



Activity manual

version 1.0 Standard

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Arduino is an open source project supported by many. The Team is composed of Massimo Banzi, David Cuartielles, Tom Igoe, Gianluca Martino, and David Mellis. Nicholas Zambetti has contributed since the beginning. Yaniv Steiner and Giorgio Olivero have been supporting the project and are working at using it with the Instant Soup platform. The Arduino platform used to include the avr-gcc tool chain, uisp, and the Procyon AVR-LIB by Pascal Stang. The Arduino language syntax is based on Wiring by Hernando Barragan. The Arduino environment is based on Processing by Ben Fry and Casey Reas. Thanks to all the people who are supporting arduino.

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1 : POP-BOT part list

1.1 Part list of POP-BOT mobile robot kit

1. POP-168 The Arduino-mini compatible microcontroller module
2. RBX-168 Robot controller board with 4-AA battery holder
3. Switch module with JST cable (2 sets)
4. Infrared Reflector board with JST cable (2 sets)
5. GP2D120 Infrared distance sensor with JST cable
6. Serial LCD 16 characters by 2 lines module with LED backlight and cable
7. 48:1 ratio 4.5V DC motor gearbox with IDC cable (2 sets)
8. Standard servo motor (Operating voltage is 4.8 to 7.2Vdc)
9. Circle wheel and Threaded rubber wheel set with 2mm. tapped-screw. (2 sets)
10. 80x60 cm. and 80x80 cm. Plastic Grid plate set (2 sets)
11. Circle base with idle ball wheels
12. Plastic joiner and Strip joiner set (60 pieces of 3-type mix colored plastic joiner, 4 pieces of each 3/5/12 holes of Strip joiner)
13. Right-angled metal shaft set (4 pieces of each 1x2, 2x2, 2x5 Right-angled metal shaft)
14. Nuts and Screws set
15. Line tracking demo paper sheet
16. UCON-4 USB to serial converter cable for downloading and communication
17. CD-ROM contains software tools, source code and documentation

1.2 Microcontroller components information

1.2.1 POP-168 microcontroller module

The Arduino POP-168 is a flexible board with no hidden components which allows full development of its features with AVR Standard tools like the like IAR C/C++ , MikroElektronika Mikro BASIC/ MikroPascal for AVR, and also the open-source tool WINAVR: AVRGCC for Windows ... etc.

Arduino POP-168 use the ATmega168 of AVR microcontroller from Atmel (www.atmel.com). **Arduino POP-168**is **oin assignment is similar** BASIC Stamp **module** (www.parallax.com). **It includes** RS-232 serial port communication circuit for downloading and data communication with computer. Arduino POP-168 module's hardware is compatible with Arduino-mini in Arduino project (www.arduino.cc/en)

The complete schematic diagram of Arduino POP-168 module is shown in figure 1-1. The summarize features of POP-168 module is as follows :

- ATmega168 on board with 10-bit ADC converter, 16KB flash program memory, 512-byte EEPROM, 1KB RAM, 16MHz clock
- Built-in RS-232 interface for Communication
- Immediate code upload with the built-in Bootloader
- Reset Button for reset capability
- Small Form Factor for compact size development
- ISP port for programming with the PX-400/PX-4000 device
- SMD Leds for indications
- Fully compatible with the Arduinno Project
- 16 I/O pin assignement compatible i-Stamp/i-Stamp2P24 module
- Supply voltage range +3.3 to +5V 50mA

1.2.2 RBX-168 Robot controller board for Arduino POP-168

The RBX-168Robot controller board is a complete, low-cost development platform designed for those interested in learning and using Arduino POP-168 module in robotic applications. Its compact size, convenient features, and low price make it an ideal tool for the student and educator. Figure 1-2 shows the layout of RBX-168 board and complete schematic diagram of its is shown in the figure 1-3. The summarized technical feature of the RBX-168 board is as follows :

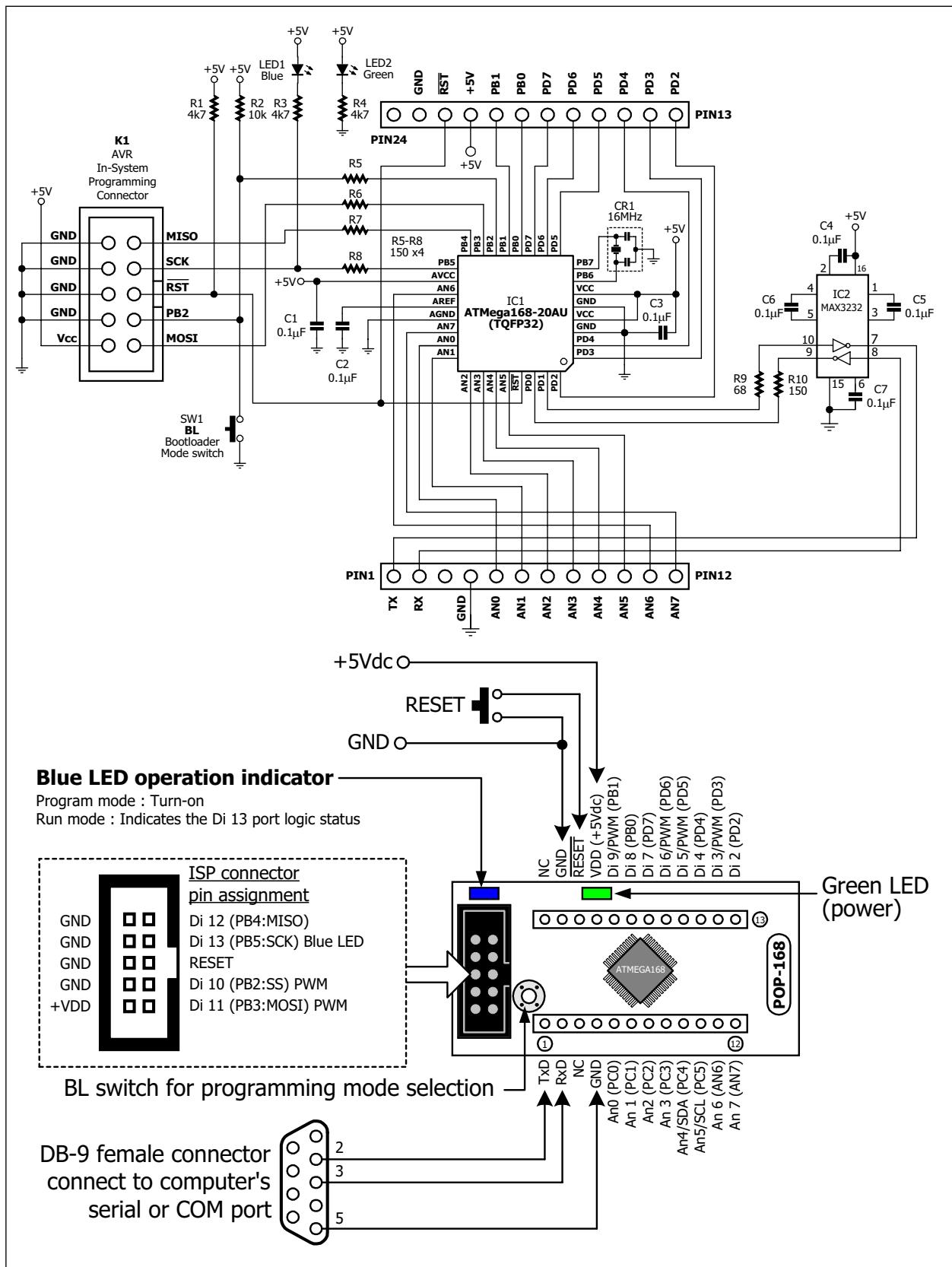


Figure 1-1 Schematic diagram, Pin assignment and simple connection of POP-168 microcontroller module

- Screw terminal block for battery connections. It supports +4.8 to +12Vdc and has an on-board power switch.
- +5Vdc switching regulator power supply circuit. Its regulates the supply voltage for POP-168 module and all sensor ports.
- 2-push button switch are connected with the digital port 2 (Di2) and 4 (Di4). Also connndt with LED for indicator the operation.
- 5-Universal port support Analog input function and Digital input/output function; An1 (Di15) to An5 (Di19)
- 2-Analog input port ; An6 and An7. Both port pin are analog input only.
- I²C bus port; An4 (SDA) and An5 (SCL)
- RS-232 serial port interfacing.
- 2-ch. DC motor driver with indicators. Support motor voltage 2.5 to 13.5Vdc.
- 2-Servo motor output; connect with the digital port 7 (Di7) and 8 (Di8).
- Piezo speaker connections (do not show in the figure 1-2; it is fixed at bottom circuit board of RBX-1689 board. It is connected with POP-168 An0/Di14 pin.

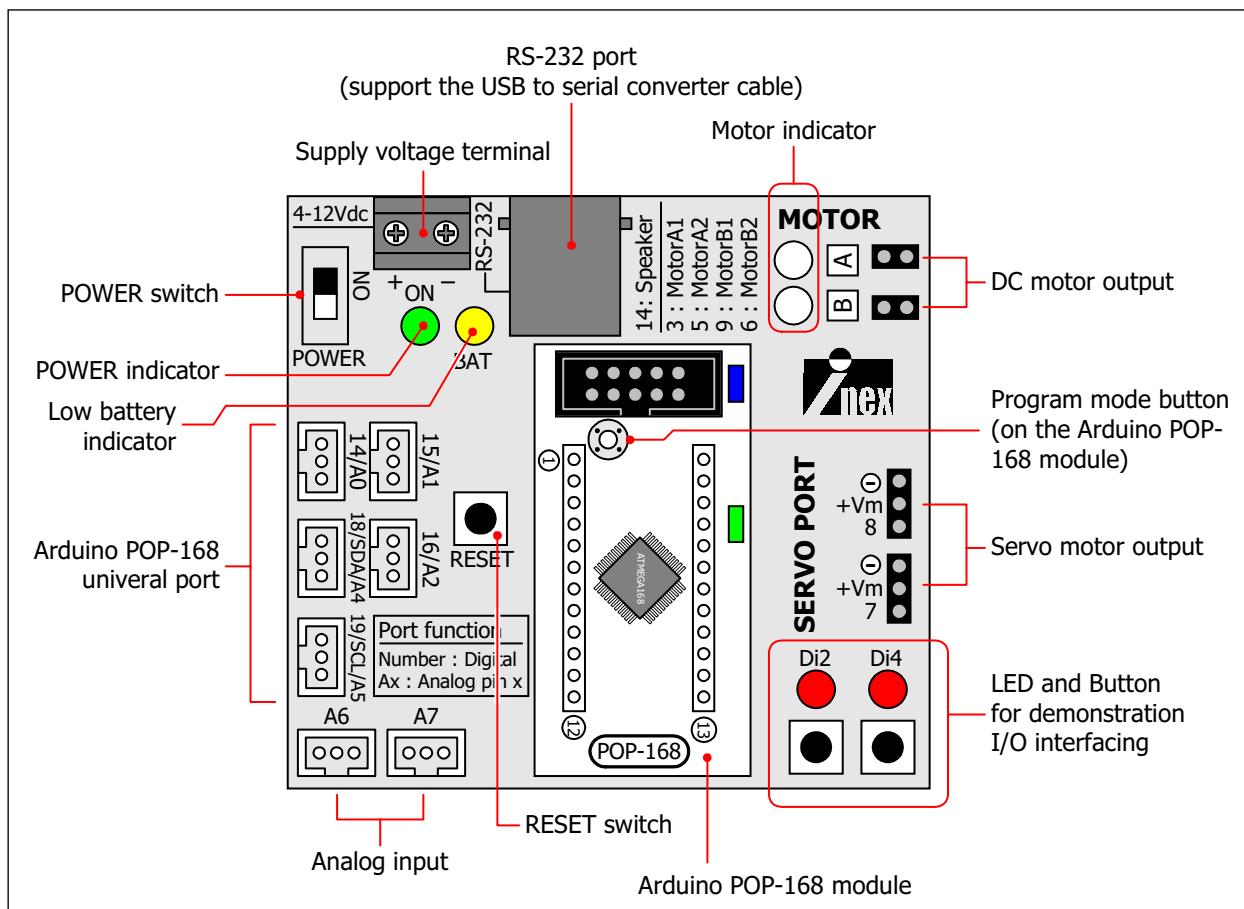


Figure 1-2 The layout of RBX-168 controller board

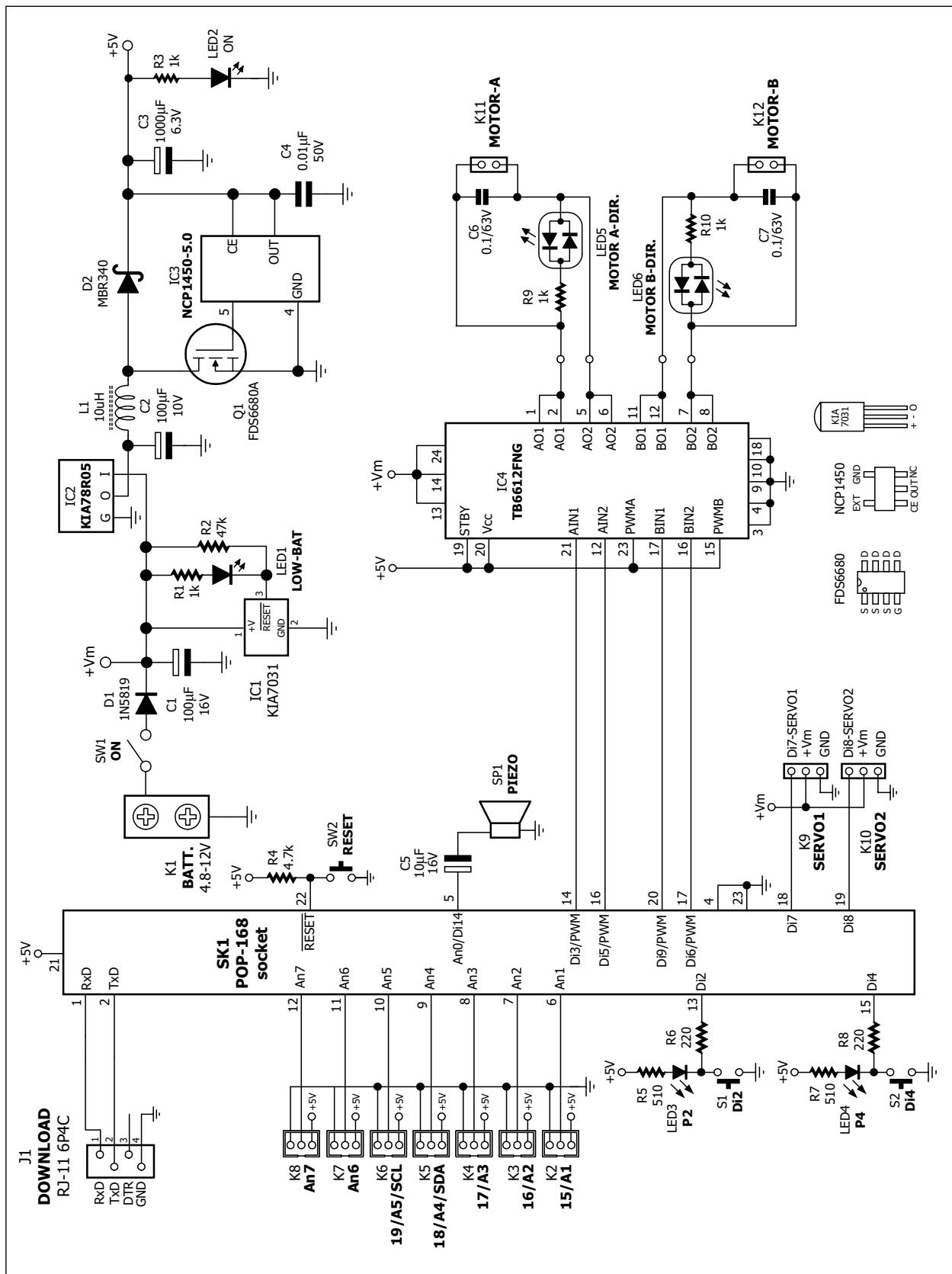
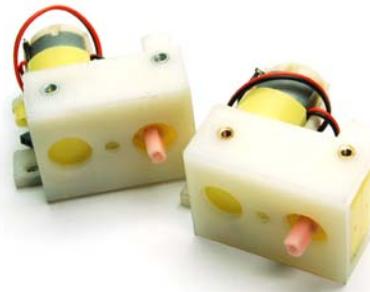


Figure 1-3 The completely schematic diagram of RBX-168 controller board

1.3 Output device features

1.3.1 DC motor gearbox

This robot kit provides 48:1 ratio DC motor gearbox; model BO-2 with IDC connector cable. This is features :



- Operating voltage is +3 to +9Vdc
- Current consumption 130mA @ +6Vdc and no load)
- Average speed 170 to 250 round per minute (RPM) @ +6V and no load
- Weight is 30 grams
- Minimum torque is 0.5 kg.cm.
- Attached with the plastic mounting with 5 of insert nuts
- 42 x 45 x 22.7 mm. (WxLxH) dimension

1.3.2 Standard RC servo motor

The standard servo is ideal for robotics and basic movement projects. These servos will allow a movement range of 0 to 180 degrees. The servo output gear shaft is a standard Futaba configuration. Technical Specifications are :



- Operating voltage is 6Vdc max.
- Speed 0 deg to 180 deg in 1.5 seconds on average.
- Weight 45.0 grams/1.59oz
- Torque 3.40 kg-cm/47oz-in
- Size mm (L x W x H) 40.5x20.0x38.0

1.3.3 SLCD16x2 : 16 characters 2 lines Serial LCD module

The 16x2 Serial LCD module provides a simple way to display data from micro-controller. The module requires only one I/O pin, +5 V and ground to function. Simple serial data out commands can be used in the Arduino POP-168 module to communicate with the module at 2400 and 9600 baud.

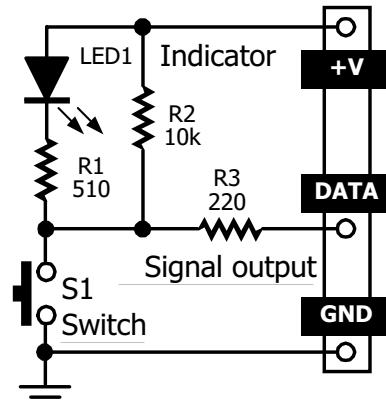


Features of the 16x2 Serial LCD Module:

- Serial Input with Invert/Non-invert TTL logic level.
- 1/8 or 1/16 Duty can be selected by jumper.
- Scott Edwards's LCD Serial Backpack™ command compatible addition with Extended Command that make LCD control easier.
- Operation with +5 Vdc supply
- SLCD16x2 provides a brightness adjustment with variable resistor at **BRIGHTNESS** position.
- Interfacing connector has 3 pins : +5V Supply voltage (+), Serial data input (**S**) and Ground (**G**).

1.4 Sensor module features

1.4.1 Switch module/Touch sensor



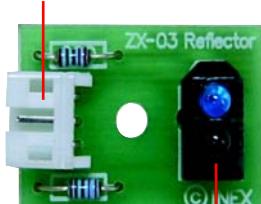
The switch input is used to detect collision at logic $\overline{0}$. Two sets along with the connecting cable are provided.

1.4.2 ZX-03 : Infrared reflector sensor

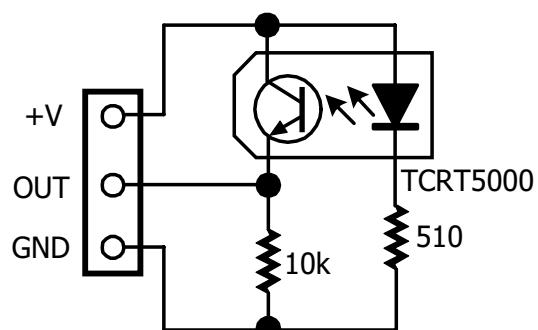
The heart of this sensor is TCRT5000 reflective object sensor. It is designed for close proximity infrared (IR) detection. There is an infrared diode behind its transparent blue window and an infrared transistor behind its black window. When the infrared emitted by the diode reflects off a surface and returns to the black window, it strikes the infrared transistor's base, causing it to conduct current. The more infrared incident on the transistor's base, the more current it conducts. When used as an analog sensor, the ZX-03 can detect shades of gray on paper and distances over a short range if the light in the room remains constant.

The suitable distance from sensor to line or floor is during 3 to 8 mm. The output

Signal connector



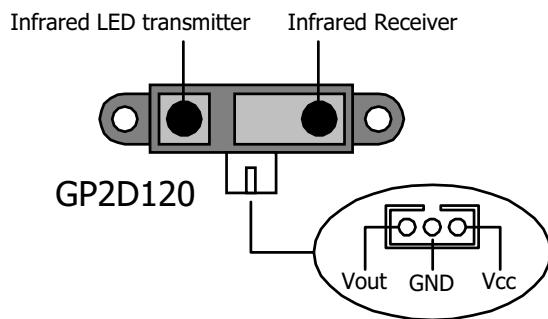
Infrared Reflector



voltage is during 0.1 to 4.8V and digital value from 10-bit A/D converter is 20 to 1,000. Thus, ZX-03 will be suitable to apply to line tracking sensor.

1.4.3 GP2D120 Infrared distance sensor

One of the special sensors in robotics is the GP2D120. It is an Infrared Distance sensor. Some people call it the IR Ranger. With the GP2D120 module, it adds the distance measuring and Obstacle detection using infrared light feature to your robot. Your MicroCamp robot can avoid obstacles without having to make any physical contact.



Features of the GP2D120 module

- Uses Infrared light reflection to measure range
- Can measure a range from 4 to 30 cm.
- 4. 5 to 5 V power supply and 33mA electric current
- The output voltage range is 0.4 to 2.4V when supplied by +5V

GP2D120 Infrared Ranger module has 3 terminals: Power input (Vcc), Ground (GND) and Voltage output (Vout). To read the voltage values from the GP2D120, you must wait till after the acknowledgement period which is around 32 to 52.9 ms.

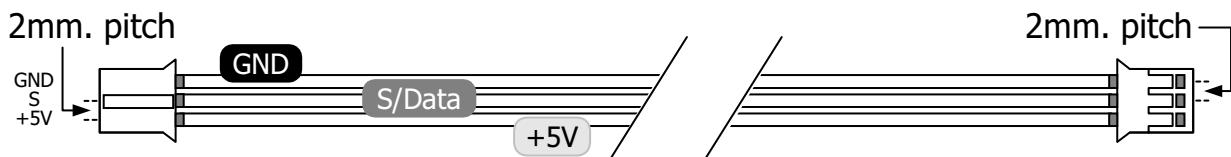
The output voltage of GP2D120 at a range of 30 cm and +5V power supply is between 0.25 to 0.55V, with the mean being 0.4V. At the range of 4 cm., the output voltage will change at $2.25V \pm 0.3V$.

1.5 POP-BOT cable information

The POP-BOT mobile robot kit includes some signal cables for the interfacing between the controller board, sensor module and the computer. They includes the JST3AA-8 cables for interconnection to the sensor module, UCON-4 the USB to RS-232 converter cable for interfacing with the computer.

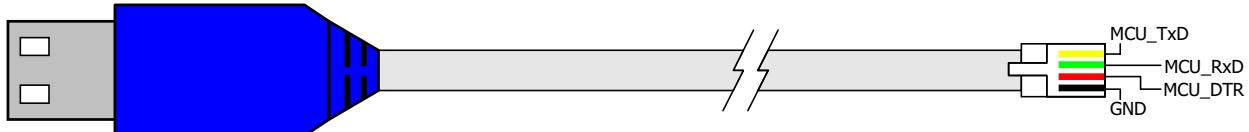
1.5.1 JST3AA-8 cable

This is an INEX standard cable, 3-wires combined with 2mm. The JST connector is at each end. 8 inches (20cm.) in length. Used for connecting between microcontroller board and all the sensor modules in the POP-BOT robot kit. The wire assignment is shown in the diagram below.



1.5.2 UCON-4 USB to Serial port converter cable

This is used to connect between the computer's USB port and the RBX-168 controller board. The cable's end uses a Modular plug RJ-11 6P4C (6-pins form and 4-contacts). Its Length is 1.5 meters approximation. The cable assignment is shown in the diagram below.

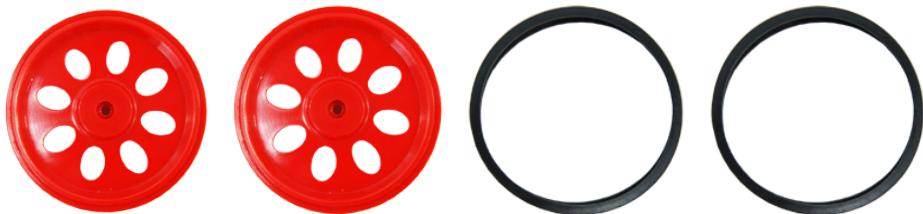


This cable requires +5V from USB port and support USB 1.0/2.0. User can set the baudrate up to 115,200 bit per second. Requires the driver installation before using.

