

John Romero Programming Proverbs

- 6. “As soon as you see a bug, you fix it. Do not continue on. If you don’t fix your bugs your new code will be built on a buggy codebase and ensure an unstable foundation.”
- John Romero, “The Early Days of Id Software - John Romero @ WeAreDevelopers Conference 2017”

If your ioquake is not allowing Pylego to disableAI

- then you need to download and install this tarball

- ```
$ ssh mcgreg.comp.glam.ac.uk
<enter your linux password>
$ cd $HOME/Sandpit
$ wget http://floppsie.comp.glam.ac.uk/download/c/ioquake-20161025.tar.gz
$ rm -rf ioquake-latest
$ tar zxf ioquake-20161025.tar.gz
$ exit
your command line is back on the client
$ cd $HOME/Sandpit/ioquake-latest3/ioquake
$./compilequake
```

- please only do the above if you are experiencing problems getting pylego to connect

## python-bot/bot-legoman/botfiles/bots/botlib.py

- enumerated type of rpc meta types:

- ```
CHAR, WEIGHT, AI, BASIC, GOAL, COMMANDS = range(1, 7)
```

- CHAR

- the packets contain characteristic information

- WEIGHT

- not yet implemented, but it will upload weightings for weapons


- AI

- codes are only just being implemented they consist of new commands necessary to enable Python to connect to ioquake

`python-bot/bot-legoman/botfiles/bots/botlib.py`

- the following meta types correspond to the AI layered architecture in ioquake (they should be extended when time permits)
- BASIC
 - basic actions which we can tell the bot to do (jump, crouch, fire)
- GOAL
 - interface to the goal logic of the AI engine.
- COMMANDS
 - give bot commands (as a team leader)

python-bot/bot-legoman/botfiles/bots/botlib.py



```
# AI codes
SKILL, CONT = range(1, 3)
# BASIC codes
JUMP, CROUCH, FIRE = range(1, 4)
```

class bot: __init__

```
def __init__ (self, server, port):  
    global s  
  
    self.init_chars()  
    s = socket(AF_INET, SOCK_STREAM)  
    print "bot trying to connect to the server",  
    while True:  
        try:  
            s.connect((server, port))  
            break  
        except:  
            print ".",  
            sys.stdout.flush()  
            time.sleep(1)  
    print "bot connected"
```

class bot: init_chars (self)

- initialises all the characteristics which can be altered in the Python bot
- no data is sent to the ioquake3 server at this point
- the `botlib.py` is told the characteristic name, type, code, max, min values

Python bot

- recall our bot code can be simplified to

Python bot

```
id = botlib.bot("localhost", 7000)
print "hello world, python is alive in Quake 3"
id.defaults()
print "bot is now active!"
id.disableAI()
while True:
    print "trying to crouch"
    id.crouch()
    print "in crouch position"
    time.sleep(1)
    id.jump()
    print "in jump position"
    time.sleep(1)
    id.fire()
    print "fire"
    time.sleep(1)
```

class bot: defaults

■ [ioquake-latest/python-bot/bot-legoman/botfiles/bots/botlib.py](#)

```
def defaults(self):
    if self.skill() == 1:
        self.c_name.set("Pylego")
        self.c_gender.set("male")
        self.c_attack_skill.set(0.9)
        self.c_weaponweights.set("bots/Easy_w.c")
        self.c_aim_skill.set(0.95)
    ...
```

class bot: skill

■ [ioquake-latest/python-bot/bot-legoman/botfiles/bots/botlib.py](#)

```
def skill (self):  
    """ this must be the next method called after __init__ """  
    print "sending skill"  
    return callBI(AI, SKILL)
```

callBI

■ [ioquake-latest/python-bot/bot-legoman/botfiles/bots/botlib.py](#)

```
#  
# callBI - makes a call and returns an byte integer.  
#  
  
def callBI (c1, c2):  
    global s  
  
    p = makeHeader(struct.pack("B", c1), struct.pack("B", c2))  
    for i in p:  
        print ord(i),  
    print  
    s.send(p)  
    return getReturnByte(s)
```

