA_DATA_R;
    //Check and see if it is turned to the right
    if ((PORTA_DATA & 0x8) != 0) {
        turningRight = 0;
        turningLeft = 1;
    }
    //Check and see if it is turned to the left
    else if ((PORTA_DATA & 0x4) != 0) {
        turningRight = 1;
        turningLeft = 0;
    }
}

```



```

    }
    //Otherwise, somewhere in the middle
    else {
        turningRight = 0;
        turningLeft = 0;
    }

    GPIO_PORTA_ICR_R = 0xFF; //Service the interrupt
}

//Setup the GPIO port for the LED outptu (head and break lights)
void setupLED() {
    SYSCCTL_RCGC2_R |= 0x10; //Enable clock for PortE
    GPIO_PORTE_DIR_R = 0x1; //set direction to output
    GPIO_PORTE_PUR_R = 0x1; //Pull up resistor
    GPIO_PORTE_DEN_R = 0x1; //digital enable

    GPIO_PORTE_DATA_R = 0x1; //turn off LED lights
}

//Initialize timer 1, used as a watchdog
void Timer1A_init() {
    SYSCCTL_RCGCTIMER_R = 0x2;
    TIMER1_CTL_R = 0x0; //Stop timer
    TIMER1_CFG_R = 0x0; //Select 32 bit mode
    TIMER1_TAMR_R = 0x2; //Periodic mode
    TIMER1_TAILR_R = 0x7A1200; //Timer set to expire after 1 second
    TIMER1_IMR_R = 0x1; //Enable interrupt on port
    NVIC_EN0_R |= (1 << 21); //Enable in NVIC
    TIMER1_CTL_R = 0x1; //Start timer
}

//Respond to the watchdog call
void TIMER1A_Handler() {
    TIMER1_ICR_R = 0x1F;
    GPIO_PORTE_DATA_R = 0x1; //Turn off the lights
    GPIO_PORTA_DATA_R = 0xF0; //Stop the motors

    //Put the motors in stop mode
    PWM0Duty = 0;
    PWM1Duty = 0;
}

int main(void) {
    //Setup everything
    UART2_INIT();
    PWM_init();
    SysTickConfig();
    GPIOA_INIT();
    setupLED();
}

```

```
    Timer1A_init();  
  
    //Wait for bluetooth command  
    while(1);  
}
```

6.2 GPIO.h

This is a file provided by Valvano, please see link for GPIO.h file.
<http://users.ece.utexas.edu/~valvano/arm/>

6.3 iOS Code

Ill let Erik put the code here...