1.6 Mechanical prt features

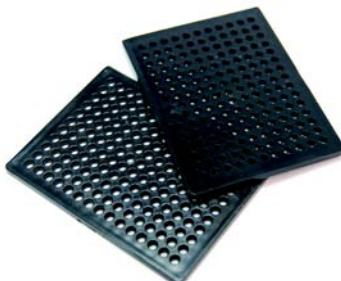
1.6.1 Circle wheel and Tire set

Includes 2 pairs of the suitable circle wheel for BO-2 DC motor gearbox and tread rubber tire. Fix the wheel with gearbox shaft by 2mm. self-tapping screws



1.6.2 Plastic grid plate set

Includes each of the universal plastic grid plate 2 sizes; 80x60mm. and 80x80mm. Each plate provides 3mm. diameter holes with 5mm. pitch.



1.6.3 Circle base

This base is injected from high quality ABS plastic. Diameter ismm. It has 2 free ball wheels at both side. This base has many 3mm. holes for fixing the controller board, sensors and more mechanical parts.



1.6.4 Plastic joiners

60 pieces of varied color joiners made from PVC plastic. They can be connected together or by using screws and 3 mm nuts in installation. There are 4 types; Right angle, Obtuse, Straight joiner and Hole straight joiner.



1.6.5 Strip joiners

They are made from plastic. Each joiner has 3mm. hole 5mm. pitch. Each joiner can connect for lenght expansion. They are 4 pieces of 3 sizes; 3, 5 and 12 holes type. Total 12 pieces.



1.6.6 Box holder

It is injected plastic box for supporting the RBX-168 controller board. It has some of 3mm. hole for fixing with any platform.



1.6.7 Right-angle metal shaft

It is 7.5mm. width right-angle metal shaft. Each shaft has 3mm. hole for inserting the screw to fix with another structures. The set includes 4 pieces of 1x2, 2x2 and 2x5 holes metal shaft.



1.6.8 Screw and Nut set

Includes 2 of 2mm. self-tapping screws, 4 of 3x8mm. M3 screws, 30 of 3x10mm. M3 screws, 4 of 3x15 mm. M3 screws, 4 of 3x40mm. M3 screws, 10 of 3x8mm. flat-head screws and 30 of 3mm. M3 nuts.



1.6.9 Metal spacer

They are metal parts for supporting the plate and sensor board. They are made from nikle plating metal. Includes 6 of 33mm. metal hexagonal spacers. Each standoff has 3mm. thread through-hole.



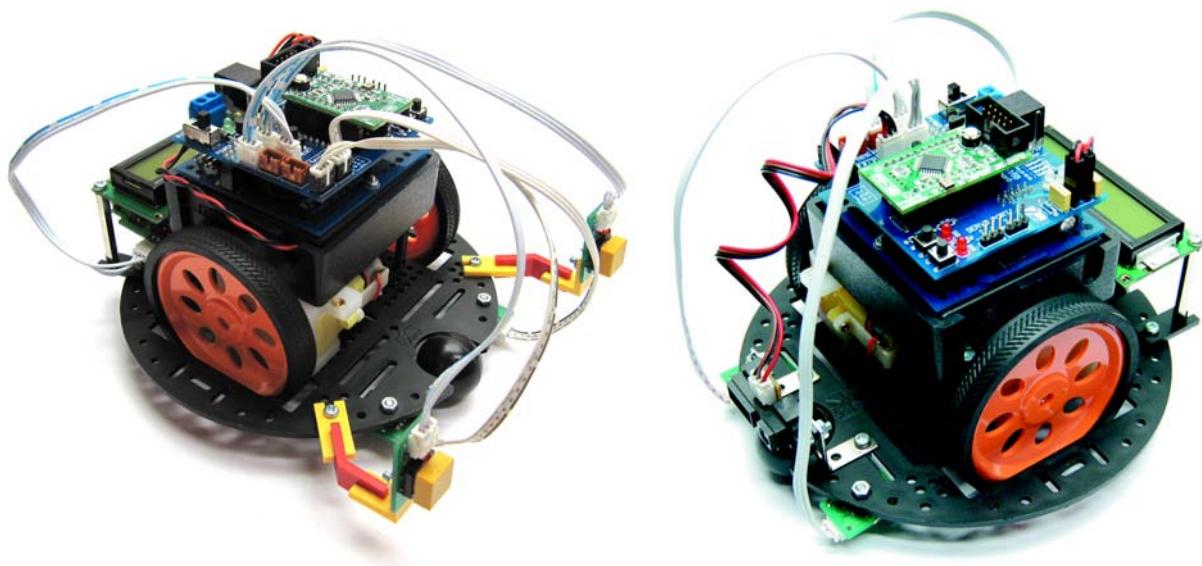
1.6.10 Plastic spacer

They are some mechanical parts for supporting the plate and sensor board. This kit includes 4 pieces set of plastic spacer (3mm., 10mm., 15mm. and 25mm.) 4 sets



2 : Building POP-BOT mobile robot

2.1 POP-BOT features



- Move with DC motor gearboxes and wheels.
- Controlled by Arduino POP-168 microcontroller module. Based on ATmega168 microcontroller.
- Programmable via serial port and support the USB to serial port converter.
- Support variety of sensors such as Infrared reflector for line tracking, Touch sensor for object avoiding, Infrared ranger or Distance sensor for touchless object avoiding.
- Support the wired remote control included PlayStation controller.
- Support the wireless serial data communication module such as XBee, XBee-Pro and Bluetooth.
- Includes 16x2 Serial LCD module for monitoring and display operating status.
- 2 servo motor driver port. Support small RC servo motor 4.8 to 6V.
- Requires 4 of AA batteries. The Alkaline, Evolta and Rechargeable Ni-MH are recommended.

2.2 Part list



Circle base x 1



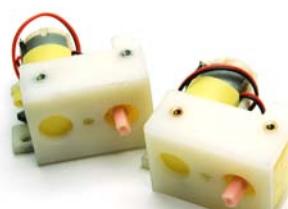
RBX-168 board with POP-168 x1



Box holder x 1



Circle wheel and tire x 2



DC motor gearbox x 2



33mm. metal spacer x 4



Serial LCD module x 1



Infared reflector x 2



GP2D120 distance sensor x 1



Plastic joiners



Right angled metal shaft 2x2 x 2



2mm. self-tapping screw x 2



Plastic spacer set



Screw and Nut set

2.3 Building procedure

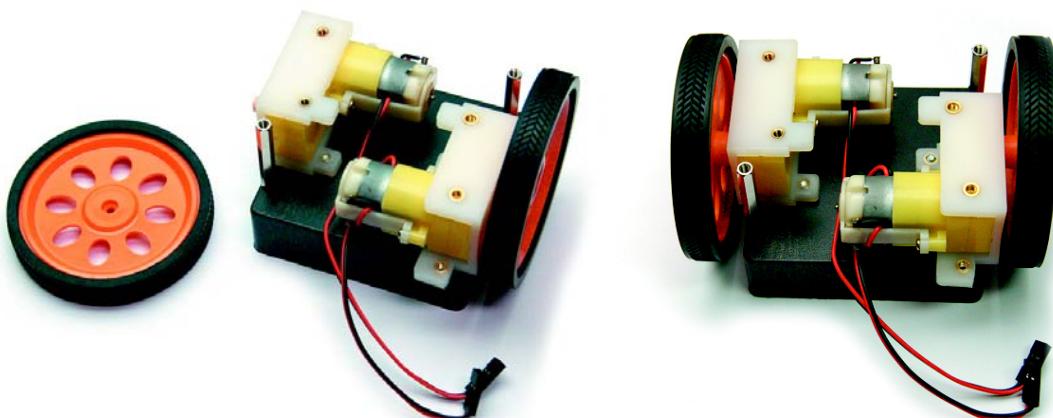
(1) Attach both DC motor gearboxes with the Box holder by 3x8mm. flat screws.



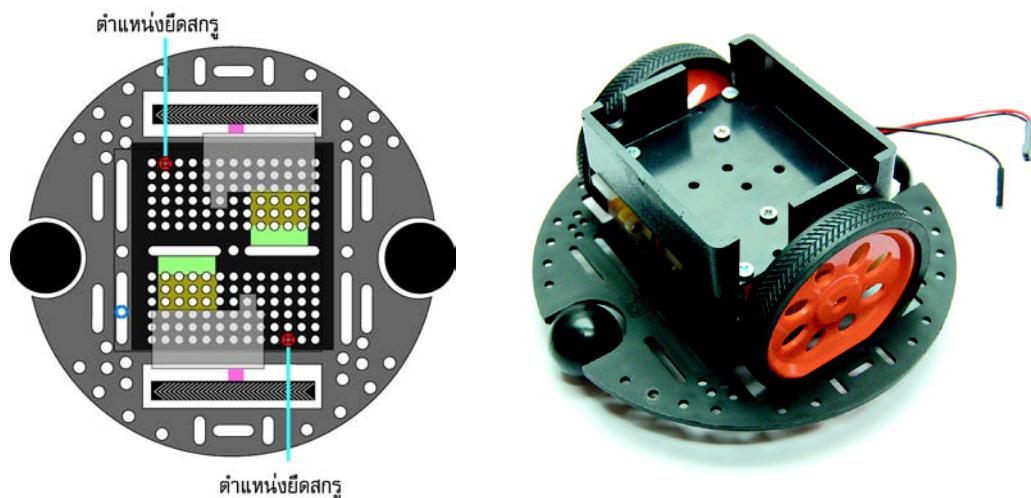
(2) Attach 2 of 33mm. metal spacers with the Box holder by 3x8mm. flat screws at the position following the pictures below.



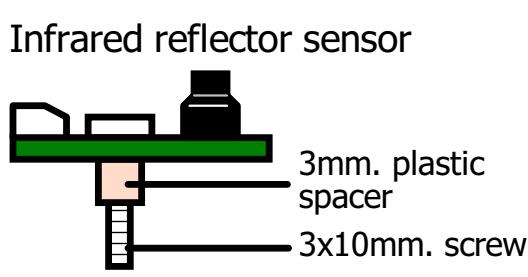
(3) Insert the wheel with tire to DC motor gearbox's shaft and fix with 2mm. self-tapping screws.



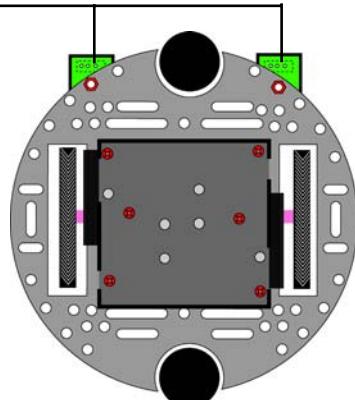
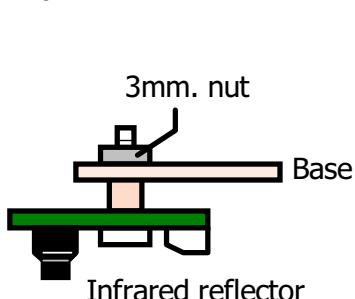
(4) Attach the gearbox structure as shown in step (3) with the circle base by using 3x6mm. screws at the position following the pictures below. See the weheelis position is the center of base.



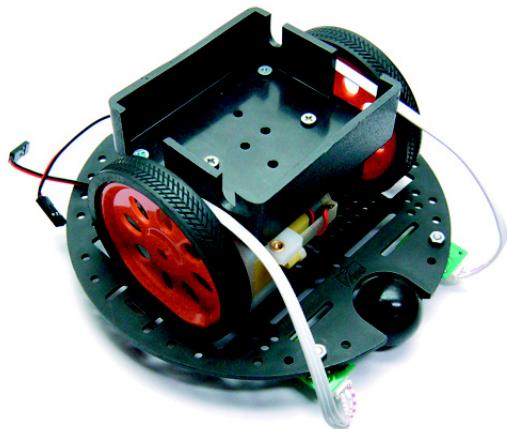
(5) Insert the 3x10mm. screw via the Infrared reflector's hole and 3mm. plastic spacer. Make 2 sets.



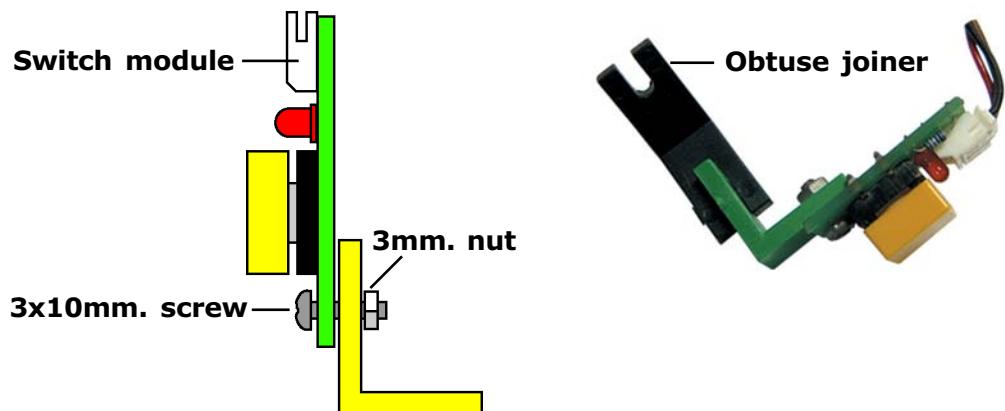
(6) Fix both Infrared reflector structures from step (5) at the in-front-of robot base both side by using 3mm. nut.



(7) Now the POP-BOT chassis with Infrared reflector sensors is ready.



(8) Attach the Right angle joiner with Switch module by using 3x10mm. screw and 3mm. nut following connect the obtuse joiner at the end of the right angle joiner. Make 2 sets.



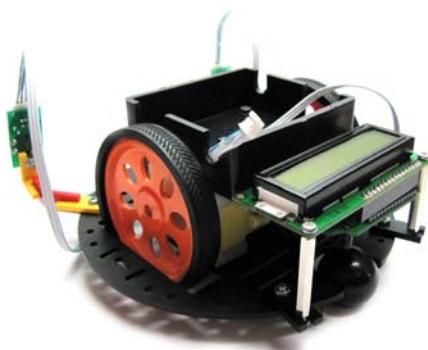
(9) Fix 2 pieces of Straight joiner at the front of robot chassis by using 3x6mm. screws and 3mm. nuts. Next, connect the Switch structures from step (9) at the end of Straight joiners.



- (10) Attach 2 of 33mm. metal spacers with SLCD16x2 module by using 3x6mm. screws. Next, fix the straight joiner at the end of spacer by using 3x10mm. screw.

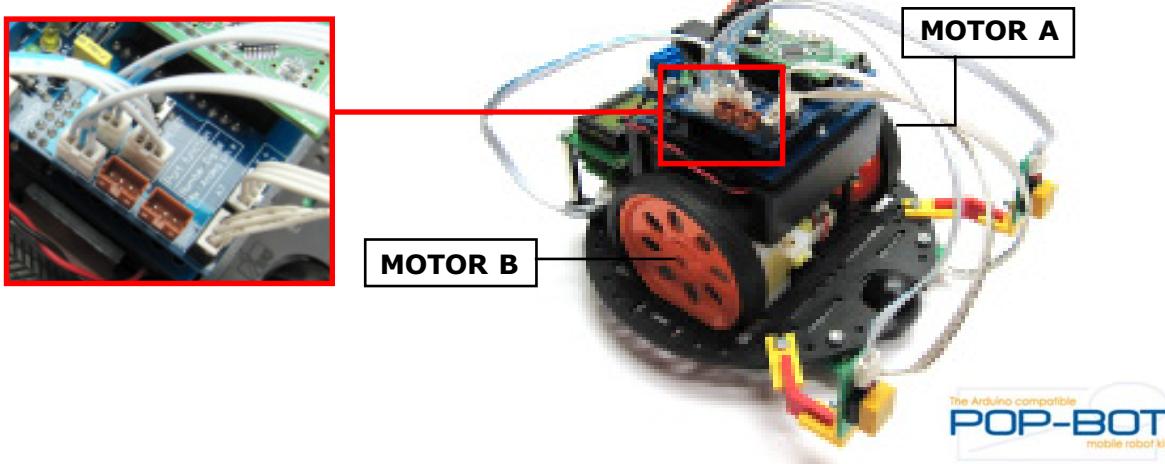


- (11) Fix the SLCD16x2 structure from step (10) at the back of robot chassis following the picture below by using 3x10mm. screws and 3mm. nuts



- (12) Put the RBX-168 board into the Box holder. Connect all cables. Start with Left motor cable to MOTOR A output, Right motor cable to MOTOR B output. Connect the left Infrared reflector cable to **A7** pin, the right Infrared reflector cable to **A6** pin. Next, connect the leftt switch module cable to **15/A1** pin, the right switch cable to **17/A3** and connect SLCD16x2 to **16/A2 pin**.

The POP-BOT is just ready for programming now.



3 : Introduction to Arduino IDE

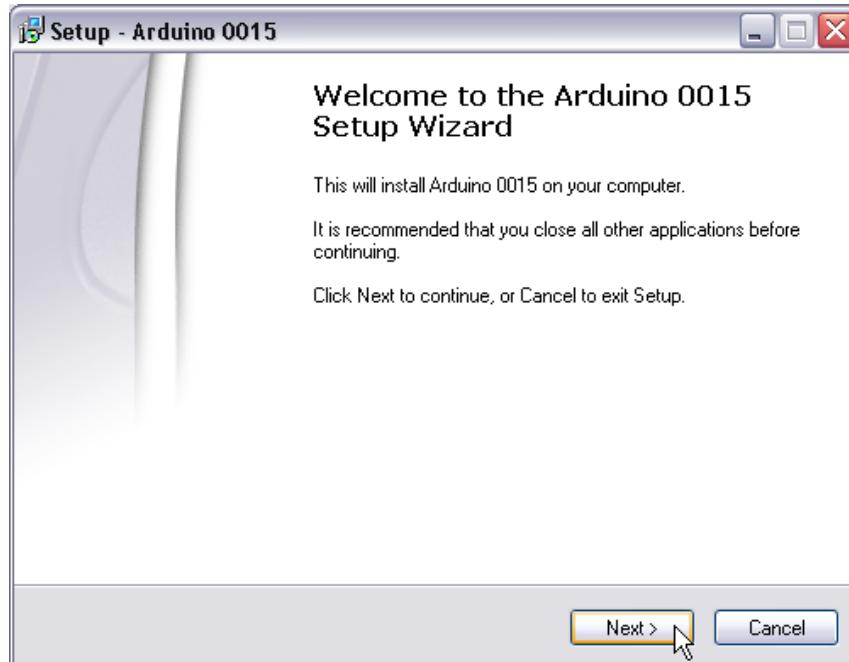
Arduino is an open-source electronics prototyping platform based on flexible, easy-to-use hardware and software. It's intended for artists, designers, hobbyists, and anyone interested in creating interactive objects or environments.*

This chapter describe about introduction to Arduino. Begin with Installation, explain about Arduino IDE components and Menu bar details.

3.1 Installation software

(1) Insert the POP-BOT CD-ROM to CD drive of your computer.

(2) Enter the **Software → Arduino** folder. Find the **ArduinoSetup.exe** and double-click. The installation will start .



POP-BOT CD-ROM contains the Arduino software V15 , all example codes for POP-BOT activities and necessary library files. You can get the latest version of Arduino at www.arduino.cc. However you need to ensure the correct path of POP-BOT library after you upgrade the new version of Arduino IDE.

* Introduction paragraph is from Arduino website (www.arduino.cc)

3.2 Arduino environment

After starting Arduino IDE, the main window will appear as shown in the figure 3-1. The Arduino includes the environments as follows.

- **Menu** : Select the operation command
- **Toolbar** : Includes all most command button
- **Tabs** : Allows you to manage sketches with more than one file (each of which appears in its own tab).
 - **Text editor** : Text editor area for creating the sketch.
 - **Message area** : Shows the program operation status such as compiling result.
 - **Text area** : The space demonstrates compiling information and Serial data Terminal window if enable.

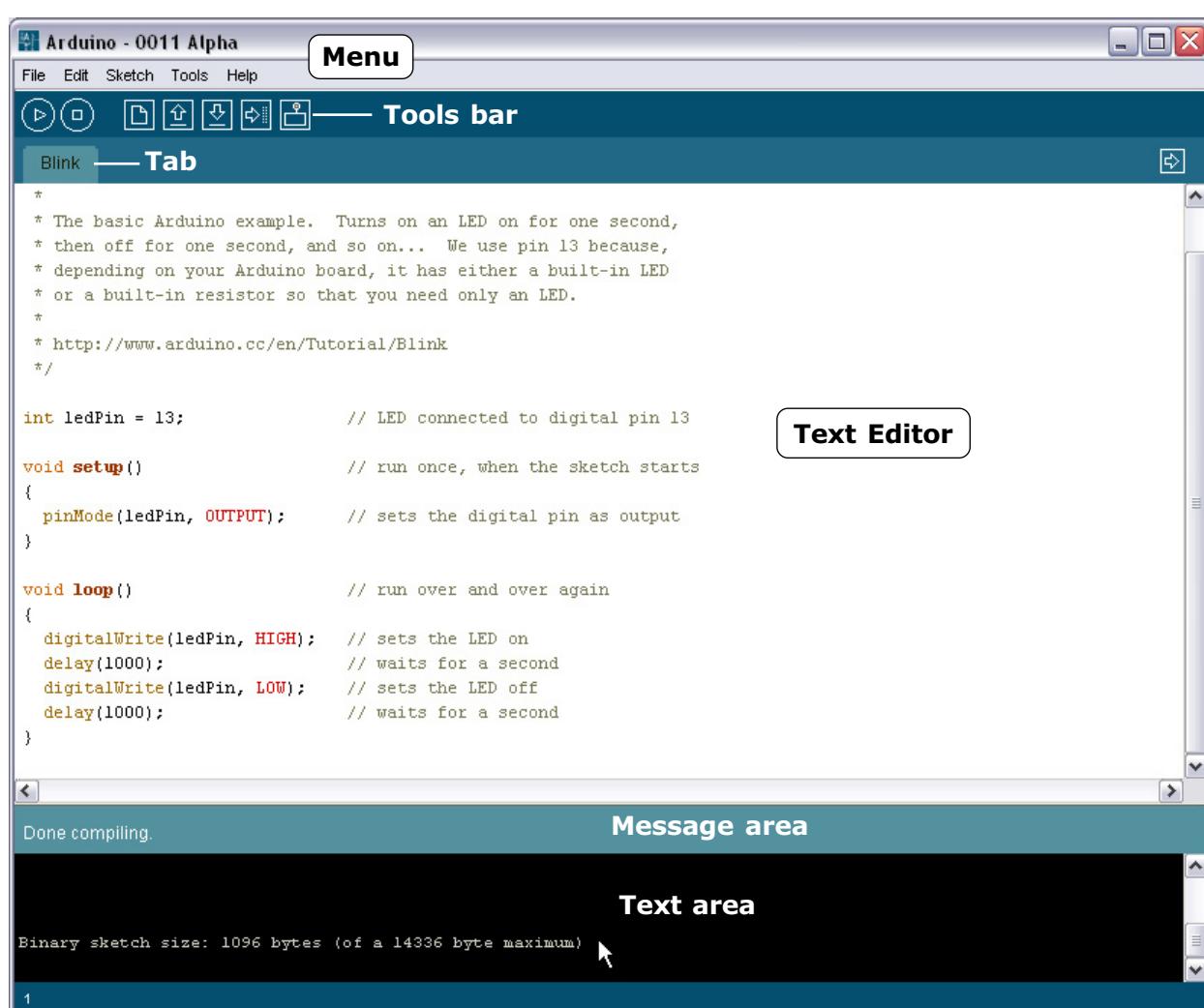


Figure 3-1 Arduino environment

3.3 Menu bar

3.3.1 File

The Arduino calls the code as **Sketch**. This menu contains many commands like open, save and close the sketch as follows :

- **New** : Creates a new sketch, named is the current date format "sketch_YYMMDDa".
- **Sketchbook**
 - **Open** : Open the exist sketch.
 - **Example** : Open the example sketch.
- **Save** : Save the current sketch
- **Save as** : Save the current sketch as another name.
- **Upload to I/O board** : Uploads your code to the Arduino I/O board (POP-168 module). Make sure to save or verify your sketch before uploading it.
- **Preference** : Set some preference of Arduino environment
- **Quit** : Exit the Arduino IDE

3.3.2 Edit

The Edit menu provides a series of commands for editing the Arduino files.