■ the `struct.pack("B", c1)` packs a Python integer `c1` into a byte

makeHeader

■ [ioquake-latest/python-bot/bot-legoman/botfiles/bots/botlib.py](#)

```
#  
# makeHeader - creates the rpc header  
#  
  
def makeHeader (meta, data = ""):  
    s = meta + data  
    return prependLength(s)
```

makeHeader

■ [ioquake-latest/python-bot/bot-legoman/botfiles/bots/botlib.py](#)

```
#  
# prependLength - places the length byte at the start of the packet  
#  
  
def prependLength (s):  
    print "prepending length of", len(s)  
    return struct.pack("B", len(s)) + s
```

getReturnByte

ioquake-latest/python-bot/bot-legoman/botfiles/bots/botlib.py

```
#
# getReturnByte - defensively receives the return byte
#

def getReturnByte (s):
    p = ""
    while True:
        p = s.recv(1)
        if len(p) == 1:
            print "received packet of length", ord(p[0])
            break
    if ord(p[0]) == 2:
        while True:
            p = s.recv(1)
            if len(p) == 1:
                break
        printf("byte returned has value %d\n", struct.unpack("B", p)[0])
        return struct.unpack("B", p)[0]
    else:
        printf("expecting length of 2 received %d\n", ord(p[0]))
    return 0
```

Protocol

- first byte contains the packet length
- so the above code expects two bytes
 - a length byte of value, 2
 - the second byte is the data byte which is returned as an integer

setchar - low level function to send a characteristic to the ioquake3 server

■ [ioquake-latest/python-bot/bot-legoman/botfiles/bots/botlib.py](#)

```
#
# setchar - send value using code, type, value to the server
#

def setchar (code, type, value):
    global s

    print "sending characteristic", code, type, value
    c = struct.pack("B", CHAR)
    d = struct.pack("B", code)
    if type=="int":
        s.send(makeHeader(c, d+struct.pack("i", value)))
    elif type=="float":
        s.send(makeHeader(c, d+struct.pack("f", value)))
    elif type=="string":
        s.send(makeHeader(c, d+struct.pack("(%ds" % (len(value)+1)), value)))
    if not getReturnBoolean(s):
        print "failed to set characteristic", code, "type", type, "value", value
```

ioquake3 server must match these rpc requests

- examine the file `$HOME/Sandpit/ioquake-latest/ioquake3/code/botlib/be_ai_py.c` and in particular start by understanding the function `initPy`
- then examine `testFor` and `waitForCont`
- notice that both are very similar
- notice that `execFunction` is called to handle the rpc
 - a return packet is sent back provided that the `execFunction` populated the return buffer
- understand that the rpc server is a state machine
 - `py->state` is set to `pyInit`, `pyOut`, `pyIn`

testFor

ioquake-latest/ioquake3/code/botlib/be_ai_py.c

```
int testFor (py_bot_t *py)
{
    if (py->state == pyInit) {
        py->in = 0;
        py->out = 0;
        py->used = 0;
        py->state = pyIn;
    }
    if (py->state == pyIn) {
        if (getPacket(py, qtrue))
            py->state = pyInit;
        else
            return qfalse;
        execFunction(py);
    }
}
```

testFor

ioquake-latest/ioquake3/code/botlib/be_ai_py.c

```
if (py->state == pyOut) {  
    if (putPacket(py, qtrue)) {  
        py->out = 0;  
        py->used = 0;  
        py->state = pyInit;  
    } else  
        return qfalse;  
}  
return qtrue;  
}
```

Tutorial

- read these notes carefully and open up emacs and read the actual code being discussed
- take a pen and paper and now create your own notes detailing how a Python call to the method `ourself` is executed
 - your notes should include both client and server activity