- **Undo** : Reverses the last command or the last entry typed.
- **Redo** : Reverses the action of the last Undo command. This option is only available, if there has already been an Undo action.
- **Cut** : Removes and copies selected text to the clipboard.
- **Copy** : Copies selected text to the clipboard.
- **Paste** : Inserts the contents of the clipboard at the location of the cursor, and replaces any selected text.
- **Select All** : Selects all of the text in the file which is currently open in the text editor.
- **Find** : Finds an occurrence of a text string within the file open in the text editor and gives the option to replace it with a different text.
- **Find Next** : Finds the next occurrence of a text string within the file open in the text editor.

3.3.3 Sketch

This menu provides a series of commands for compile the code and manage library.

- **Verify/Compile** : Verify and compiles the code
- **Stop** : Stops current activity.
- **Add file** : Opens a file navigator. Select a code files to add it to the sketches "data" directory.
- **Import Library** : Import the addition library.
- **Show Sketch folder** : Opens the directory for the current sketch.

3.3.4 Tools

This menu provides commands about tools for developing the Arduino sketch and setting up the Arduino hardware.

- **Auto Format** : Attempts to format the code into a more human-readable layout. Auto Format was previously called Beautify.
- **Archive Sketch** : Compress the current sketch to the zip file.
- **Export Folder** : Open the folder that contain the current sketch.
- **Board** : Choose the Arduino hardware. For POP-BOT, choose **POP-168** or **Arduino Mini**
- **Serial Port** : Allows to select which serial port to use as default for uploading code to the Arduino I/O Board or monitor data coming from it. The data coming from the Arduino I/O Board is printed in character format in the text area region of the console.

3.3.5 Help

This menu contains many information in HTML format for supporting the Arduino user.

- **Getting Start** : Opens the How to start Arduino.
- **Troubleshooting** : Suggest the solution when meet the problem in Arduino.
- **Environment** : Describe about Arduino environments
- **Reference** : Opens the reference in the default Web browser. Includes reference for the language, programming environment, libraries, and a language comparison.
- **Frequently Asked Question** : See the popular question and answer about Arduino.
- **Visit www.arduino.cc** : Opens default Web browser to the Arduino homepage.
- **About Arduino** : Opens a concise information panel about the software.

3.4 Tools bar



Verify/Compile : Checks your code for errors.



Stop : Stops the serial monitor, or unhighlight other buttons.



New : Creates a new sketch.



Open : Presents a menu of all the sketches in your sketchbook.



Save : Saves your sketch.



Upload to I/O Board : Uploads your code to the Arduino I/O board (POP-168 module). Make sure to save or verify your sketch before uploading it.



Serial Monitor : Displays serial data being sent from the Arduino board (USB or serial board). To send data to the board, enter text and click on the "send" button or press enter. Choose the baud rate from the drop-down that matches the rate passed to **Serial.begin** in your sketch. Note that on Mac or Linux, the Arduino board will reset (rerun your sketch from the beginning) when you connect with the serial monitor.

3.5 Arduino programming reference notice

This activity book will not describe about Arduino programming. You can read and make the understanding about Arduino syntax and programming reference from Help menu or learn from Arduino website at www.arduino.cc.

Addition, you can learn from 40-pages of **Arduino Programming Notebook**. Also download rom Arduino website in *Playground* page.



4 : POP-BOT program development by Arduino

The POP-BOT program development can summarize as the diagram following the figure 4-1.

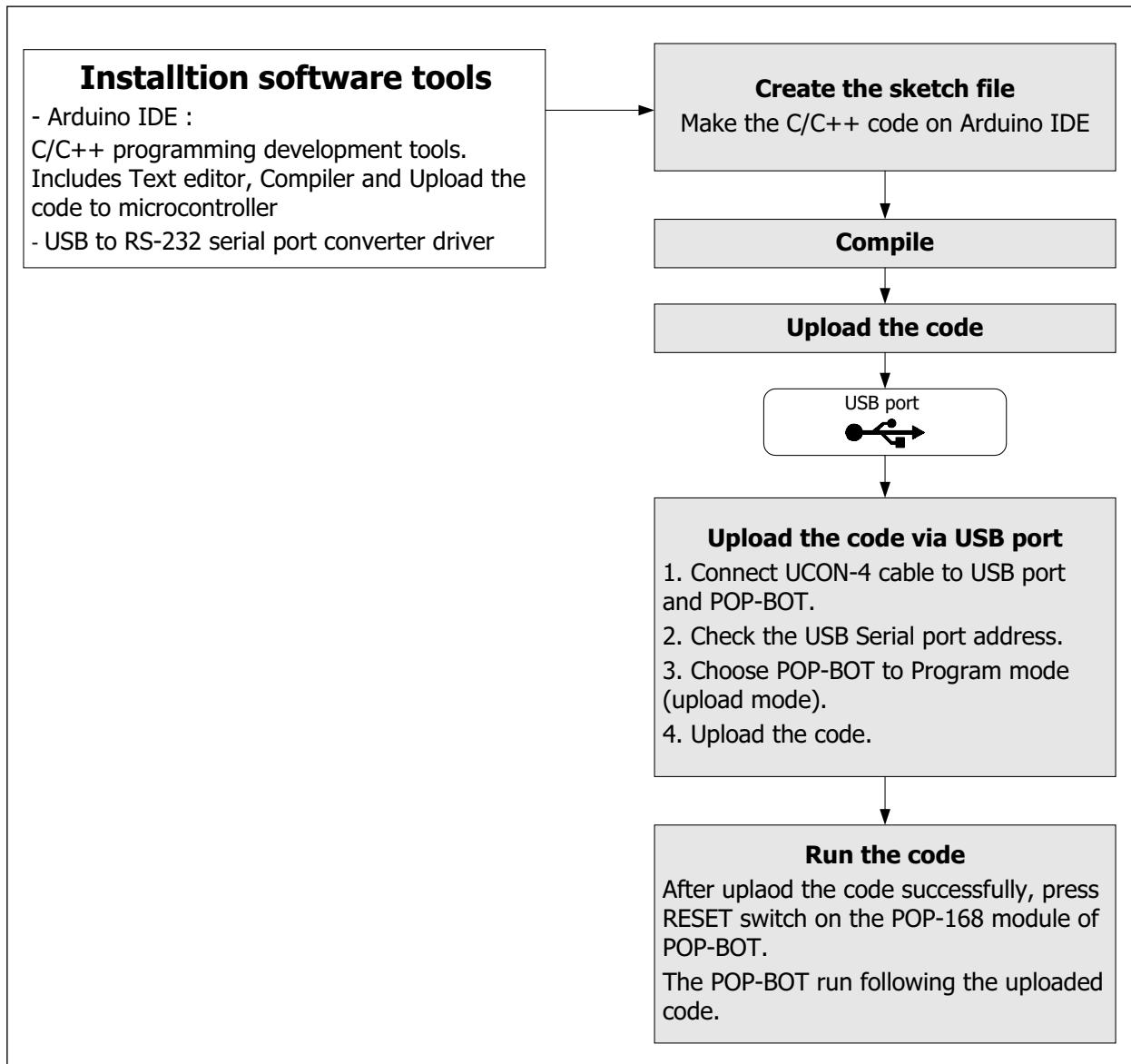


Figure 4-1 Programming development diagram of POP-BOT by using Arduino IDE

4.1 Preparing the UCON-4; USB to RS-232 serial port converter cable

The POP-BOT requires computer interface and Arduino for uploading the code. Normally use RS-232 serial port or COM port. For modern computer provide the main interface port as USB. Therefore the USB to RS-232serial port converter is required. In the POP-BOT kit prepares the UCON-4 cable for this purpose.

Before using the UCON-4 cable, you must install the suitable driver and check some configuration.

4.1.1 Driver installation

Double click at USBDriverInstallerV2.0.0.exe file from POP-BOT bundled CD-ROM to start the driver instalation. The installation dialogue-box will appear below.

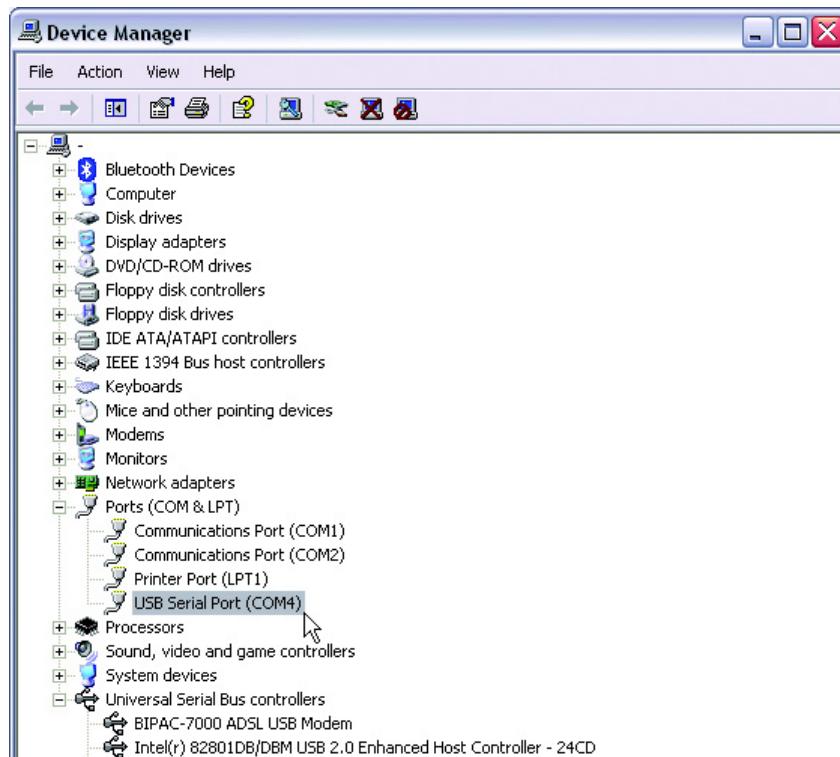


4.1.2 Check the USB serial port address

- (1) Plug the USB cable to USB port and POP-BOT controller board. Wait a moment.
- (2) Check the Virtual COM port or USB Serial port address by clicking Start → Control Panel → System → Hardware → Device Manager



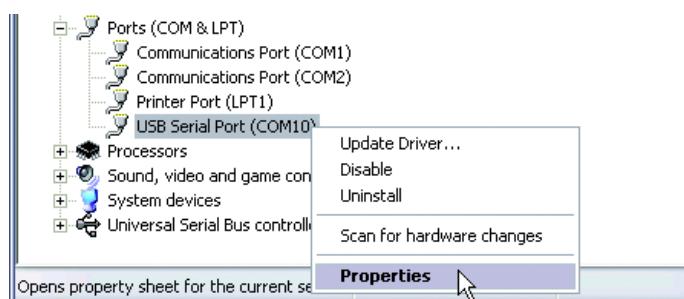
(3) See the list of USB serial port and remember the COM port address to work with UCON-4 cable. Normally it will create COM3 or above. In this example is **COM4**



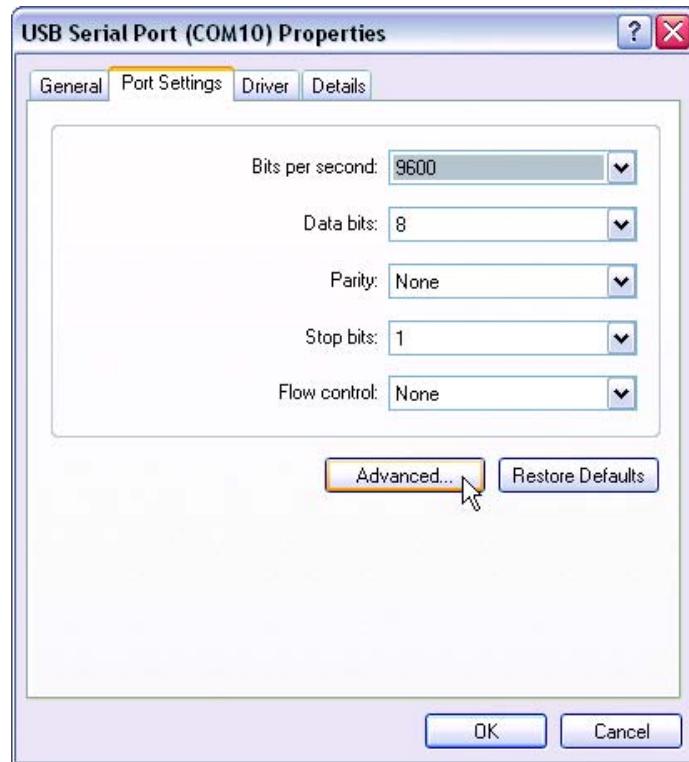
4.1.3 UCON-4 cable with Arduino operation notice

Normally Arduino software can interface with COM port not higher than COM9. Thus, user must make sure the USB serial port address not higher than COM9. If higher, please do following procedure.

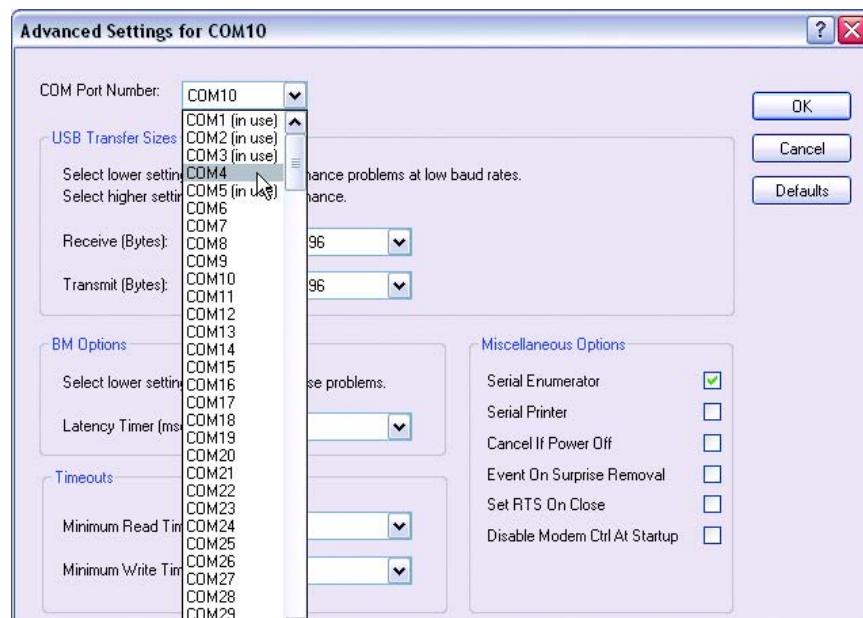
- (1) Connect the UCON-4 cable to Computer USB port.
- (2) Check the COM port address by clicking at **Start → Control Panel → System**
- (3) Select the **Hardware** tab and click on the **Device Manager** button.
- (4) Check the hardware listing. At the Port listing, you will found **USB Serial port (COM x)**. If COM port is higher than COM9 (this example is COM10), please click on the right-button mouse and select to **Properties**



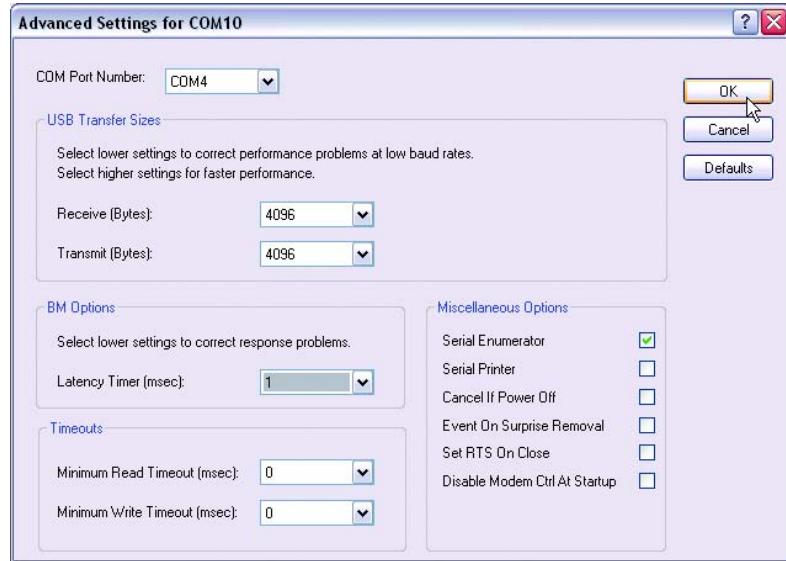
(5) The **USB Serial Port (COM10) Properties** window will appear. Select the **Port Setting** tab and set all value following the figure below and click on the **Advance** button



(6) The Advanced Setting for COM10 will appear. Click on the **COM Port Number** box to change to **COM4** or another port in range **COM1** to **COM9**.



(7) Set the value following the figure below. Especially at the **Latency Timer (msec)** suggested to set to 1 and check the box at **Serial Enumerator**. Click **OK** button.



(8) Go back to the USB Serial Port Properties. Now the *COM port number at the title bar* will change to **COM4**. Click on the **OK** button.

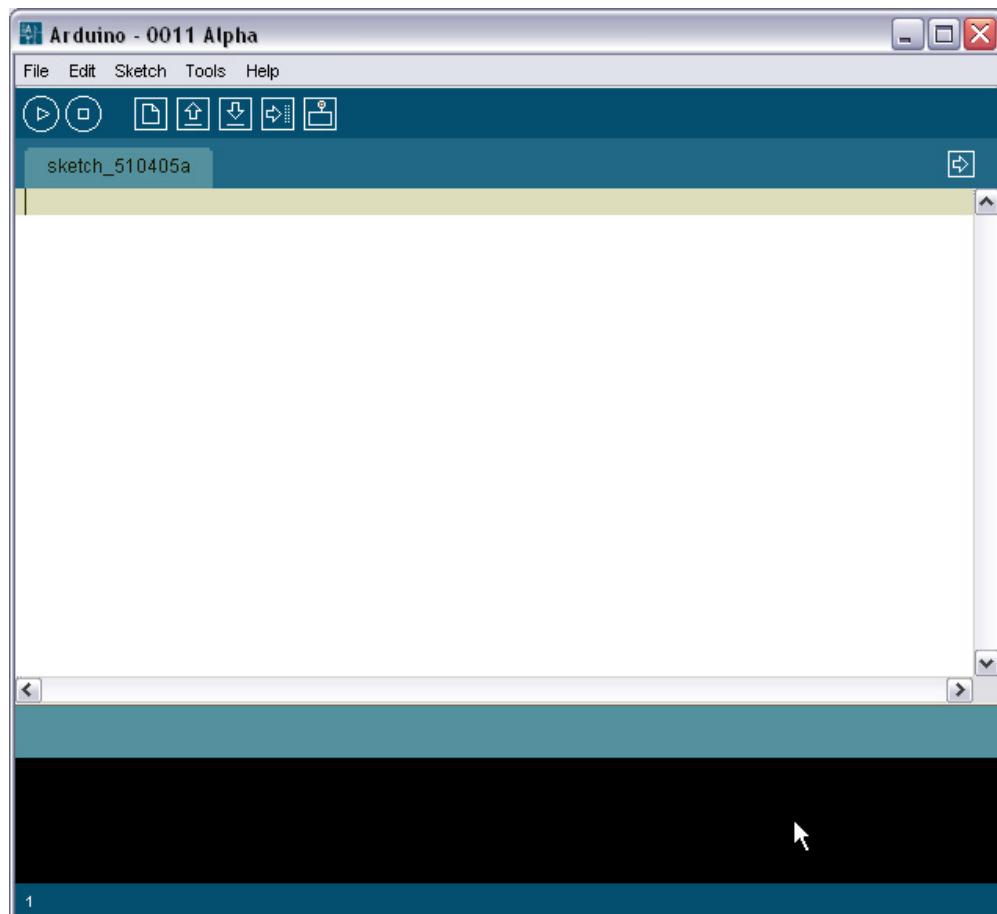


(9) Remove the UCON-4 cable from USB port and re-plug again. Check the USB Serial port address. The new address must be **COM4**. Now the UCON-4 cable ready for using with Arduino IDE software.

4.2 Getting start POP-BOT with Arduino

Run Arduino IDE by clickng the **Start → All Programs → POP-168 Software Package → Arduino**

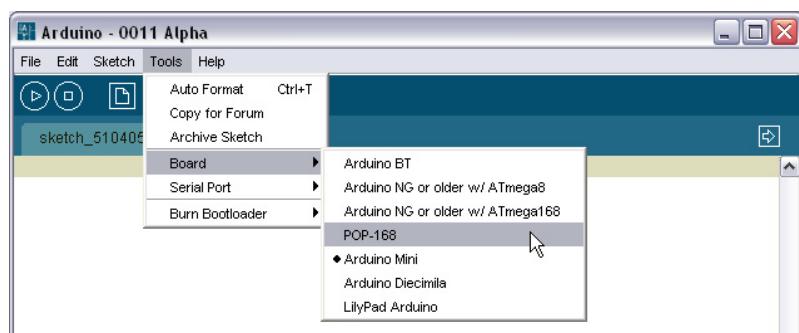
The first launch of Arduino show the screen below.



4.2.1 ARduino POP-168 hardware configuration

4.2.1.1 Select microcontroller chip

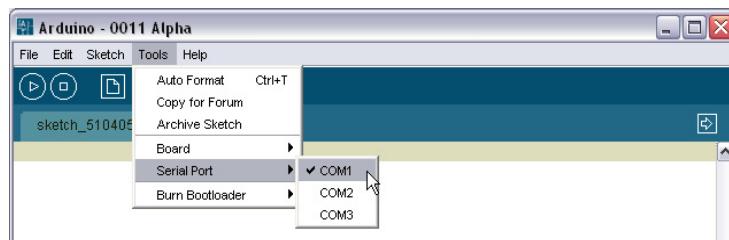
Select the menu **Tools → Board → POP-168 or Arduino Mini** (can use both versions)



4.2.1.2 Select the COM port

Uploading the sketch from Arduino IDE to POP-168 module requires serial port communication. It can work with virtual COM port that created from USB to Serial port converter.

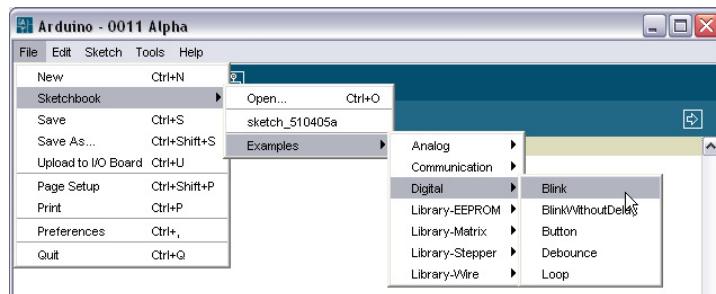
Select menu **Tools** → **Serial Port**. You can select the target COM port.



Normally on-board serial port will be COM1 or COM2. For USB Serial port address will be COM3 or higher. But Arduinoi can support COM port not higher COM9.

4.2.2 Open the example sketch file

Select menu **File** → **Sketchbook** → **Examples** → **Digital** → **Blink**



The example code; `Blink.pde` will appear on the text editor area.

```

/*
 * Blink
 *
 * The basic Arduino example. Turns on an LED on for one second,
 * then off for one second, and so on... We use pin 13 because,
 * depending on your Arduino board, it has either a built-in LED
 * or a built-in resistor so that you need only an LED.
 *
 * http://www.arduino.cc/en/Tutorial/Blink
 */

int ledPin = 13;           // LED connected to digital pin 13

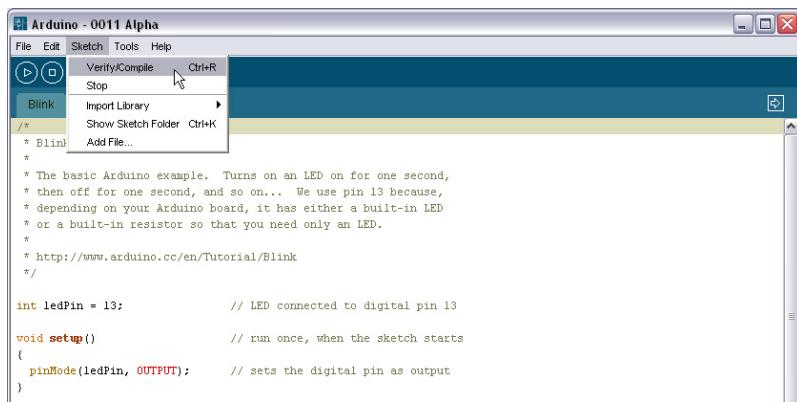
void setup()               // run once, when the sketch starts
{
  pinMode(ledPin, OUTPUT); // sets the digital pin as output
}

void loop()                // run over and over again
{
  digitalWrite(ledPin, HIGH); // sets the LED on
  delay(1000);              // waits for a second
  digitalWrite(ledPin, LOW); // sets the LED off
  delay(1000);              // waits for a second
}

```

4.2.3 Compile the sketch

After open the sketch file and edit ready, you can compile theis sketch by selecting the menu **Sketch → Verify/Compile** or click on the button 



```

Arduino - 0011 Alpha
File Edit Sketch Tools Help
(Blink) Verify/Compile Ctrl+R
Stop Import Library
Show Sketch Folder Ctrl+K
Blink Add File...
/*
 * The basic Arduino example. Turns on an LED on for one second,
 * then off for one second, and so on... We use pin 13 because,
 * depending on your Arduino board, it has either a built-in LED
 * or a built-in resistor so that you need only an LED.
 *
 * http://www.arduino.cc/en/Tutorial/Blink
 */
int ledPin = 13; // LED connected to digital pin 13
void setup() // run once, when the sketch starts
{
  pinMode(ledPin, OUTPUT); // sets the digital pin as output
}

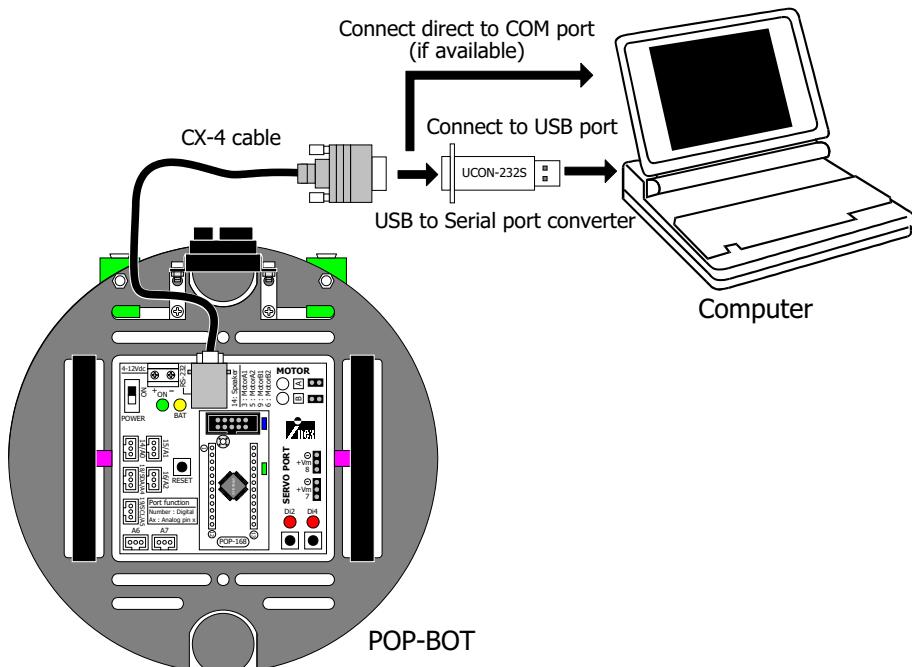
```

The status bar at the bottom of main screen will display the compilation status. If compile no error, it reports **Done compiling** and the Text area will display message of binary sketch size.

4.2.4 Uploading the sketch to POP-168 module

Downloading the machine code from compiling to Arduino hardware is called Uploading. You must prepare the Aruino hardware ready for uploading by setting the POP-168 to Bootloader mode. The procedure is :

- (1) Connect the POP-BOT with your computer COM port by CX-4 cable or via USB to Serial port converter.



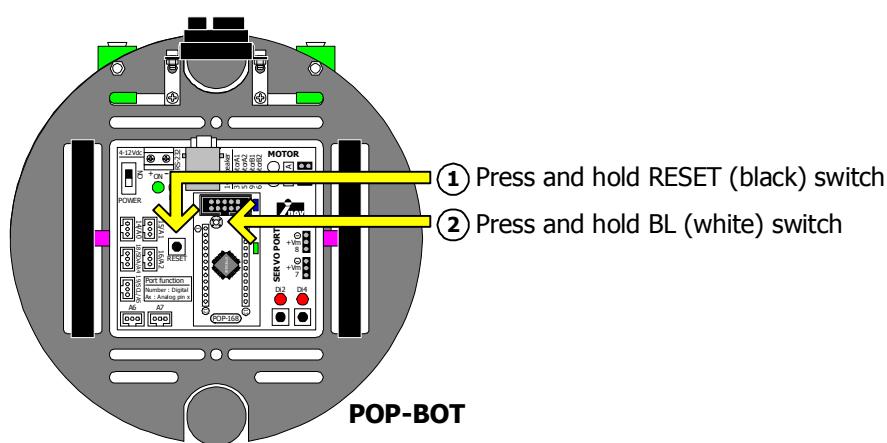
(2) Set POP-168 module to program mode. It has 2 options.

(2.1) Use RESET switch on RBX-168 board and BL switch on POP-168 module

(2.1.1) Turn on POP-BOT

(2.1.2) Press and hold RESET switch on the RBX-168 controller board.

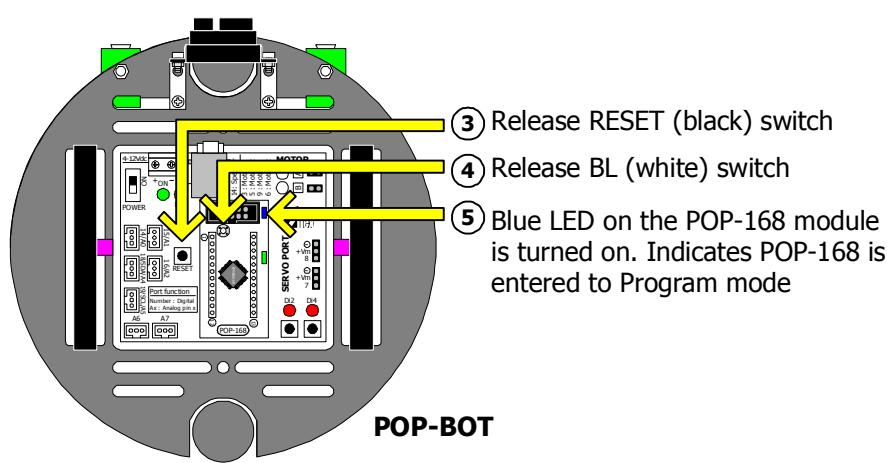
(2.1.3) Press and hold BL switch on the POP-168 module.



(2.1.4) Release the RESET switch.

(2.1.5) Release the BL switch following.

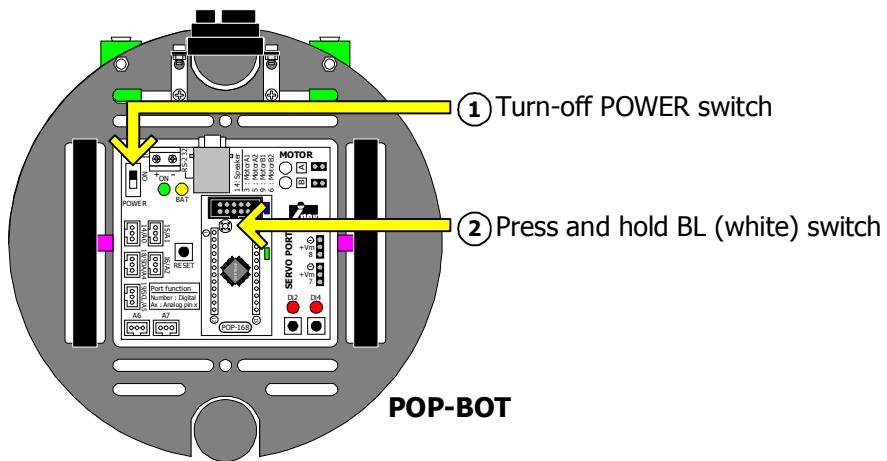
If Blue LED on POP-168 is turned on and not blink, then POP-168 had entered Bootloader mode and ready to uploaded.



(2.2) Use POWER T switch on RBX-168 board and BL switch on POP-168 module

(2.2.1) Turn off the POP-BOT.

(2.2.2) Press and hold BL switch.



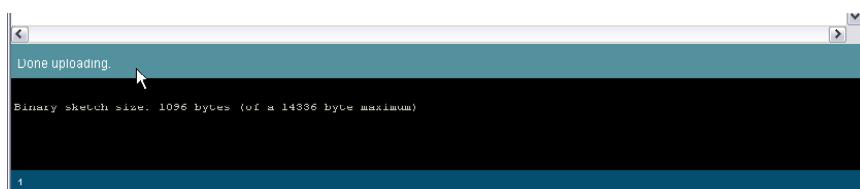
(2.2.3) Turn-on the POWER switch

(2.2.4) Release the BL switch

If Blue LED on POP-168 is turned on and not blink, then POP-168 had entered Bootloader mode and ready to uploaded.

(3) At Arduino IDE, select menu **File → Upload to I/O Board**. Wait for uploading.

(4) When uploading complete, the status bar at the bottom of main screen will display message **Done Uploading**.



(5) After the uploading is finished, press RESET switch again. The sketch will run on the POP-BOT.

The LED at D13 (Blue LED) on the POP-168 module blinks 1 second rate.

5 : POP-BOT movement activities

The POP-BOT has 2 channels of DC motor drivers. You can control the speed and direction of DC motor rotation with software. Because DC motor is driven by PWM (Pulse width modulation) signal. In this section describe how to drive DC motor with PWM and how to generate PWM signal of Arduino POP-168 microcontroller in C programming.

5.1 Basic operation of driving DC motor with PWM

By changing (modulating) the width of the pulse applied to the DC motor we can increase or decrease the amount of power provided to the motor, thereby increasing or decreasing the motor speed. Notice that, although the voltage has a fixed amplitude, it has a variable duty cycle. That means the wider the pulse, the higher the speed.

Refer Figure 5-1, the Vs supplies PWM signal to DC motor. The speed is dependent on Ton time (ON time of motor). At this time, DC motor will receive the full voltage; Vm. If Ton's width is more, DC motor is received more voltage. It rotate in high speed. The ratio of Ton time in percentage with period (T) is called Duty cycle. You can calculate this as follows :

$$\% \text{ duty cycle} = 100 \times \frac{T_{on}}{T_{on} + T_{off}} \quad \dots \dots \dots \quad (5.1)$$

$$\text{Average DC motor voltage drop} = \text{Supply voltage} \times \text{duty cycle (\%)} \quad \dots \quad (5.3)$$

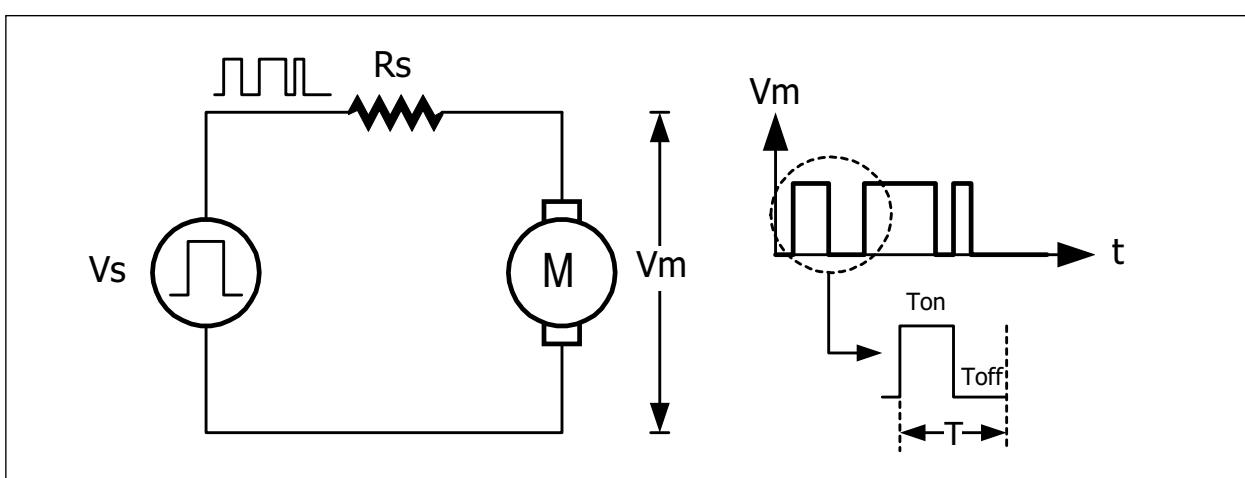


Figure 5-1 : The PWM signal for driving DC motor

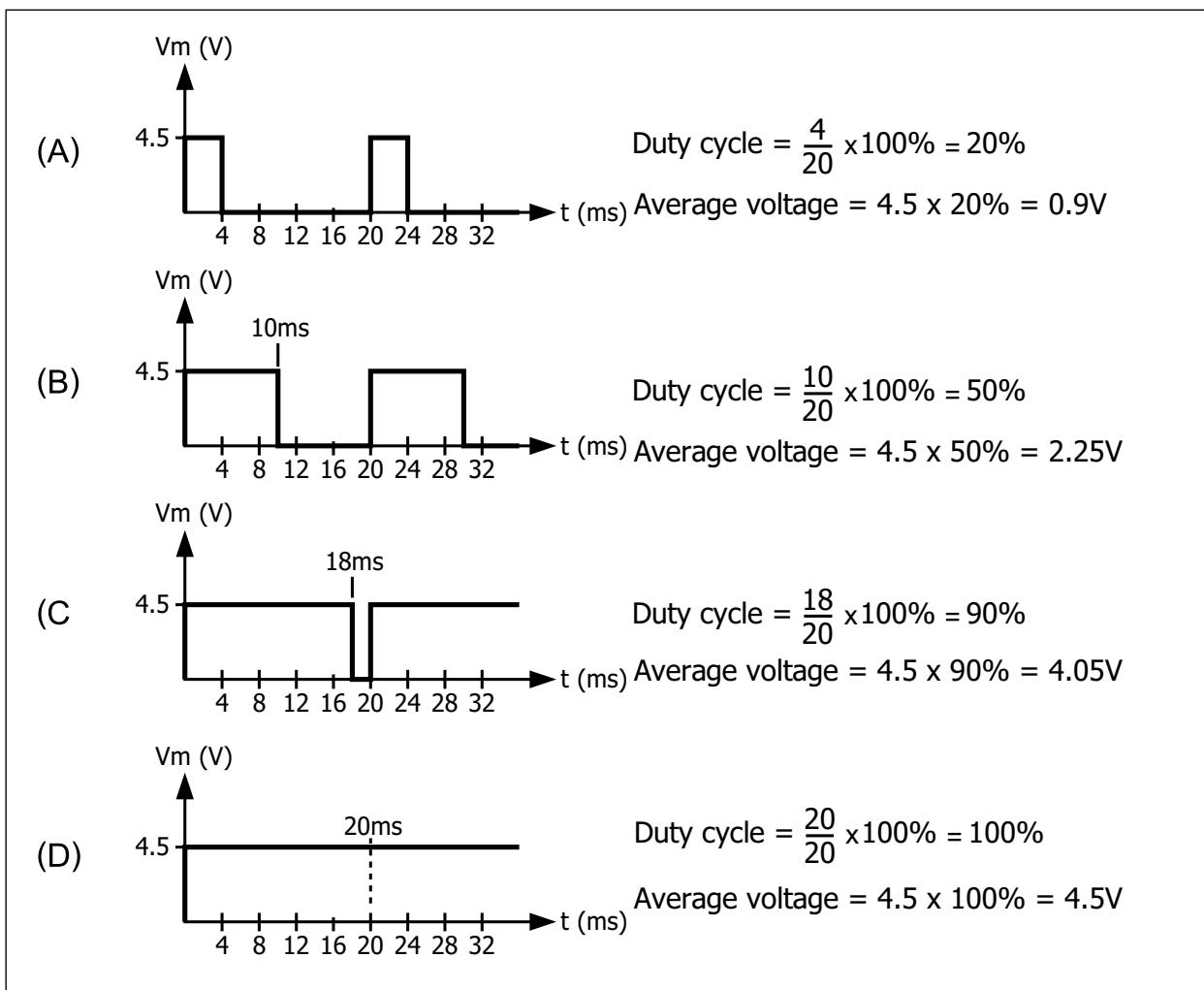


Figure 5-2 : Shows the relation between the different duty cycle and voltage accross the DC motor.

Although the duty cycle is determine the motor speed. But DC motor can operate at limit frequency. If the PWM frequency is over the limit, DC motor will stop because its operation reach to saturation point. The example PWM signal in figure 5-2 has 20 milliseconds period and 50Hz frequency.

In Figure 5-2 (A) the PWM duty cycle is 20%. Motor will rotate with lowest speed because the voltage drop is only 0.9V. When increase the duty cycle in Figure 5-2 (B) and (C), voltage is applied to DC motor increase. Its speed is increase too.

In Figure 5-2 (D) the voltage is applied to DC motor full level because duty cycle is 100%. Thus, controlling the PWM duty cycle is a method of motor speed control.

5.2 Arduino with PWM

Arduino has a special function to generate PWM signal and outs to any digital pins. It is `analogWrite()`. User can adjust PWM duty cycle from 0 to 100% with value between 0 to 255.

At value = 0, no PWM signal is occurred. Voltage output as 0V.

At value = 51, The PWM signal has positive pulse width 20% of period. The duty cycle is equal to 20%.

At value = 127, The PWM signal has positive pulse width half of period. The duty cycle is equal to 50%.

At value = 191, The PWM signal has positive pulse width 75% of period. The duty cycle is equal to 75%.

At value = 255, The PWM signal has full positive pulse width. The duty cycle is equal to 100%.

The figure 5-2 shows the PWM signal at any duty cycle.

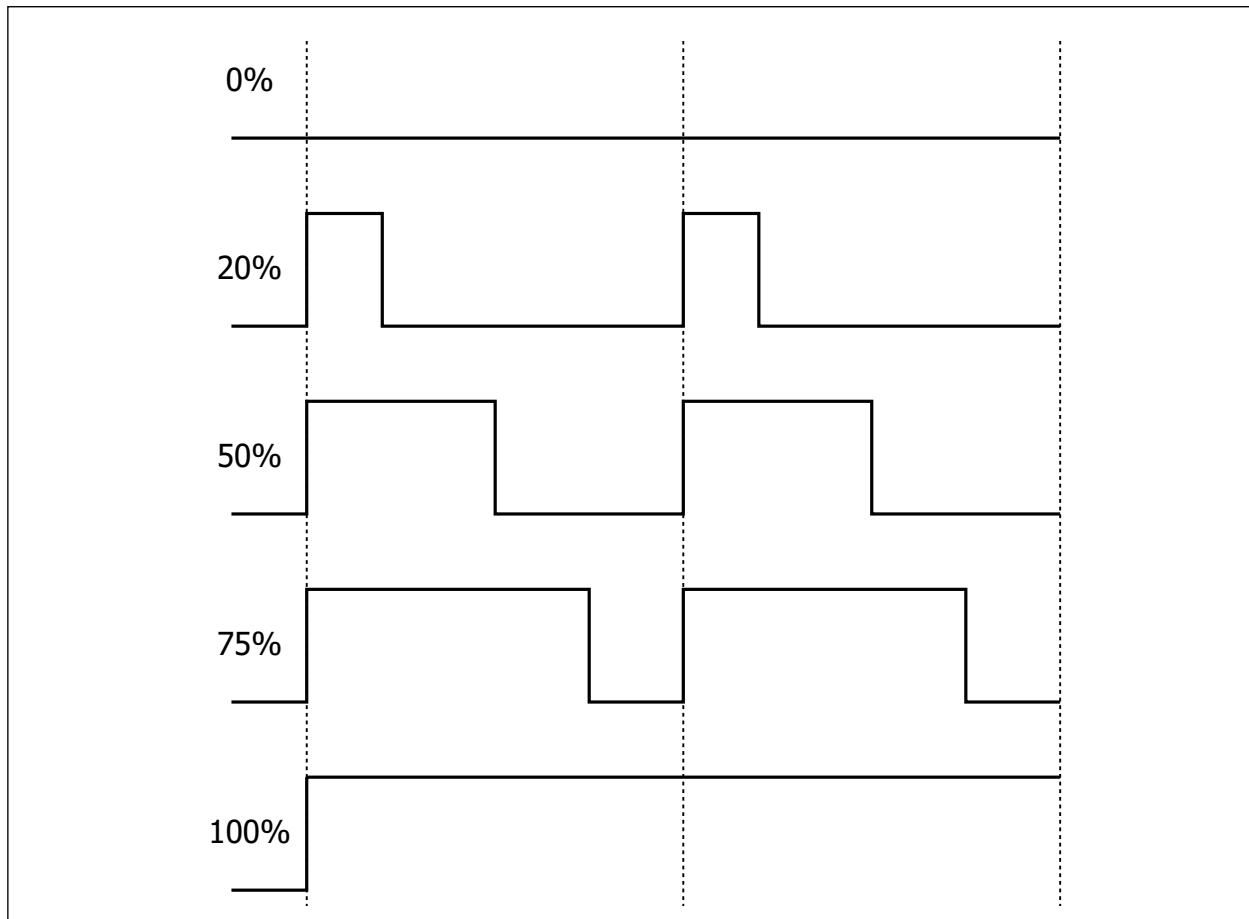


Figure 5-2 shows the PWM signal at any duty cycle.

Output voltage of PWM signal is average value relate the duty cycle. You can calculate from this relation below :

$$\text{Outout_voltage} = (\text{on_time} / \text{off_time}) * \text{max_voltage}$$

We can use the PWM signal from analogWrite() function to adjust the LED brightness or amplify to drive the DC motor. The Arduino's pin that assigned to PWM output will output the PWM continue until do the analogWrite() function in new period or execute digitalWrite and digitalRead funtion at same pin.

Arduino POP-168 module has 4 analog output pins; it includes pin 3, 5, 6 and 9 (D13, D15, D16 and D19).

The analogWrite function format is

analogWrite(pin,value);

Thus; *pin* as The Arduino's port pin 3, 5, 6 and 9

value as Duty cycle value 0 to 255.

Activity 1 : POP-BOT basic movement

Activity 1-1 Forward and Backward movement

A1.1 Open the Arduino IDE and create the sketch code from Listing A1-1.

A1.2 Set the POP-BOT into Program mode. Upload the sketch to the robot.

A1.3 Turn-off power and Remove the download cable.

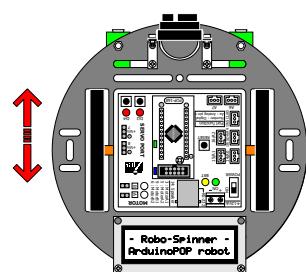
A1.4 Make sure the robot is on a flat surface. Turn-on the power and observe the operation.

The POP-BOT moves forward. See both LED motor indicators light in green color.

After 1 second, both indicators change color to red and the robot moves backward.

If this is incorrect you will need to re-connect the motor cable to its opposite port / polarity. Do this until your robot moves correctly. Once its done, Use this motor port configuration for all your programming activities from now on. The robot will move forward and backward continually until you turn off its power.

```
/*
 * POP-BOT V1.0
 * Running Forward/Backward Full Speed
 */
void setup() {
    pinMode(3,OUTPUT);           // Motor A1
    pinMode(5,OUTPUT);           // Motor A2
    pinMode(6,OUTPUT);           // Motor B2
    pinMode(9,OUTPUT);           // Motor B1
}
void Forward(){                  // Robo-Spinner Go Forward Routine
    digitalWrite(3,HIGH);
    digitalWrite(5,LOW);
    digitalWrite(6,HIGH);
    digitalWrite(9,LOW);
}
void Backward(){                 // Robo-Spinner Go Backward Routine
    digitalWrite(3,LOW);
    digitalWrite(5,HIGH);
    digitalWrite(6,LOW);
    digitalWrite(9,HIGH);
}
void loop(){
    Forward();
    delay(1000);
    Backward();
    delay(1000);
}
```



Listing A1-1 : Forward_Backward.pde file; the Arduino sketch file for driving POP-BOT to forward and backward direction.

Activity 1-2 Circle-shape movement control

With setting the different speed for each motor, it cause the robot move in circle-shape. You can try with this procedure as follows :

A1.5 Create a new sketch file and write the following C Codes shown in Listing A1-2.

A1.6 Set the POP-BOT into Program mode. Upload the sketch to the robot.

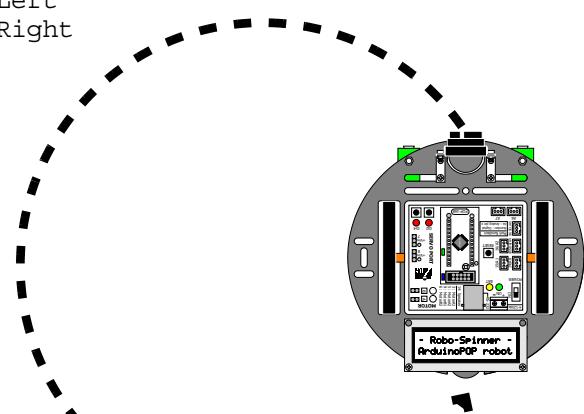
A1.7 Turn-off power and Remove the download cable.

A1.8 Make sure the robot is on a flat surface. Turn-on the power and observe the robot.

The robot moves with circle-shape continually until you press the button switch at Di4 pin of POP-BOT controller board to stop the robot movement.

```
/*
 * POP-BOT V1.0
 * Filename : MotorSpeedControl.pde
 * Left Motor Lowspeed and Right Motor Highspeed Robo-Spinner Run in Circle
 */
void setup() {
    pinMode(3,OUTPUT);          // Motor A1
    pinMode(5,OUTPUT);          // Motor A2
    pinMode(6,OUTPUT);          // Motor B2
    pinMode(9,OUTPUT);          // Motor B1
    pinMode(2,INPUT);           // Switch Left
    pinMode(4,INPUT);           // Switch Right
}
void Forward(int Lspeed,int Rspeed) {
    analogWrite(3,Lspeed);
    digitalWrite(5,LOW);
    analogWrite(6,Rspeed);
    digitalWrite(9,LOW);
}
void Motor_Stop(){
    digitalWrite(5,LOW);
    digitalWrite(3,LOW);
    digitalWrite(6,LOW);
    digitalWrite(9,LOW);
}
void loop(){
    Forward(80,255);          // Circle running
    if(digitalRead(4)==0){      // if Switch Press
        Motor_Stop();          // Stop
        while(1);
    }
}
/*

```



Listing A1-2 : MotorSpeedControl.pde file; the Arduino sketch file for circle movement of POP-BOT

Activity 1-3 Square-shape movement control

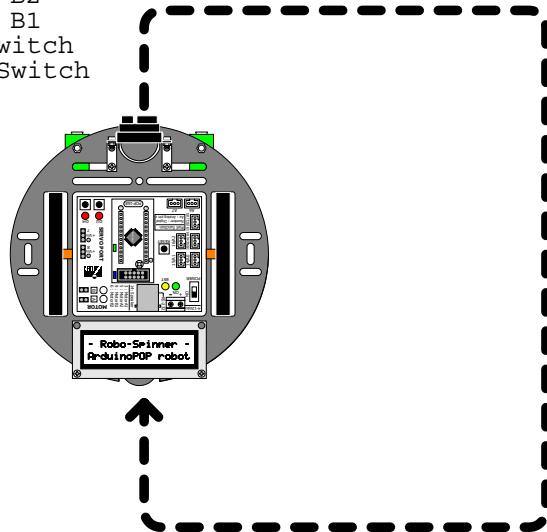
A1.9 Create a new sketch file and write the following C Codes shown in Listing A1-3.

A1.10 Upload the sketch to the robot. Turn-off power and Remove the download cable.

A1.11 Turn-on the power and observe the robot.

The robot will be activated if SW1 or SW2 is being pressed. If you Press SW1, the robot will move forward and turn left continually, making a square. If you press SW2, the operation is vice versa.

```
*****
* Robo-Spinner V1.0
* Filename : Rectangle_Running.pde
* Running 90 Degree Turnleft And Turnright
*****
void setup() {
    pinMode(3,OUTPUT);           // Motor A1
    pinMode(5,OUTPUT);           // Motor A2
    pinMode(6,OUTPUT);           // Motor B2
    pinMode(9,OUTPUT);           // Motor B1
    pinMode(2,INPUT);            // LeftSwitch
    pinMode(4,INPUT);            // RightSwitch
}
void Forward(int speed){
    analogWrite(3,speed);
    digitalWrite(5,LOW);
    analogWrite(6,speed);
    digitalWrite(9,LOW);
}
void Spin_Left(int speed){
    analogWrite(5,speed);
    digitalWrite(3,LOW);
    analogWrite(6,speed);
    digitalWrite(9,LOW);
}
void Spin_Right(int speed){
    analogWrite(3,speed);
    digitalWrite(5,LOW);
    analogWrite(9,speed);
    digitalWrite(6,LOW);
}
void loop(){
    if (digitalRead(2)==0){      // Switch Di2 Press
        while(1){
            Forward(125);
            delay(900);
            Spin_Left(125);
            delay(400);
        }
    }
    if (digitalRead(4)==0){      // Switch Di4 Press
        while(1){
            Forward(125);
            delay(900);
            Spin_Right(125);
            delay(400);
        }
    }
}
```



Listing A1-3 : Rectangle_Running.pde file; the Arduino sketch file for square-shape movement



Activity 2 : POP-BOT Bumper

Activity 2-1 Simple collision detection

This activity is program the robot to detect the collision of both switches at the front of the POP-BOT robot. After a collision is encountered, the robot will move backward and change the its direction of movement.

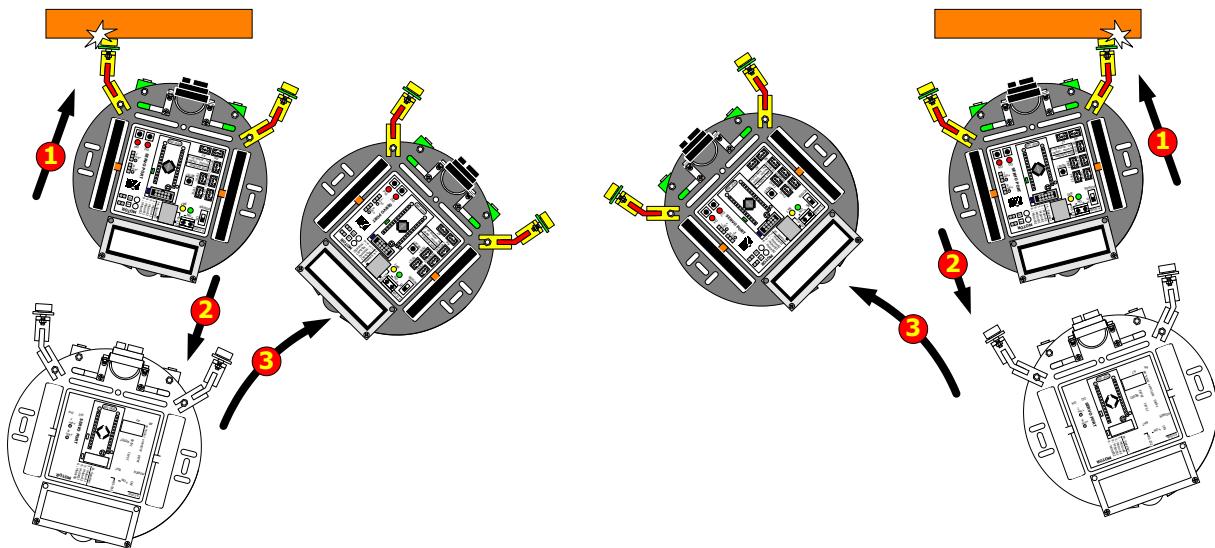
- A2.1 Open the Arduino IDE and create the sketch code from Listing A2-1.
- A2.2 Set the POP-BOT into Program mode. Upload the sketch to the robot.
- A2.3 Turn-off power and Remove the download cable.
- A2.4 Prepare the demonstration area by placing and securing boxes or objects on the surface.
- A2.5 Place the robot on the demonstration area. Turn-on the power and observe the robot.

The POP-BOT will read both switch status from **15/A1** and **17/A3** port. If any switch is pressed or touches some object, the result is logic **10**.

In a normal operation, the robot will move forward continually.

If the Left Switch module touches any object, the robot will move backward and change its moving direction to its right to avoid the object.

If the Right Switch module touches any object, the robot will move backward and change its moving direction to its left to avoid the object.



Robot attacks the object in the left.

Robot attacks the object in the right.

```

/*********************  

* POP-BOT V1.0  

* Filename : BumperRobot.pde  

* POP-BOT with bumper sensor  

*****  

void setup() {  

    pinMode(3,OUTPUT); // Motor A1  

    pinMode(5,OUTPUT); // Motor A2  

    pinMode(6,OUTPUT); // Motor B2  

    pinMode(9,OUTPUT); // Motor B1  

    pinMode(15,INPUT); // Left Switch  

    pinMode(17,INPUT); // Right Switch  

}  

void loop(){  

    Forward(150);  

    if (digitalRead(15)==0){ // Test Bumper Switch From Left  

        Backward(150);delay(500);  

        Spin_Right(200);delay(400);  

    }  

    if (digitalRead(17)==0){ // Test Bumper Switch From Right  

        Backward(150);delay(400);  

        Spin_Left(200);delay(400);  

    }  

}  

*****  

void Forward(int speed){  

    analogWrite(3,speed);  

    digitalWrite(5,LOW);  

    analogWrite(6,speed);  

    digitalWrite(9,LOW);  

}  

void Backward(int speed){  

    analogWrite(5,speed);  

    digitalWrite(3,LOW);  

    analogWrite(9,speed);  

    digitalWrite(6,LOW);  

}  

void Spin_Left(int speed){  

    analogWrite(5,speed);  

    digitalWrite(3,LOW);  

    analogWrite(6,speed);  

    digitalWrite(9,LOW);  

}  

void Spin_Right(int speed){  

    analogWrite(3,speed);  

    digitalWrite(5,LOW);  

    analogWrite(9,speed);  

    digitalWrite(6,LOW);  

}  

*****  


```

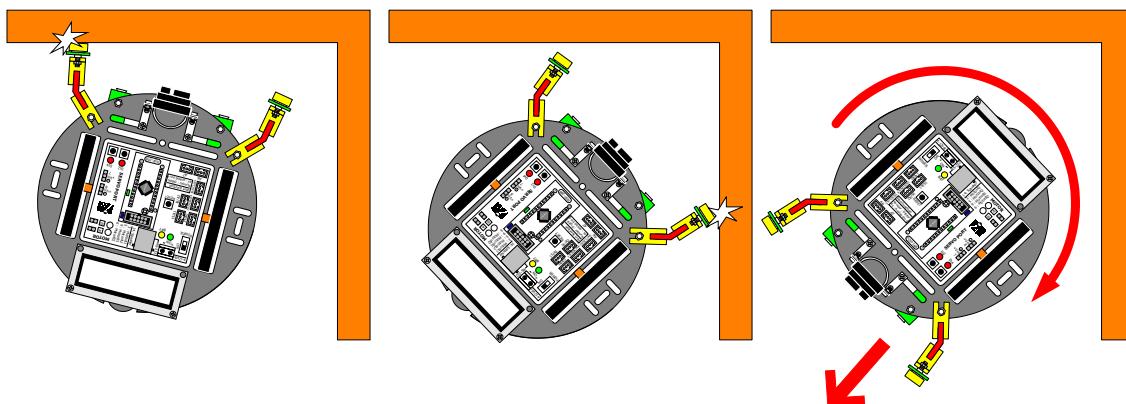
Listing A2-1 : BumperRobot.pde file; the Arduino sketch file for POP-BOT Bumper activity.

Activity 2-2 Trapped in a corner situation

When the POP-BOT is in a corner, it is caught in between whereby to the left or right is a wall. This causes continuous hitting of the walls and thus trapping the robot in this corner. The solution is to modify your exiting C Code from Listing A2-1 to that which is shown in Listing A2-2.

- A2.6 Open the Arduino IDE and create the sketch code from Listing A2-2.
- A2.7 Set the POP-BOT into Program mode. Upload the sketch to the robot.
- A2.8 Turn-off power and Remove the download cable.
- A2.9 Prepare the demonstration area by placing and securing boxes or objects on the surface same in Activity 2-1.
- A2.10 Place the robot on the demonstration area. Turn-on the power and observe the robot.

The robot will move forward and check for collision. If this happens over 5 times consecutively, the robot will spin 180 degrees to change its direction.



```
/*
 * POP-BOT V1.0
 * Filename : CornerEscape.pde
 * Robot escapes from corner
 */
int Count=0;
int Flag_=0;

void setup() {
    pinMode(3,OUTPUT);           // Motor A1
    pinMode(5,OUTPUT);           // Motor A2
    pinMode(6,OUTPUT);           // Motor B2
    pinMode(9,OUTPUT);           // Motor B1

    pinMode(15,INPUT);           // Left Switch
    pinMode(17,INPUT);           // Right Switch
}
void loop(){
    Forward(150);
    if(Count>5)
        Spin();
}
```

```

if (Count>5){                                // Trapped in a corner more than 5 times ?
  Count=0;
  Backward(150);                            // Escape from corner
  delay(2000);
  Spin_Right(200);
  delay(800);
}

if (digitalRead(15)==0){                      // Test left switch
  if(Flag_==1){                             // Check previous state
    Count++;
  }
  else{
    Count=0;
  }
  Flag_=0;
  Backward(150);                          // Normal operate
  delay(500);
  Spin_Right(200);
  delay(400);
}

if (digitalRead(17)==0){                      // Test right switch
  if(Flag_==0){                           // Check previous state
    Count++;
  }
  else{
    Count=0;
  }
  Flag_=1;
  Backward(150);                          // Normal operate
  delay(400);
  Spin_Left(200);
  delay(400);
}

void Forward(int speed){
  analogWrite(3,speed);
  digitalWrite(5,LOW);
  analogWrite(6,speed);
  digitalWrite(9,LOW);
}

void Backward(int speed){
  analogWrite(5,speed);
  digitalWrite(3,LOW);
  analogWrite(9,speed);
  digitalWrite(6,LOW);
}

void Spin_Left(int speed){
  analogWrite(5,speed);
  digitalWrite(3,LOW);
  analogWrite(6,speed);
  digitalWrite(9,LOW);
}

void Spin_Right(int speed){
  analogWrite(3,speed);
  digitalWrite(5,LOW);
  analogWrite(9,speed);
  digitalWrite(6,LOW);
}

```

Listing A2-2 : CornerEscape.pde file; the Arduino sketch file for trapped in a corner solution of POP-BOT



6 : POP-BOT with Serial LCD

The Serial LCD or SLCD16x2 is the 16 characters 2 lines LCD module that communicates by serial interface. It receives data serially and displays on the LCD. Accept serial data at 2400 or 9600 baud rate. Normally LCD interfacing requires at least 6 wires but SLCD16x2 need only one signal wire. This display module is suitable for POP-BOT robot.

6.1 SLCD16x2 information

8.1.1 Features

- Serial Input or Invert/Non-invert TTL/CMOS logic level.
- 1/8 or 1/16 Duty can be selected by jumper.
- Scott Edwards's LCD Serial Backpack™ command compatible addition with Extended Command that make LCD control easier.
- Easy to interface with the microcontroller
- Operation with +5 Vdc supply

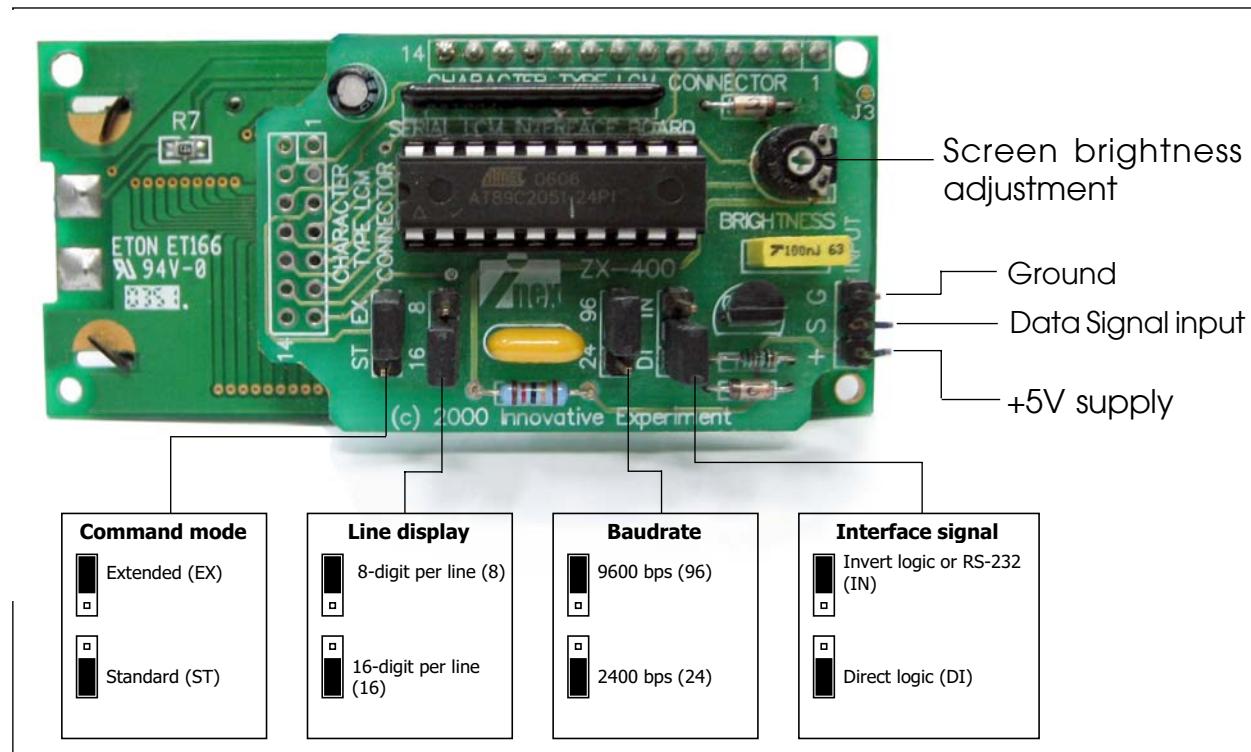


Figure 6-1 Details of SLCD16x2's jumper selections

6.1.2 Setting up

In the figure 6-1, it shows the detail of SLCD16x2 backside. The user will see 4 jumpers configurated as follows :

(1) **Mode command jumper** : Selects the command modes. SLCD16x2 has 2 modes. One is Standard command (ST). This mode compatible with Scott Edwards's LCD Serial Backpack™ . Another mode is Extended mode command (EX). **For POP-BOT activities select Standard command mode (ST).**

(2) **Lines jumper** : Selects the line displays ; 1/8 and 1/16 Duty. 1/8 Duty means displaying 8 digit per line. 1/16 Duty means displaying 16 digit per line or more. Normally set to **1/16**.

(3) **Baudrate select jumper** : 2 selections as 2400 and 9600 bps (bit per second) with 8N1 data format (8-bit data, no parity bit and 1 stop bit). **For POP-BOT set to 9600**

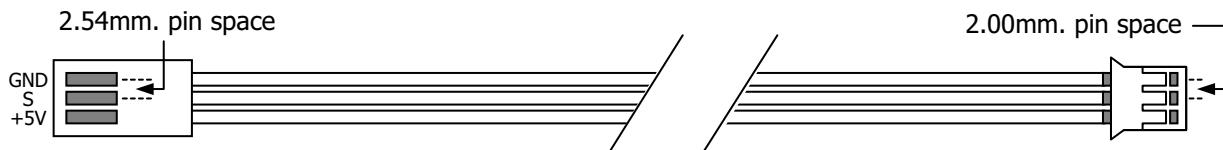
(4) **Interface signal jumper** : 2 selections as Invert logic TTL/CMOS level (IN) and Direct logic TTL/CMOS level (DI). **For POP-BOT set to DI**

SLCD16x2 provides a brightness adjustment with variable resistor at **BRIGHTNESS** position.

Interfacing connector has 3 pins : +5V Supply voltage (+), Serial data input (S) and Ground (G).

6.1.3 Interfacing SLCD16x2 with POP-BOT

The JST3AA-8 cable is required for connecting between SLCD with POP-BOT controller board. This cable wire assignment can show below.



The JST3AA-8 cable has the both ends as 2.00mm. housing. It will be connect to JST connector of any port of POP-BOT controller board and the input connector of SLCD16x2

After connecting, set all jumpers as follows :

- í Select command mode to Standard (ST).
- í Select the lines display to 16-digit per line (16).
- í Select baudrate to 9600 bps (96).
- í Select the interface signal to Direct (DI).

6.1.4 Data and Command sending

Once the SLCD16x2 is properly connected and configured, data and command can be sent serially. For data sending, you can send any message such as "Hello" via serial I/O directly, "Hello" message will be shown on your LCD.

For command sending, you can send standard instruction set to LCD (see Figure 8-2) and precede it with the instruction prefix character, ASCII 254 (0FE hex or 11111110 binary). SLCD16x2 treats the byte immediately after prefix as an instruction, then automatically returns to data mode.

An example: To clear screen on LCD, clear instruction is 00000001 binary (or ASCII 1), send (254) and (1) to SLCD16x2 (where parentheses in () symbols mean single bytes set to these values)

COMMAND\DATA BIT	D7	D6	D5	D4	D3	D2	D1	D0	
1. Initial LCD	0	0	0	0	0	0	0	0	
2. Clear LCD	0	0	0	0	0	0	0	1	
3. Return Home	0	0	0	0	0	0	1	*	
4. Entry Mode Setting	0	0	0	0	0	1	I / D	S	
5. Display Setting	0	0	0	0	1	D	C	B	
6. Shift Display	0	0	0	1	S / C	R / L	*	*	
7. Function Setting	0	0	1	*	N	F	*	*	
8. Set CGRAM Address	0	1	A5	A4	A3	A2	A1	A0	
9. Set DDRAM Address	1	A6	A5	A4	A3	A2	A1	A0	

* Don't care bit
S 0=Automatic cursor shift after byte
1=Cursor not moved
I/D 0=After byte, decrease cursor position
1=After byte, increase cursor position
when S=1, cursor won't be shifted .)
D 0=Display OFF, 1=Display ON
C 0=Cursor OFF, 1=Cursor ON
B 0=Cursor not blink, 1=Cursor blink
S/C 0=Cursor shift, 1=Display Shift
R/L 0=Left shift, 1=Right shift
N 0=1/8 Duty, 1=1/16 Duty
(not recommend to set this bit,
use jumper setting instead)
F 0=5x7 dot size, 1=5x10 dot size
A0 to A7 are CGRAM or DDRAM Address

Standard instruction command set summary
(except Initial LCD is addition command.
Initialize make I/D=1, S=0, D=1, C=0, B=0, N=1, F=0, DDRAM Address=00

Serial input timing diagram

Figure 6-2 SLCD16x2 command summary and timing diagram

6.1.5 LCD Characters

Most of the LCD characters (Figure E) cannot be changed because they are stored in the ROM. However, the first eight symbols, corresponding to ASCII 0 through 7, are stored in the RAM. By Writing new values to the character-generator RAM (CGRAM), you can alter these characters as you want in 5x8 dots size.

HEX	00h	20h	30h	40h	50h	60h	70h	A0h	B0h	C0h	D0h	E0h	F0h												
DEC	0	32	40	48	56	64	72	80	88	96	104	112	120	160	168	176	184	192	200	208	216	224	232	240	248
0	(0	8	9	H	P	X)	h	P	X	4	-	3	3	3	3	3	3	3	3	3	3	3	3
1	.)	1	9	A	I	Q	Y	a	i	q	Y	3	3	3	3	3	3	3	3	3	3	3	3	3
2	*	*	2	:	B	J	R	Z	b	j	r	Z	4	4	4	4	4	4	4	4	4	4	4	4	4
3	#	+	3	3	C	K	T	S	c	k	t	S	*	*	*	*	*	*	*	*	*	*	*	*	*
4	\$,	4	4	<	D	L	T	*	d	l	T	5	5	5	5	5	5	5	5	5	5	5	5	5
5	%	!	5	5	E	M	U	J	e	m	u	J	6	6	6	6	6	6	6	6	6	6	6	6	6
6	8	.	6	6	F	N	U	V	f	n	u	V	7	7	7	7	7	7	7	7	7	7	7	7	7
7	?	/	7	7	G	O	W	9	g	o	w	9	8	8	8	8	8	8	8	8	8	8	8	8	8

NOTE: Custom characters occupy ASCII 0-7
ASCII 8-15 repeat the custom characters
ASCII 128-159 are used for Extended Mode Command only

LCD character set. (Built-in character on HD44780A or SED1278F0A)

Create your symbols by pointing to the CGRAM location, then write the first line whose bits form the desired pattern, and point to next CGRAM address to write bits later. Repeat this procedure until 8 times (one character), your character is ready to use now. CGRAM 0 is located on CGRAM Address 0x00 to 0x07, CGRAM 1 on 0x08 to 0x0F, CGRAM 2 on 0x10 to 0x17, ...until CGRAM 7 on 0x38 to 0x3F. See figure below

Bitmap Layout					Byte Values		
	bit 4	bit 3	bit 2	bit 1	bit 0	binary	decimal
byte 0	[]	[]	[]	[]	[]	xxx00000	0
byte 1	[]	[]	[]	[]	[]	xxx00100	4
byte 2	[]	[]	[]	[]	[]	xxx00010	2
byte 3	[]	[]	[]	[]	[]	xxx11111	31
byte 4	[]	[]	[]	[]	[]	xxx00010	2
byte 5	[]	[]	[]	[]	[]	xxx00100	4
byte 6	[]	[]	[]	[]	[]	xxx00000	0
byte 7	[]	[]	[]	[]	[]	xxx00000	0

Defining custom symbols.

Example: Load arrow symbol on CGRAM 3, a program would send the following bytes to the SLCD controller.

```
[254] , [01011000 b] , [0] ,
[254] , [01011001 b] , [4] ,
[254] , [01011010 b] , [2] ,
[254] , [01011011 b] , [31] ,
[254] , [01011100 b] , [2] ,
[254] , [01011101 b] , [4] ,
[254] , [01011110 b] , [0] ,
[254] , [01011111 b] , [0]
```

Standard LCD Instruction set

Only the instruction register (IR) and the data register (DR) of the LCD can be controlled by the MCU. Before starting the internal operation of the LCD, control information is temporarily stored into these registers to allow interfacing with various MCUs, which operate at different speeds, or various peripheral control devices. The internal operation of the LCD is determined by signals sent from the MCU. These signals, which include register selection signal (RS), read/write signal (R/W), and the data bus (DB0 to DB7), make up the LCD instructions (Table 3). There are four categories of instructions that:

- Designate LCD functions, such as display format, data length, etc.
- Set internal RAM addresses
- Perform data transfer with internal RAM
- Perform miscellaneous functions

Although looking at the table you can make your own commands and test them. Below is a brief list of useful commands which are used frequently while working on the LCD.

Instruction	Hex	Decimal
Function Set: 8-bit, 1 Line, 5x7 Dots	0x30	48
Function Set: 8-bit, 2 Line, 5x7 Dots	0x38	56
Function Set: 4-bit, 1 Line, 5x7 Dots	0x20	32
Function Set: 4-bit, 2 Line, 5x7 Dots	0x28	40
Entry Mode	0x06	6
Display off Cursor off (clearing display without clearing DDRAM content)	0x08	8
Display on Cursor on	0x0E	14
Display on Cursor off	0x0C	12
Display on Cursor blinking	0x0F	15
Shift entire display left	0x18	24
Shift entire display right	0x1C	30
Move cursor left by one character	0x10	16
Move cursor right by one character	0x14	20
Clear Display (also clear DDRAM content)	0x01	1
Set DDRAM address or cursor position on display	0x80+add*	128+add*
Set CGRAM address or set pointer to CGRAM location	0x40+add**	64+add**

* **DDRAM address given in LCD basics section**

** **CGRAM address from 0x00 to 0x3F, 0x00 to 0x07 for char1 and so on..**

6.2 Things to know about interface Arduino with SLCD16x2

The procedure of Arduino POP-168 with Serial LCD interfacing is :

- (1) Include the ***SoftwareSerial.h*** library with #include command
- (2) Define the POP-168 port pin with #define command as follows.

```
#define rxPin 3    // Set Di 3 as serial receiver pin or rxPin
#define txPin 2    // Set Di 2 as serial transmitter pin or txPin
SoftwareSerial mySerial = SoftwareSerial(rxPin, txPin);
```

(3) At **setup()**, you need to set the transmit pin to High logic, delay and set baudrate to 9600 with mySerial.begin(9600); command. The sample setup code is shown below.

```
digitalWrite(txPin, HIGH); // set txPin high (as recommended)
delay(1000);

// define pin modes for tx, rx pins:
pinMode(rxPin, INPUT);
pinMode(txPin, OUTPUT);
mySerial.begin(9600); // set baudrate
```

It is recommended setup code for Arduino when interface with Serial LCD or SLCD16x2 module.

The important commands for interfacing with SLCD16x2 module of POP-BOT are :

- (1) Initialized command :

```
mySerial.print(0xFE, BYTE);
mySerial.print(Command, BYTE);
```

- (2) Clear LCD screen :

```
mySerial.print(0x01, BYTE);
```

- (3) Move cursor to top left position or HOME position :

```
mySerial.print(0x80, BYTE);
```

- (4) Move cursor to left position of bottom line :

```
mySerial.print(0xC0, BYTE);
```

- (5) For writing the message, user must put message and covered by " ".

```
mySerial.print("Hello"); // Show "HELLO"
```

Activity 3 : SLCD16x2 simple programming

A3.1 Open the Arduino IDE and create the sketch code from Listing A3-1.

A3.2 Set the POP-BOT into Program mode. Upload the sketch to the robot.

A3.3 Reset the POP-BOT and observe the SLCD16x2 operation.

The SLCD16x2 shows message below :

POP-BOT
Hello World !

```
/*
 * POP-BOT V1.0
 * Filename : SimpleLCD.pde
 * Show message on SLCD
 */
#include <SoftwareSerial.h>
#define rxPin 16
#define txPin 16
SoftwareSerial MySerial = SoftwareSerial(rxPin,txPin);

void setup(){
    digitalWrite(txPin,HIGH);
    delay(1000);
    pinMode(txPin,OUTPUT);
    MySerial.begin(9600);
    delay(1000);
}
void loop(){
    MySerial.print(0xFE,BYTE);
    MySerial.print(0x80,BYTE);
    MySerial.print("POP-BOT");
    MySerial.print(0xFE,BYTE);
    MySerial.print(0xC0,BYTE);
    MySerial.print("Hello World !");
    while(1);
}
```

Listing A3-1 : SimpleLCD.pde file; the Arduino sketch file for demonstration the simple operation of Serial LCD with POP-BOT



Activity 4 : Control the SLCD16x2 with command

You can control many display operations of SLCD16x2 such as set the line display, clear screen, select the display format etc. by sending the control commands to SLCD16x2. For the Standard command mode, start byte must start with 0xFE and following the command. User can see the LCD command in SLCD information topic in this chapter.

A4.1 Open the Arduino IDE and create the sketch code from Listing A4-1.

A4.2 Set the POP-BOT into Program mode. Upload the sketch to the robot.

A4.3 Reset the POP-BOT and observe the SLCD16x2 operation.

The SLCD16x2 show many message displaying following the specific by program.

```
/*********************************************
* POP-BOT V1.0
* Filename : SLCDrunningText.pde
* Show running text and number on Serial LCD
********************************************/
#include <SoftwareSerial.h>
#define rxPin 16
#define txPin 16
SoftwareSerial MySerial = SoftwareSerial(rxPin,txPin);

void setup(){
  digitalWrite(txPin,HIGH);
  delay(1000);
  pinMode(txPin,OUTPUT);
  MySerial.begin(9600);
  delay(1000);
}
void LCD_CMD(int Command){
  MySerial.print(0xFE,BYTE);           // Command
  MySerial.print(Command,BYTE);
}
void loop(){
  int i;
  LCD_CMD(0x80);                   // First Line
  MySerial.print("POP-BOT");
  LCD_CMD(0xC0);                   // Second Line
  MySerial.print("Hello World !");
  delay(2000);

  LCD_CMD(0x01);                   // Clear Screen Command
  LCD_CMD(0x85);                   // ROW 1,COL 5
  MySerial.print("From");
  delay(500);

  LCD_CMD(0x07);                   // Shift left text
  for(i=0;i<9;i++){
    MySerial.print(" ");
    delay(200);
  }
}
```

```

LCD_CMD(0x05);                                // Shift right text
for(i=0;i<9;i++){
    MySerial.print(" ");
    delay(200);
}

for(i=0;i<9;i++){                                // Blinking text
    LCD_CMD(0x08);
    delay(200);
    LCD_CMD(0x0C);
    delay(200);
}

LCD_CMD(0x00);                                // Show text
MySerial.print("Innovative");                  // Line 1
LCD_CMD(0xC0);                                // Line 2
MySerial.print("Experiment");
delay(5000);
i=0;

// Show Number
LCD_CMD(0x01);                                // Clear screen
MySerial.print("Counter");                     // Line 1
while(1){
    i++;
    LCD_CMD(0xC5);                            // Line 2
    MySerial.print(i,DEC);
    delay(100);
}
}

```

Program description

Part 1 Initial the communication module in microcontroller and SLCD16x2

Part 2 Select the target line to display. The top line (0x80) is set to show POP-BOT message. The bottom line (0xC0) is set to show Hello World! message.

Part 3 Send the Clear screen command (0x01) and define the first letter at 5th digit on the top line of LCD (0x85) to show From message.

Part 4 Send the shift left command (0x07) and loop to shift the From message to left direction.

Part 5 Send the shift right command (0x05) and loop to shift the From message back to start.

Part 6 Loop for sending the Turn-off display command (0x08) and Turn-on display command (0x0C) and swap. It cause the message From will be blink.

Part 7 The operation is same Part 2 but change the message on top line as Innovative and bottom line as Experiment

Listing A4-1 : SLCDrunningText.pde file; the Arduino sketch file for demonstration more function of Serial LCD operation



7 : POP-BOT line tracking

Line following or Line tracking is a popular and common activity in robotics learning. The purpose of this activity is to learn about how to interface analog sensors. In the POP-BOT robot kit, it has a pair of Infrared reflector sensor for this activity. Two IR Reflector sensors will be installed at the bottom of the POP-BOT so that it can detect both white and black lines.

7.1 ZX-03 : Infrared reflector sensor

The heart of this sensor is TCRT5000 reflective object sensor. It is designed for close proximity infrared (IR) detection. There's an infrared diode behind its transparent blue window and an infrared transistor behind its black window. When the infrared emitted by the diode reflects off a surface and returns to the black window, it strikes the infrared transistor's base, causing it to conduct current. The more infrared incident on the transistor's base, the more current it conducts. The figure 7-1 shows the operation of ZX-03 sensor.

When used as an analog sensor, the ZX-03 can detect shades of gray on paper and distances over a short range if the light in the room remains constant.

The suitable distance from sensor to line or floor is during 3 to 8 mm. The output voltage is during 0.1 to 4.8V and digital value from 10-bit A/D converter is 20 to 1,000. Thus, ZX-03 will suitable to apply to line tracking sensor.

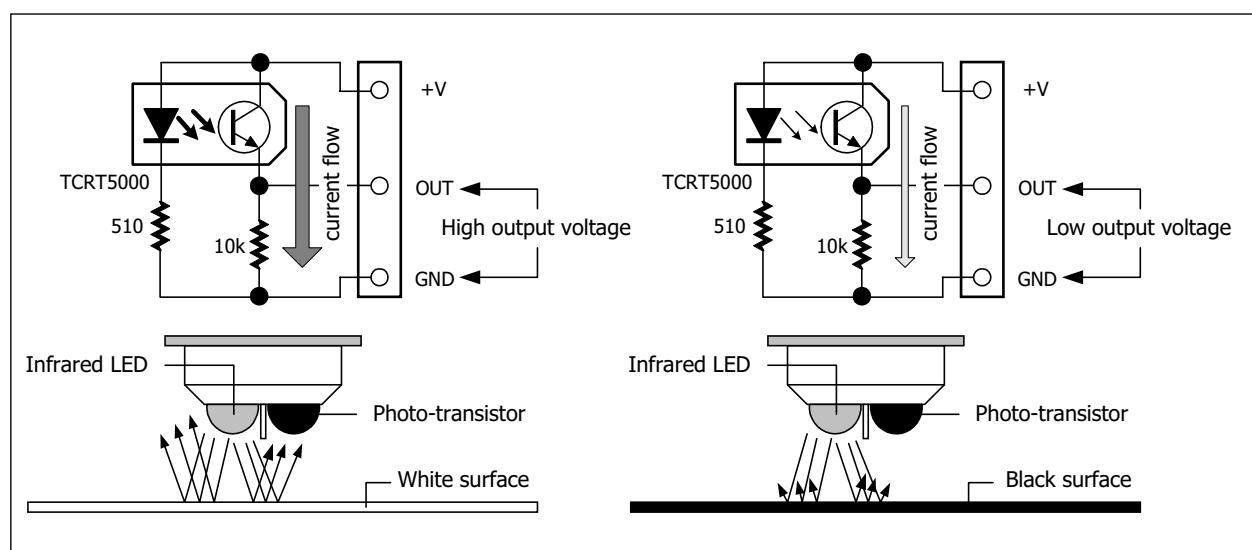


Figure 7-1 The operation of ZX-03 Infrared reflector sensor board with white and black surface

7.2 Line tracking activity preparation

7.2.1 Demonstration field component preparation

All activities are described in this chapter use the `make your own demonstration field`. They includes white surface with black line and black surface with white line field. You must make your own field using the items below (not provided in this kit) :

1. Polypropylene board or PP board white and Black sheet. Size is 90 x 60 cm. However the sizing can change depending on your applications and resources.
2. Black and white electrical tape 1 inches width 2 rolls per color. 3M brand is recommended.
3. Scissors or a Cutter

7.2.2 Set the reference value for line tracking activity with `analogRead()` function

POP-BOT can detect the difference between lines and surface by reading the infrared reflector sensors value via analog input ports. POP-BOT programming use `analogRead()` function of Arduino for reading analog sensor port.

POP-BOT reads the black line and surface data with low value (less than 400 and minimum is 0) and reads the white line and surface data with high value (higher than 500 and maximum is 1023). The reference value for making the decision about line or surface is average value from summing of black and white surface as follows :

$$\text{Reference value} = (\text{White surface value} + \text{black surface value}) / 2$$

The activity 5 shows the detail of the reference value for this line tracking activity.

Activity 5 : Testing black and white area

The POP-BOT robot is attached with 2 of Infrared reflector modules at bottom of the robot base. Thus, this activity will only dwell on the programming.

Before developing the robot to track the line, developers must program the robot to detect the difference between black and white surface.

A5.1 Open the Arduino IDE and create the sketch code from Listing A5-1.

A5.2 Set the POP-BOT into Program mode. Upload the sketch to the robot.

A5.3 Disconnect the download cable.

```
/*
 * POP-BOT V1.0
 * Filename : AnalogRead.pde
 * Read analog signal from Infrared reflector sensor to show on SLCD
 */
#include <SoftwareSerial.h>
#define rxPin 16
#define txPin 16
SoftwareSerial MySerial = SoftwareSerial(rxPin,txPin);
int LeftSensor;
int RightSensor;

void setup(){
    digitalWrite(txPin,HIGH);
    pinMode(txPin,OUTPUT);
    MySerial.begin(9600);
    delay(1000);
}
void LCD_CMD(int Command){
    MySerial.print(0xFE,BYTE);           // Command
    MySerial.print(Command,BYTE);
}
void loop(){
    LeftSensor = analogRead(7);          // Read value from left sensor
    RightSensor = analogRead(6);         // Read value from right sensor
    LCD_CMD(0x80);                     // Set display to first Line
    MySerial.print("L Sensor=      ");   // Show left sensor value on 1st line
    LCD_CMD(0x8A);
    MySerial.print(LeftSensor,DEC);

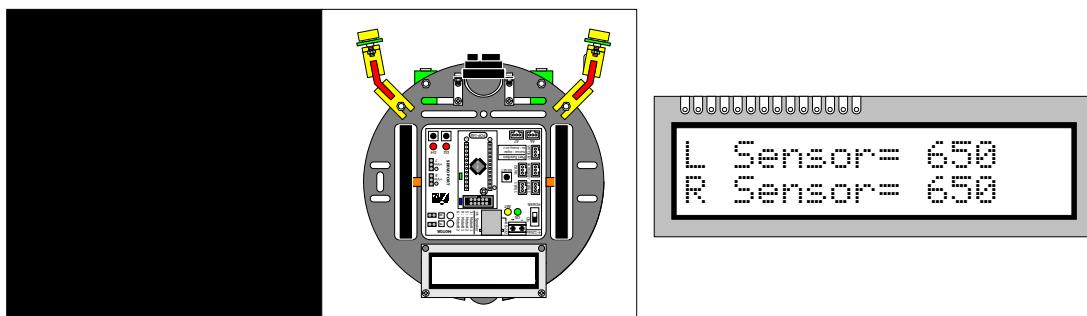
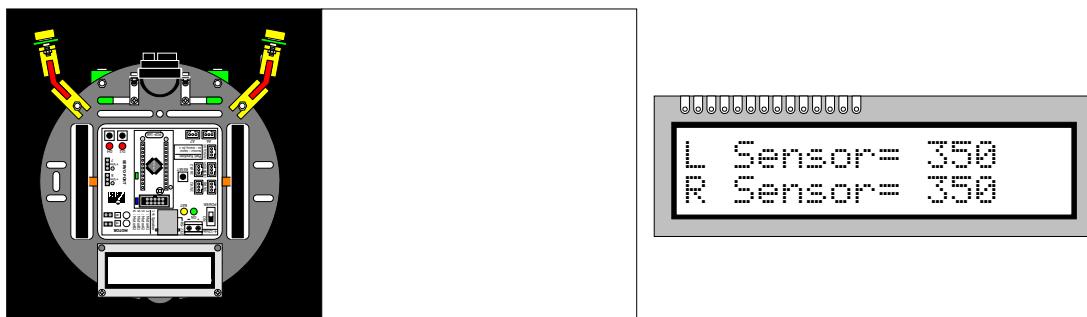
    LCD_CMD(0xC0);                     // Set display to second Line
    MySerial.print("R Sensor=      ");   // Show right sensor value on 2nd line
    LCD_CMD(0xCA);
    MySerial.print(RightSensor,DEC);
    delay(200);
}
```

Listing A5-1 : AnalogRead.pde file; the Arduino sketch file for reading the Infrared reflector sensor to display on Serial LCD of POP-BOT robot

A5.4 Make the black & white testing sheet similar to the illustration as shown below. The white surface area is 30 x 30 cm. and black surface is 30 x 30cm. (recommended).



A5.5 Place the POP-BOT that is programmed already from step A5.3 above the white surface of the testing chart. Turn on the robot. See the reading value at SLCD screen and record it. After that, read value of black surface and record the value also.



The result is :

The white surface value is between 500 and 950

The black surface value is between 100 and 400

The example reference value for detecting the line is $(650+350)/2 = 500$.



Activity 6 : POP-BOT border movement

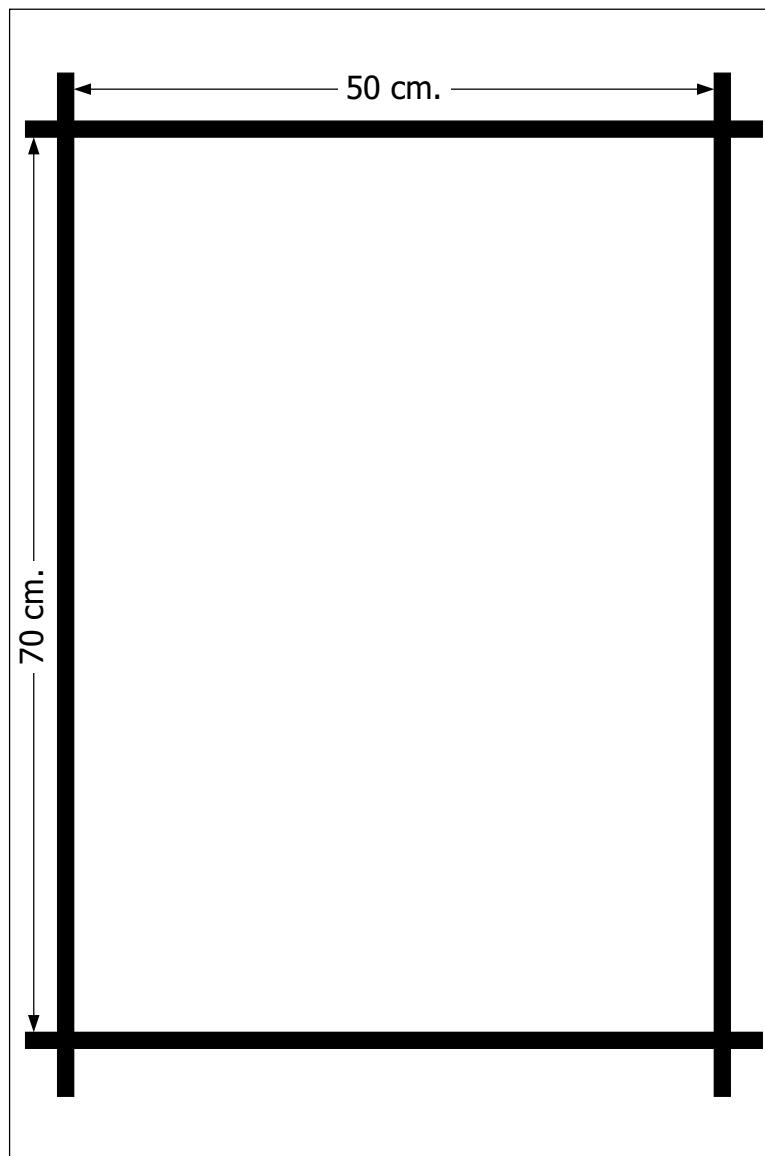
After knowing the values of the black and white surfaces, the next activity touches on how to move POP-BOT within the black border.

A6.1 Open the Arduino IDE and create the sketch code from Listing A6-1

A6.2 Set the POP-BOT into Program mode. Upload the sketch to the robot.

A6.3 Disconnect the download cable.

A6.4 Make the border field following the illustration below. The white surface area is 90 x 60 cm. and black line width is 1 inches (2.5 cm.)



```

/*********************  

* POP-BOT V1.0  

* Filename : BlackBorderMove.pde  

* POP-BOT moves in the black border line  

*****  

int Ref=500;  

int Left,Right;  

void setup(){  

    pinMode(3,OUTPUT);           // Motor A1  

    pinMode(5,OUTPUT);           // Motor A2  

    pinMode(6,OUTPUT);           // Motor B2  

    pinMode(9,OUTPUT);           // Motor B1  

}  

void loop(){  

    Left = analogRead(7);        // Read value from the left ZX-03 sensor  

    Right = analogRead(6);       // Read value from the right ZX-03 sensor  

    if (Left>Ref && Right>Ref){ // Both sensors detect the white surface  

        Forward(150);  

    }  

    else if (Left<Ref && Right<Ref){ // Both sensors detect the black line  

        Backward(150);delay(100);  

    }  

    else if (Left<Ref) {         // Only left sensor detects the black line  

        Backward(150);delay(300);  

        Spin_Right(150);delay(500);  

    }  

    else if (Right<Ref){        // Only right sensor detects the black line  

        Backward(150);delay(300);  

        Spin_Left(150);delay(400);  

    }  

}  

void Forward(int speed){  

    analogWrite(3,speed);  

    digitalWrite(5,LOW);  

    analogWrite(6,speed);  

    digitalWrite(9,LOW);  

}  

void Backward(int speed){  

    analogWrite(5,speed);  

    digitalWrite(3,LOW);  

    analogWrite(9,speed);  

    digitalWrite(6,LOW);  

}  

void Spin_Left(int speed){  

    analogWrite(5,speed);  

    digitalWrite(3,LOW);  

    analogWrite(6,speed);  

    digitalWrite(9,LOW);  

}  

void Spin_Right(int speed){  

    analogWrite(3,speed);  

    digitalWrite(5,LOW);  

    analogWrite(9,speed);  

    digitalWrite(6,LOW);  

}

```

Listing A6-1 : BlackBorderMove.pde file; the Arduino sketch file for black border movement demonstration of POP-BOT

A6.5 Place the POP-BOT within the black border field. Turn on the robot. Observe the robot movement.

POP-BOT moves forward on the white surface until any sensor detects the black border. This is robot behavior :

If both sensor detect the black line : POP-BOT move backward for a short while and then forward again.

If the left sensor detects the black line : POP-BOT move backward for a short while, spin right and then forward again.

If the right sensor detects the black line : POP-BOT move backward for a short while, spin left and then forward again.

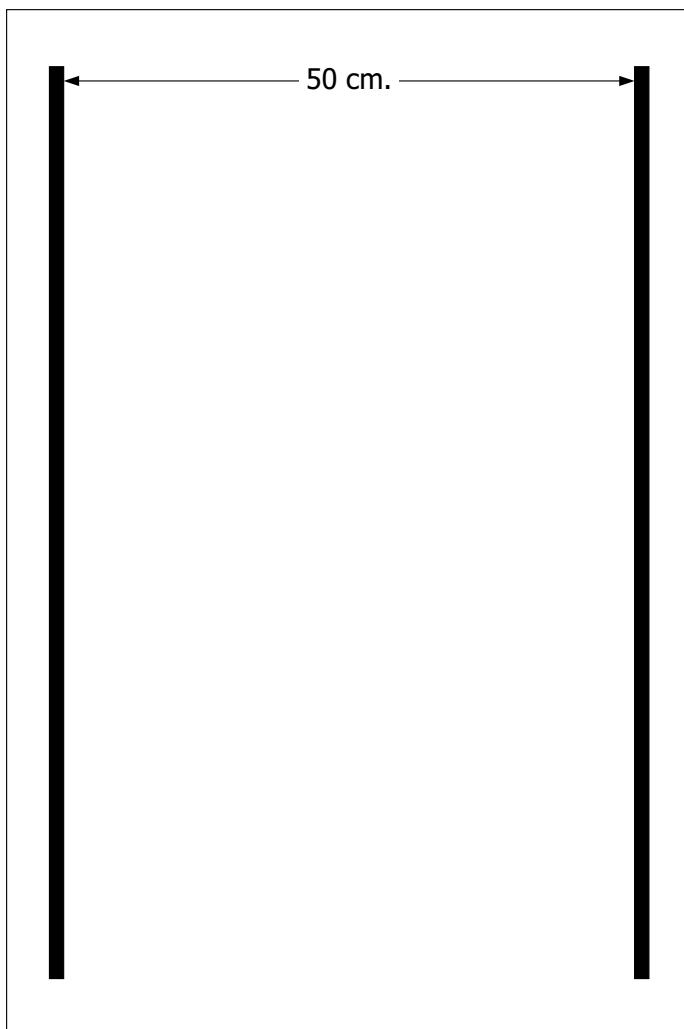
Finally, POP-BOT moves within the black border continually.



Activity 7 : POP-BOT with ping-pong movement

In this activity, it shows how POP-BOT move in a ZIG-ZAG format. The black line is the turning point. The POP-BOT moves forward until found the black line to change the direction. Loop this operation always. Thus, robot will move within space between both black lines.

- A7.1 Open the Arduino IDE and create the sketch code from Listing A6-1
- A7.2 Set the POP-BOT into Program mode. Upload the sketch to the robot.
- A7.3 Disconnect the download cable.
- A7.4 Make the Ping-pong field following the illustration below. The white surface area is 90 x 60 cm. and black line width is 1 inches (2.5 cm.)



```

/*****
 * POP-BOTV1.0
 * Filename : PingPong.pde
 * POP-BOT moves zigzag with 2 parallel lines
 *****/
int Ref=500;
int Left,Right;
void setup(){
    pinMode(3,OUTPUT);           // Motor A1
    pinMode(5,OUTPUT);           // Motor A2
    pinMode(6,OUTPUT);           // Motor B2
    pinMode(9,OUTPUT);           // Motor B1
}
void loop(){
    Left = analogRead(7);         // Read value from the left ZX-03 sensor
    Right = analogRead(6);        // Read value from the right ZX-03 sensor
    if (Left>Ref && Right>Ref){ // Both sensors detect the white surface
        Forward(150);
    }
    else if (Left<Ref && Right<Ref){ // Both sensors detect the black line
        Backward(150);delay(100);
    }
    else if (Left<Ref) {          // Only the left sensor detects the line
        Spin_Right(150);
        delay(420);
    }
    else if (Right<Ref){          // Only the right sensor detects the line
        Spin_Left(150);
        delay(420);
    }
}
void Forward(int speed){
    analogWrite(3,speed);
    digitalWrite(5,LOW);
    analogWrite(6,speed);
    digitalWrite(9,LOW);
}
void Backward(int speed){
    analogWrite(5,speed);
    digitalWrite(3,LOW);
    analogWrite(9,speed);
    digitalWrite(6,LOW);
}
void Spin_Left(int speed){
    analogWrite(5,speed);
    digitalWrite(3,LOW);
    analogWrite(6,speed);
    digitalWrite(9,LOW);
}
void Spin_Right(int speed){
    analogWrite(3,speed);
    digitalWrite(5,LOW);
    analogWrite(9,speed);
    digitalWrite(6,LOW);
}

```

Listing A7-1 : PingPong.pde file; the Arduino sketch file for Ping-pong movement demonstration of POP-BOT

Programming concept

The steps of programming in this activity are :

- (1) Find the value between the white surface and black line.
- (2) Read the sensor values and store to compare
- (3) Check the condition as follows :

Case #1 : Both sensors detect the white surface

Action : Robot moves forward.

Case #2 : Only the left sensor detects the black line.

Action : Robot spins right to change direction for moving to the black lines opposite side.

Case #3 : Only the right sensor detects the black line.

Action : Robot spins left to change direction for moving to the black lines opposite side.

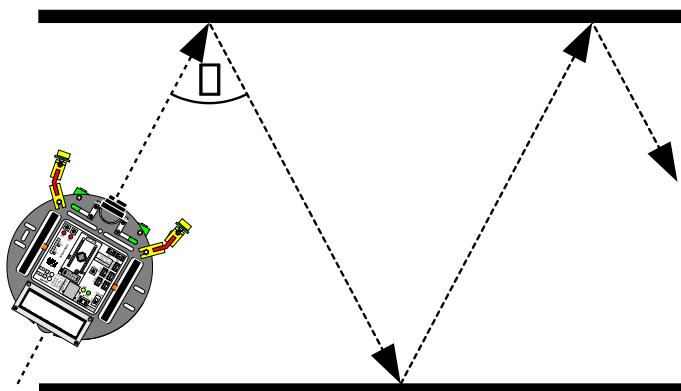
Case #4 : Out of 3 conditions above

Action : Up to programmer purpose.

- (4) Back to step (2).

A7.5 Place the POP-BOT on the Ping-pong field. Turn on the robot. Observe the robot movement.

In this program, determine the turning time to 150 millisecond approximation. It cause the turning angle ϕ (see the illustration below). Programmer can adjust the time value to make the suitable angle for control the movement path correctly.



If the time value is more, the ϕ angle is narrow. It cause the robot moves back to same path. In the other hand, the time value is less, the robot should move out of the line or possible to moves parallel the lines with do not detect the lines



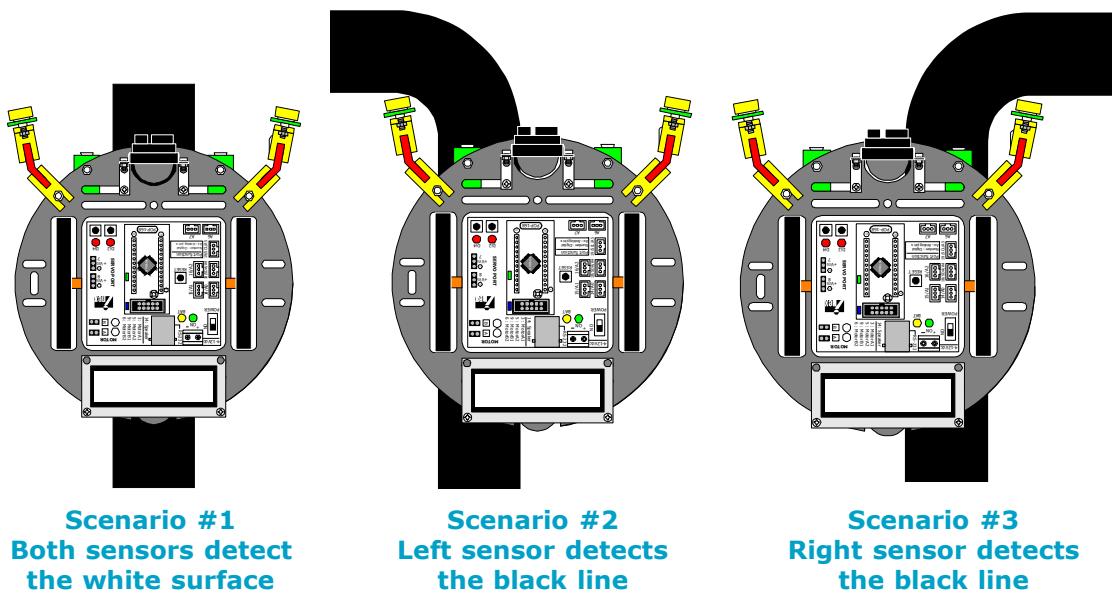
Activity 8 : Robot moves along the black line

The robot moving along the line can be in 3 different scenarios.

(1) Both sensors read values that are white : The robot will move forward. Thus, this program is written so that the robot moves forward normally.

(2) The left sensor detects the black line : This occurs when the robot is slightly turned to the right. Thus, the program is written for the robot to move back left to resume its normal path.

(3) The right sensor detects the black line : This occurs when the robot is slightly turned to the left. Thus, the program is written for the robot to move back to the right to resume its normal path.



From all scenarios,, you can make the C program as follows in the listing A8-1

A8.1 Open the Arduino IDE and create the sketch code from Listing A8-1

A8.2 Set the POP-BOT into Program mode. Upload the sketch to the robot.

A8.3 Disconnect the download cable.

```

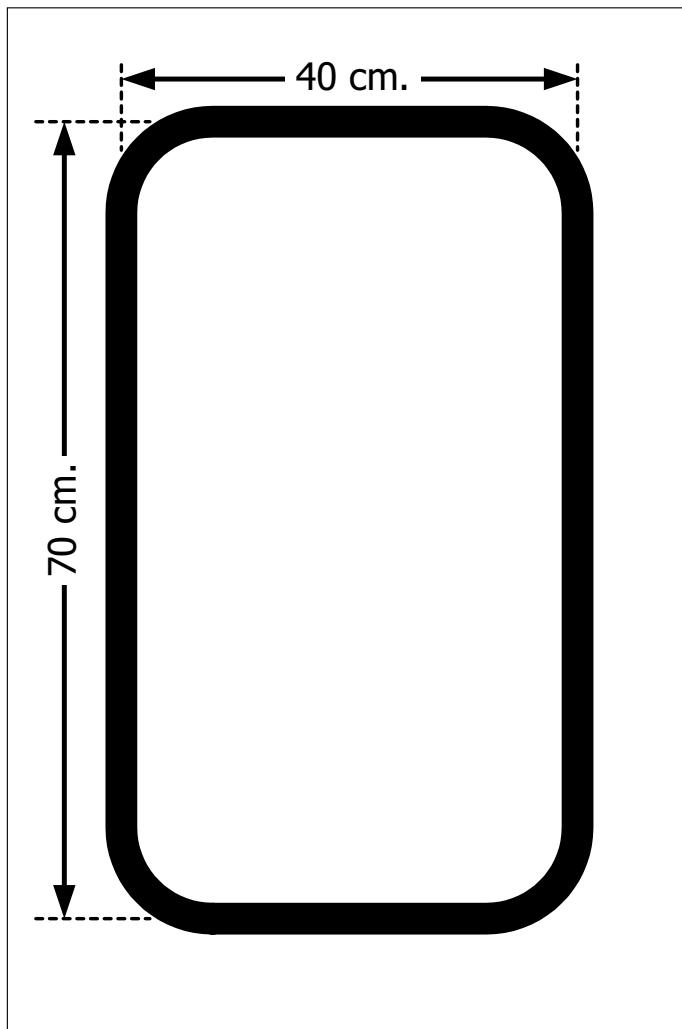
/*****
* POP-BOT V1.0
* Filename : SimpleLineTracking.pde
* POP-BOT tracks the black line
*****/
int Ref=500;
int Left,Right;
void setup(){
    pinMode(3,OUTPUT);           // Motor A1
    pinMode(5,OUTPUT);           // Motor A2
    pinMode(6,OUTPUT);           // Motor B2
    pinMode(9,OUTPUT);           // Motor B1
}
void loop(){
    Left = analogRead(7);        // Read value from left sensor
    Right = analogRead(6);       // Read value from right sensor
    if (Left>Ref && Right>Ref){ // Both sensors detect white surface
        Forward(150);
    }
    else if (Left<Ref) {         // Left sensor detects black line
        Spin_Left(250);
    }
    else if (Right<Ref){         // Rightt sensor detects black line
        Spin_Right(250);
    }
}

void Forward(int speed){
    analogWrite(3,speed);
    digitalWrite(5,LOW);
    analogWrite(6,speed);
    digitalWrite(9,LOW);
}
void Spin_Left(int speed){
    analogWrite(5,speed);
    digitalWrite(3,LOW);
    analogWrite(6,speed);
    digitalWrite(9,LOW);
}
void Spin_Right(int speed){
    analogWrite(3,speed);
    digitalWrite(5,LOW);
    analogWrite(9,speed);
    digitalWrite(6,LOW);
}

```

Listing A8-1 : SimpleLineTracking.pde file; the Arduino sketch file for POP-BOT moves along the black line

A8.4 Make the simple black line field following the illustration below. The white surface area is 90 x 60 cm. and black line width is 1 inches (2.5 cm.)



A8.5 Place the POP-BOT on the Black line field. Turn on the robot. Observe the robot movement.

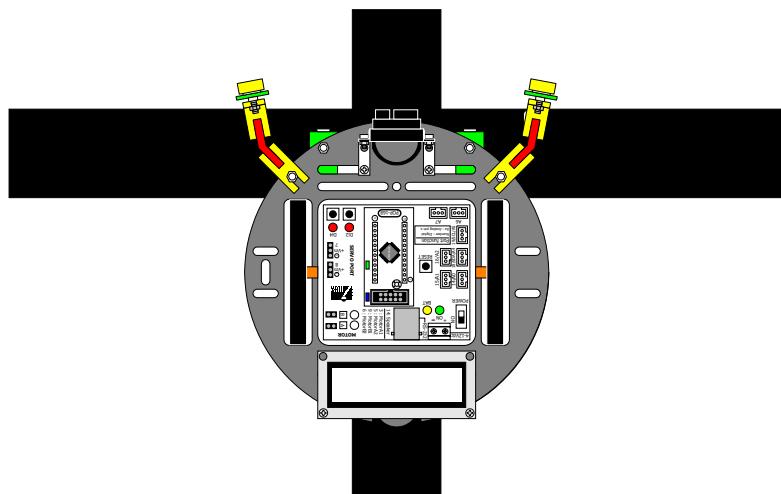
The POP-BOT will move along the black line. It is possible that the robot moves out of the line. You can improve the precision by editing the program with adjusting the sensor reference value and adjust to the position of both infrared reflector sensors.



Activity 9 : Line crossing detection

From the activity 8, you can improve the POP-BOT robot so that it moves along the black line and detects the junction or line with the same 2 sensors. All you have to do is to edit your program code.

When the robot moves to the black line T junction , both sensors will detect the black line. You must add the program for supporting this scenario. The improved C program is shown in the Listing A9-1.



```
/*
 * POP-BOT V1.0
 * Filename : CrossingLineDetect.pde
 * POP-BOT tracks the black line and beep when detect the crossing line
 */
int Ref=700;
int Left,Right;
int Cnt=0,j;
void setup(){
    pinMode(3,OUTPUT);           // Motor A1
    pinMode(5,OUTPUT);           // Motor A2
    pinMode(6,OUTPUT);           // Motor B2
    pinMode(9,OUTPUT);           // Motor B1
    pinMode(14,OUTPUT);          // PIEZO Speaker
}
void loop(){
    Left = analogRead(7);         // Read value from left sensor
    Right = analogRead(6);        // Read Value from right sensor
    if (Left>Ref && Right>Ref){ // Both sensors detect the white surface
        Forward(150);
    }
    else if (Left<Ref && Right<Ref){ // Both sensors detect the black line.
        // It's mean crossing line.
        Cnt++;
        Motor_Stop();
        for (j=0;j<Cnt;j++){
    }
```

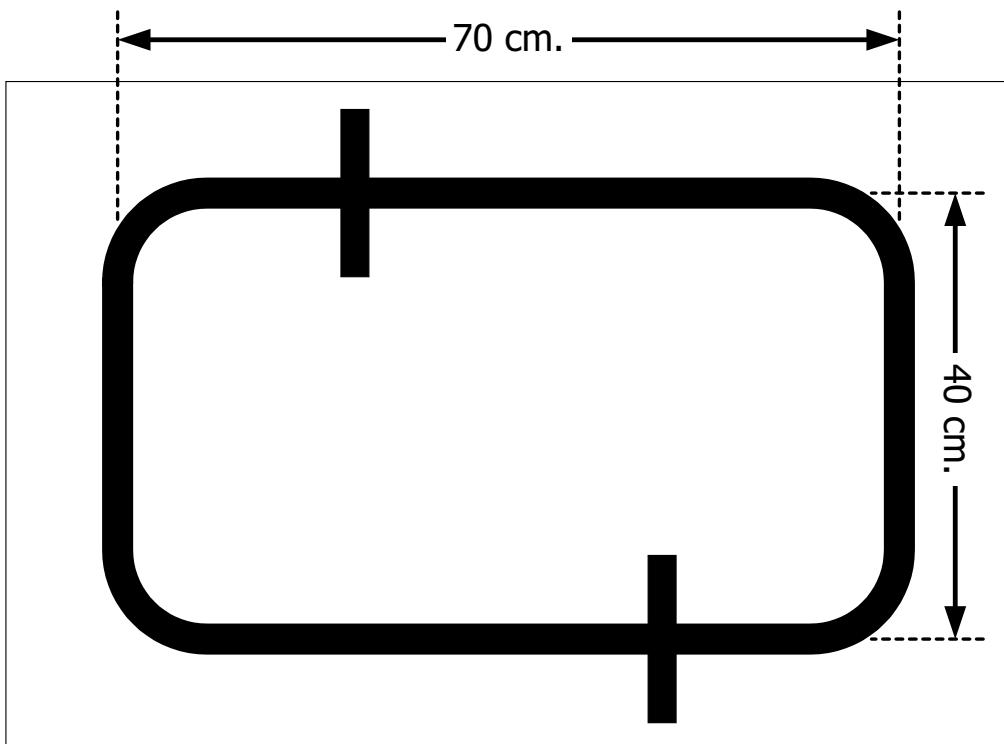
```

        Beep();
        delay(100);
    }
    Forward(150);
    delay(100);
}
else if (Left<Ref) {           // Left sensor detects the black line
    Spin_Left(255);
}
else if (Right<Ref){          // Right sensor detects the black linek
    Spin_Right(255);
}
}
void Beep(){                   // Beep routine
int i;
for (i=0;i<600;i++){
    digitalWrite(14,HIGH);
    delayMicroseconds(150);
    digitalWrite(14,LOW);
    delayMicroseconds(150);
}
}
void sound(int freq ,int duration){
unsigned long us;
int duration_,i;
us=(1000000/(freq*2));
duration_ = (duration/(us*2));
for (i=0;i<duration_;i++){
    digitalWrite(14,HIGH);
    delayMicroseconds(us);
    digitalWrite(14,LOW);
    delayMicroseconds(us);
}
}
void Forward(int speed){
analogWrite(3,speed);
digitalWrite(5,LOW);
analogWrite(6,speed);
digitalWrite(9,LOW);
}
void Motor_Stop(){
digitalWrite(3,LOW);
digitalWrite(5,LOW);
digitalWrite(6,LOW);
digitalWrite(9,LOW);
}
void Spin_Left(int speed){
analogWrite(5,speed);
digitalWrite(3,LOW);
analogWrite(6,speed);
digitalWrite(9,LOW);
}
void Spin_Right(int speed){
analogWrite(3,speed);
digitalWrite(5,LOW);
analogWrite(9,speed);
digitalWrite(6,LOW);
}
}

```

Listing A9-1 : CrossingLineDetect.pde file; the Arduino sketch file for POP-BOT moves along the black line and detects the crossing line

A9.1 Improve the simple black line field from Activity 8. Add some cross lines. Add as many junctions as you like. However, make sure that they are at least 2 robots width apart.



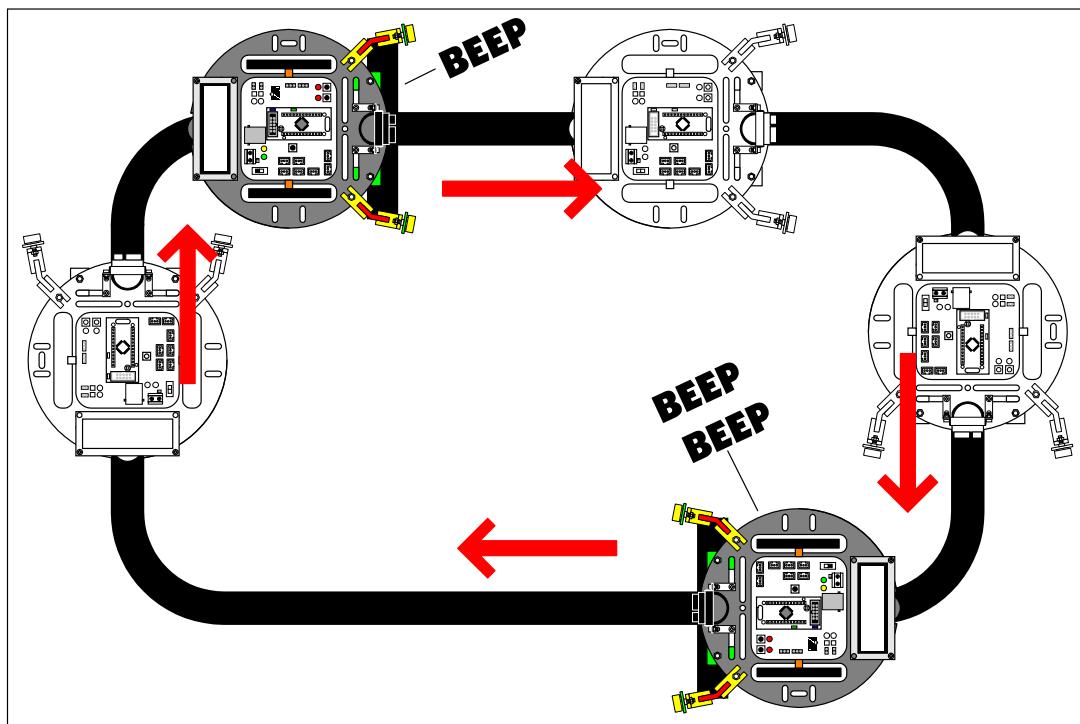
A9.2 Open the Arduino IDE and create the sketch code from Listing A9-1.

A9.2 Set the POP-BOT into Program mode. Upload the sketch to the robot.

A9.3 Disconnect the download cable.

A9.3 Place the robot on the field. Turn on power. Observe the robot movement.

The Robot will move along the black line. When the robot detects the junction, it will brake and beep once. When it finds the second junction, the robot will drive beep twice and this will increase for the subsequent junctions.



Note : In the motor brake operation, the robot will stop and lock the motor's shaft immediately. But sometimes, this is not enough. You must program the robot to move backwards for a short time. This will cause the robot to stop at its position.



Activity 10 : POP-BOT with 90 degree turning line tracking

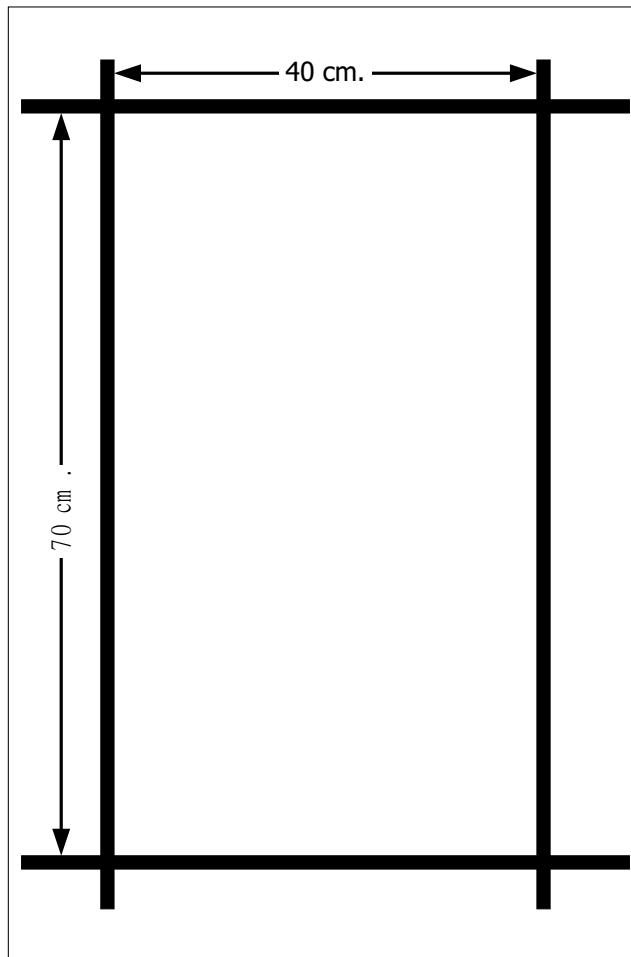
This activity features about 90 degree turning when robot detects the junction or crossing point. This technique is very important in Robotic challenges. Many line tracking challenges prepare many crossing lines or junctions. Robot must detect and moves precisely enough to maintain its movement stability.

A10.1 Open the Arduino IDE and create the sketch code from Listing A10-1

A10.2 Set the POP-BOT into Program mode. Upload the sketch to the robot.

A10.3 Disconnect the download cable.

A10.4 Make the border field following the illustration below. The white surface area is 90 x 60 cm. and black line width is 1 inches (2.5 cm.).



```

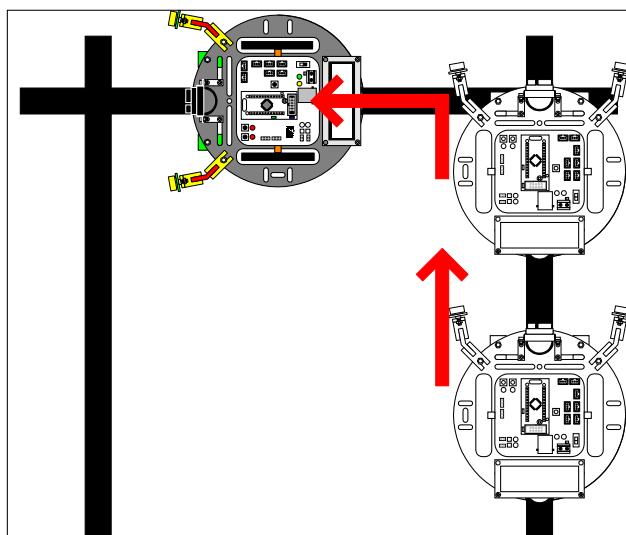
/*
 * POP-BOT V1.0
 * Filename : RightTurnLineTracking.pde
 * POP-BOT move following the line and turns right 90° when detect the crossing line
 */
int Ref=700;
int Left,Right;
void setup(){
    pinMode(3,OUTPUT);                                // Motor A1
    pinMode(5,OUTPUT);                                // Motor A2
    pinMode(6,OUTPUT);                                // Motor B2
    pinMode(9,OUTPUT);                                // Motor B1
    pinMode(14,OUTPUT);                               // PIEZO Speaker
}
void loop(){
    Left = analogRead(7);                            // Read value from the left ZX-03 sensor
    Right = analogRead(6);                           // Read value from the right ZX-03 sensor
    if ((Left<Ref) && (Right>Ref)){ // Detect the crossing line
        Right90();
    }
    else if ((Left>Ref) && (Right>Ref)){ // Over the line
        Forward(150);
    }
    else if (Left<Ref){ // Only the left sensor detects the black line
        Spin_Left(150);
    }
    else if (Right<Ref){ // Only the right sensor detects the black line
        Spin_Right(150);
    }
}
/*Turn right 90 degree function */
void Right90(){
    Forward(150);
    delay(50);
    Spin_Right(200);
    delay(100);
    while(analogRead(6)>Ref);
    delay(50);
}
/*Movement function*/
void Forward(int speed){
    analogWrite(3,speed);
    digitalWrite(5,LOW);
    analogWrite(6,speed);
    digitalWrite(9,LOW);
}
void Spin_Left(int speed){
    analogWrite(5,speed);
    digitalWrite(3,LOW);
    analogWrite(6,speed);
    digitalWrite(9,LOW);
}
void Spin_Right(int speed){
    analogWrite(3,speed);
    digitalWrite(5,LOW);
    analogWrite(9,speed);
    digitalWrite(6,LOW);
}

```

Listing A10-1 : CrossingLineDetect.pde file; the Arduino sketch file for POP-BOT moves along the black line and detects the crossing line

A10.5 Place the POP-BOT over the line. Turn on and observe the robot movement.

POP-BOT moves along the line. Every time robot detects the crossing line, it turns right with 90 degrees angle and continues to follow the line.



The most important factor of this activity is **Right90** function. It is C/C++ function for Arduino. We can describe the function operation as follows :

1. After robot's sensor detect the junction, POP-BOT must move forward 0.05 second for setting the robot's position at the centre of crossing line.
2. Spin right and delay 0.1 second
3. Loop to read the right sensor value and return until detect the black line.
4. Delay 0.05 second before back to main loop.

The source code of this function is shown below.

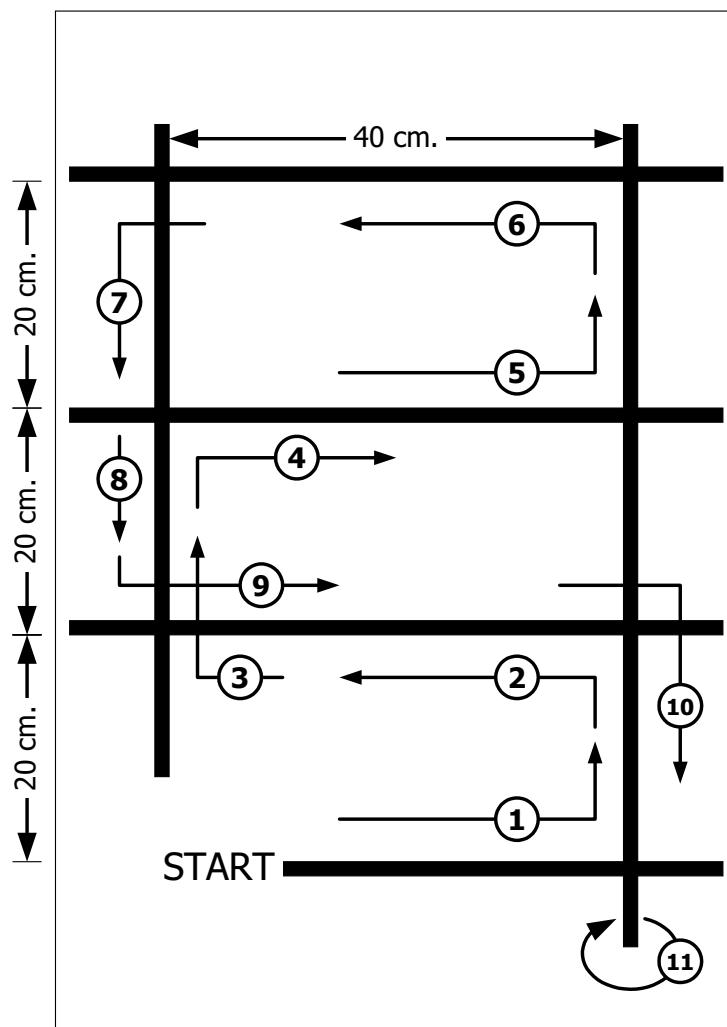
```
/*Turn right 90 degree function */
void Right90() {
    Forward(150);
    delay(50);
    Spin_Right(200);
    delay(100);
    while(analogRead(6) >Ref) ;
    delay(50);
}
```



Activity 11 : Multi-crossing line mission

This activity is taken from many popular line tracking mission in many robotic games. Many crossing line are included the field. The robot must move following the line and detect every crossing point or junction and make the decision to turn left or right or forward or backward.

With the example code in Activity 8 to 10, you can combine all to make the complete code for solving the multi-crossing line mission. The example field and movement path are shown below.



A11.1 Open the Arduino IDE and create the sketch code from Listing A11-1

A11.2 Set the POP-BOT into Program mode. Upload the sketch to the robot.

A11.3 Disconnect the download cable.

```

/*********************************************
* POP-BOT V1.0
* Filename : MultiCrossingLineDetect.pde
* POP-BOT move following the line and check the crossing line to do complex movement
********************************************/
int Ref=700;
int Left,Right;
int Cnt=0;
void setup() {
    pinMode(3,OUTPUT); // Motor A1
    pinMode(5,OUTPUT); // Motor A2
    pinMode(6,OUTPUT); // Motor B2
    pinMode(9,OUTPUT); // Motor B1
    pinMode(14,OUTPUT); // PIEZO Speaker
}
void loop(){
    while(Cnt<11){
        Left = analogRead(7); // Read value from the left ZX-03 sensor
        Right = analogRead(6); // Read value from the right ZX-03 sensor
        if ((Left<Ref) && (Right<Ref)){ // Found crossing point
            Cross();
        }
        else if ((Left>Ref) && (Right>Ref)){ // Move across the line a short while
            Forward(150);
        }
        else if (Left<Ref) { // Only left sensor detects the black
line
            Spin_Left(150); // Spin left a short while
        }
        else if (Right<Ref){ // Only right sensor detects the black
line
            Spin_Right(150); // Spin right a short while
        }
        Forward(200);
        delay(200);
        Spin_Left(200); // Turn around
        delay(2000);
        Motor_Stop();
        Beep();
        while(1);
    }
    void Cross(){
        Cnt++;
        if (Cnt==11){
            Motor_Stop();
        }
        else if (Cnt==8){ // Check for Forward
            Forward(200);
            delay(300);
        }
        else if(Cnt==3 || Cnt==4 || Cnt==10 ){ // Check for Turn right 90 degree
            Right90();
        }
        else{ // else Turn Left
            Left90();
        }
    }
}

```

```

/*Turn 90 degree function */
void Right90(){
    Forward(150);
    delay(50);
    Spin_Right(200);
    delay(100);
    while(analogRead(6)>Ref);
    delay(50);
}
/*Turn left 90 degree function */
void Left90(){
    Forward(150);
    delay(50);
    Spin_Left(200);
    delay(100);
    while(analogRead(7)>Ref);
    delay(50);
}
void Beep(){
    int i;
    for (i=0;i<600;i++){
        digitalWrite(14,HIGH);
        delayMicroseconds(150);
        digitalWrite(14,LOW);
        delayMicroseconds(150);
    }
}
void Forward(int speed){
    analogWrite(3,speed);
    digitalWrite(5,LOW);
    analogWrite(6,speed);
    digitalWrite(9,LOW);
}
void Spin_Left(int speed){
    analogWrite(5,speed);
    digitalWrite(3,LOW);
    analogWrite(6,speed);
    digitalWrite(9,LOW);
}
void Spin_Right(int speed){
    analogWrite(3,speed);
    digitalWrite(5,LOW);
    analogWrite(9,speed);
    digitalWrite(6,LOW);
}
void Motor_Stop(){
    digitalWrite(3,LOW);
    digitalWrite(5,LOW);
    digitalWrite(6,LOW);
    digitalWrite(9,LOW);
}

```

Listing A11-1 : MultiCrossingLineDetect.pde file; the Arduino sketch file for POP-BOT moves along the black line and detects the crossing line to solving the Multi-crossing line mission

A11.4 Place the POP-BOT at the START point (see the field illustration). Turn on and observe the robot movement.

POP-BOT moves along the line following the movement path that show in the field illustration. POP-BOT will do 3 scenarios when a junction is detected :

Scenario 1 : Move forward after detect the junction

Scenario 2 : Turn left after detect the junction

Scenario 3 : Turn right after detect the junction

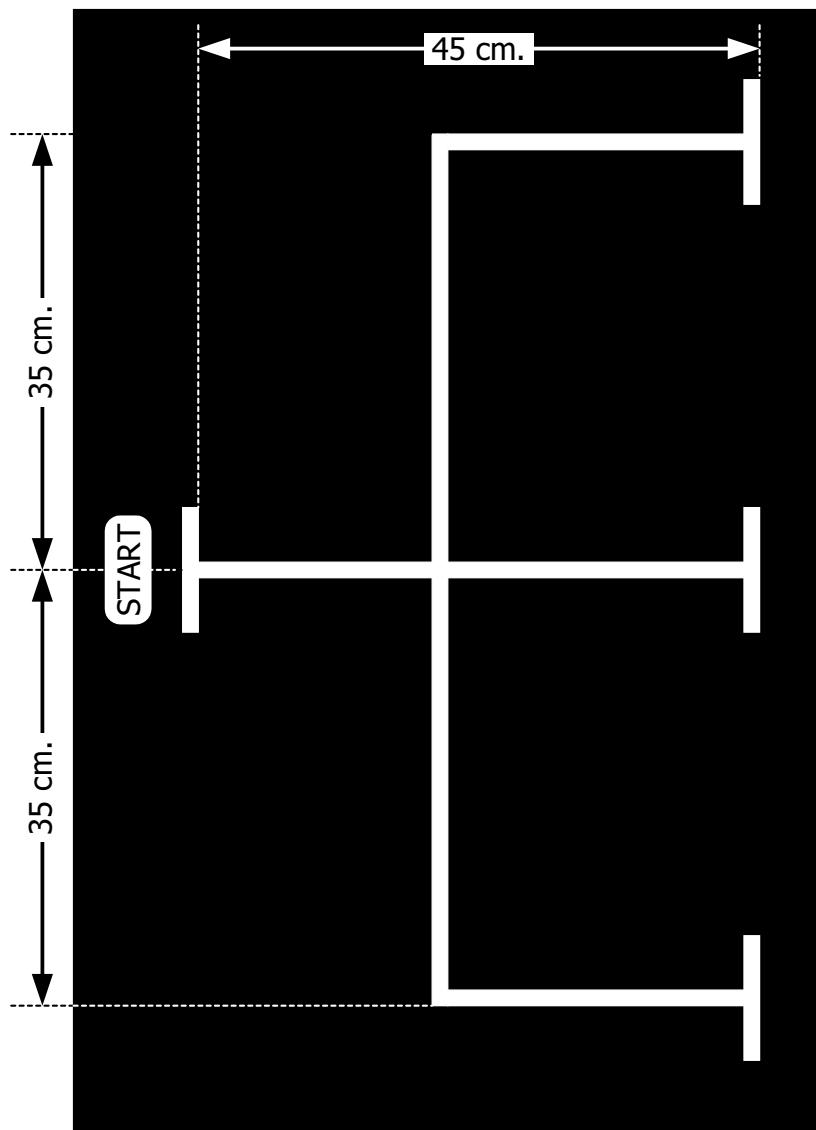
From the movement path; it has Scenario 1 only one position at 8th junction, Scenario 2 has 3 positions at 3rd-4th-10th junction. POP-BOT will do Scenario 3 for the rest junction.

After POP-BOT moves pass the last junction (11th), POP-BOT will turn around 2 seconds and stop.



Activity 12 : White line challenges

This activity is taken from the mission in robotic games. The difference from Activity 11 are line color and movement path. This activity change the line color as white on the black surface. See the illustration of field below. The mission is track the line from START to 3 ending lines or destinations. You can place a balloon at each end of line. Robot must pierce the balloon. Competitor who can pierce all balloons fastest is the winner.



A12.1 Open the Arduino IDE and create the sketch code from Listing A12-1

A12.2 Set the POP-BOT into Program mode. Upload the sketch to the robot.

A12.3 Disconnect the download cable.

```

/*****
* POP-BOT V1.0
* Filename : WhiteLineDetect.pde
* POP-BOT move following the line and check the junction to do complex movement
* for piercing the balloon at the 3 destinations
*****/
int Ref=400;
int Left,Right;
int Cnt=0;

void setup(){
    pinMode(3,OUTPUT);           // Motor A1
    pinMode(5,OUTPUT);           // Motor A2
    pinMode(6,OUTPUT);           // Motor B2
    pinMode(9,OUTPUT);           // Motor B1
    pinMode(14,OUTPUT);          // PIEZO Speaker
}

void loop(){
    while(Cnt<12){
        Left = analogRead(7);           // Read value from the left ZX-03 sensor
        Right = analogRead(6);          // Read value from the right ZX-03 sensor
        if ((Left<Ref) && (Right<Ref)){ // Detect the black crossing line
            Cross();
        }
        else if ((Left>Ref) && (Right>Ref)){ // Detect the white line
            Forward(150);
        }
        else if (Left<Ref) {           // Only the left sensor detects the line
            Spin_Right(150);          // Turn right
        }
        else if (Right<Ref){          // Only the right sensor detects the line
            Spin_Left(150);           // Turn left
        }
    }
    while(1);                      // Endless loop
}
void Cross(){
    Cnt++;
    if (Cnt==12){
        Motor_Stop();
    }
    else if (Cnt==2 || Cnt==10 ){      // Check for turning right 90 deg.
        Right90();
    }
    else if(Cnt==3 || Cnt==6 || Cnt==9 ){ // Check for turning left 180 deg.
        Left180();
    }
    else{                            // else turn left 90 deg.
        Left90();
    }
}

```

```

/*Turn right 90 degree function */
void Right90(){
    Forward(150);
    delay(50);
    Spin_Right(200);
    delay(100);
    while(analogRead(6)<Ref);
    delay(50);
}

/*Turn left 90 degree function */
void Left90(){
    Forward(150);
    delay(50);
    Spin_Left(200);
    delay(100);
    while(analogRead(7)<Ref);
    delay(50);
}

/*Turn left 180 degree function */
void Left180(){
    Spin_Left(200);
    delay(300);
    while(analogRead(7)<Ref);
    delay(50);
}

/*Movement function*/
void Forward(int speed){
    analogWrite(3,speed);
    digitalWrite(5,LOW);
    analogWrite(6,speed);
    digitalWrite(9,LOW);
}
void Spin_Left(int speed){
    analogWrite(5,speed);
    digitalWrite(3,LOW);
    analogWrite(6,speed);
    digitalWrite(9,LOW);
}
void Spin_Right(int speed){
    analogWrite(3,speed);
    digitalWrite(5,LOW);
    analogWrite(9,speed);
    digitalWrite(6,LOW);
}
void Motor_Stop(){
    digitalWrite(3,LOW);
    digitalWrite(5,LOW);
    digitalWrite(6,LOW);
    digitalWrite(9,LOW);
}

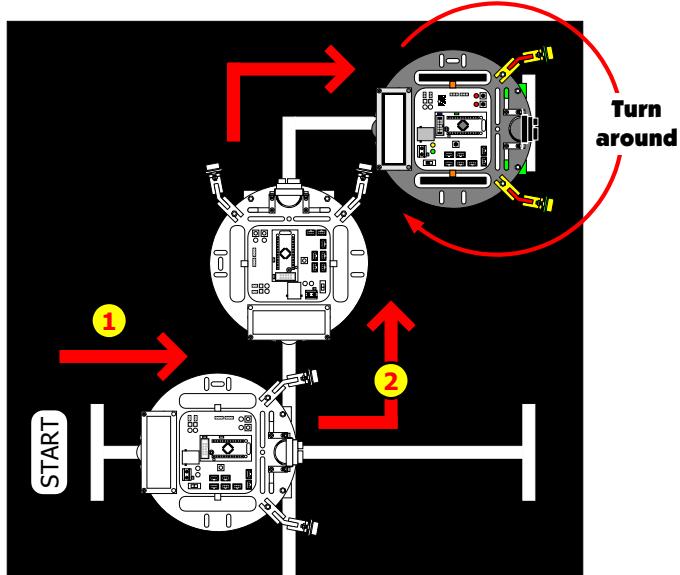
```

Listing A12-1 : WhiteLineDetect.pde file; the Arduino sketch file for POP-BOT moves along the white line and detects junctions to piercing the balloon at the destinations

A12.4 Place the POP-BOT at the START point (see the field illustration). Turn on and observe the robot movement.

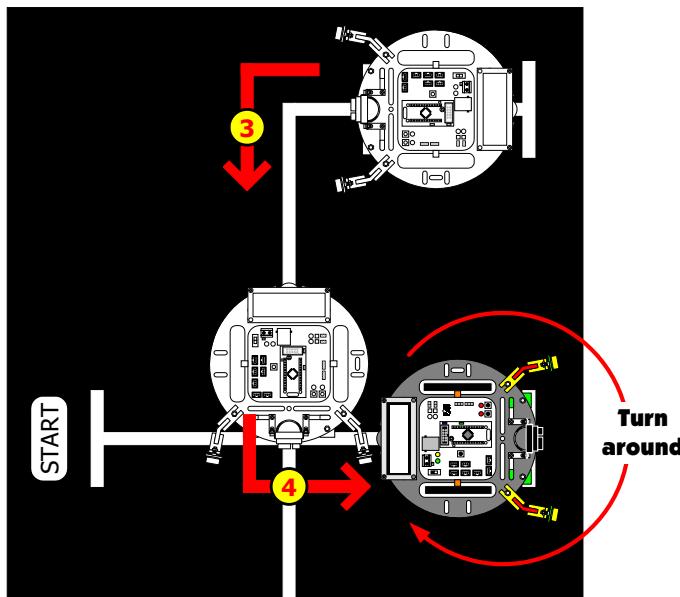
Step 1 : POP-BOT moves along the line from START point

Step 2 : POP-BOT detects the first junction and turn left to moves to the first destination at the left side of field.



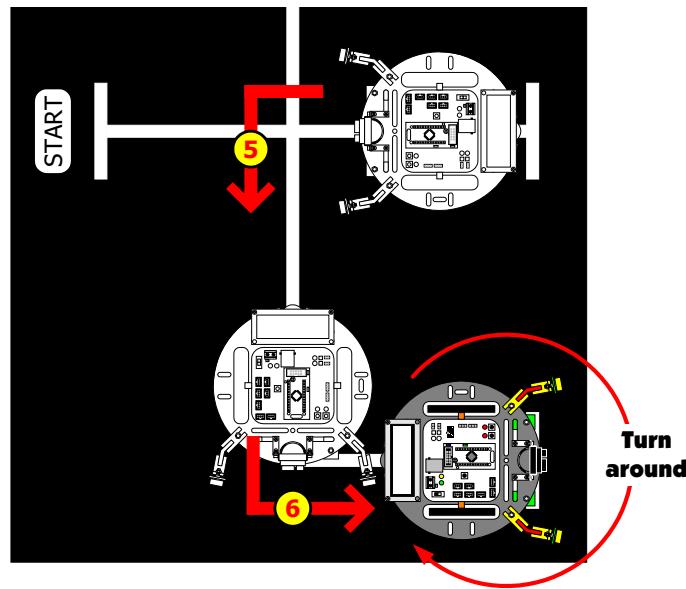
Step 3 : POP-BOT moves back from the first destination pass the junction again.

Step 4 : POP-BOT detects the junction second time and turn left to moves to the second destination at the middle of field.



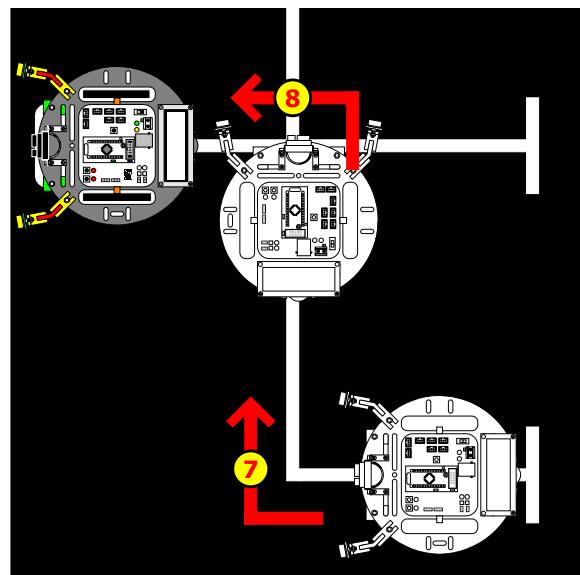
Step 5 : POP-BOT moves back from the second destination pass the junction again.

Step 6 : POP-BOT detects the junction third time and turn left to moves to the last destination at the right side of field.



Step 7 : POP-BOT moves back from the last destination pass the junction again.

Step 8 : POP-BOT detects the junction last time and moves forward to go back the START point for finishing the mission.



8 : POP-BOT Edging detection

In Chapter 7, we used the infrared reflector sensors to detect the lines. Do you know these sensor able to do more ? This chapter will show an activity about using infrared reflector sensors for surface detection to control the robot move on the table and not fall off the edge of the table !

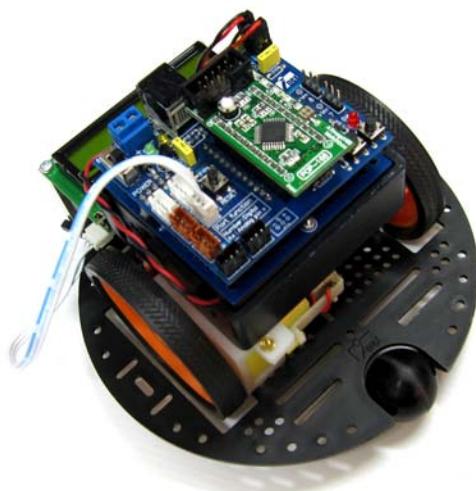
With a simple change of the position of the sensors and a simple program, you can adapt the POP-BOT to edge detection. Start assembling the mechanical parts place the sensors in the right position and create the Arduino sketch for the table surface testing.

8.1 Additional part list

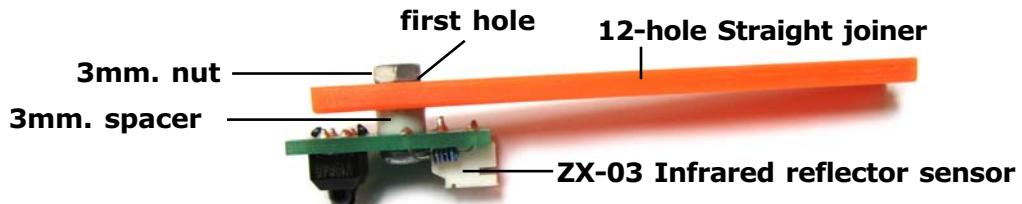


8.2 Modify procedure

(1) Remove all Touch sensors and Line tracking sensors from the POP-BOT chassis. Now we have the simplest form of the POP-BOT mobile robot.



(2) Attach the ZX-03 Infrared reflector sensor with 12-hole Straight joiner at the first hole by using 3x10mm. screw, 3mm. plastic spacer and 3mm. nut. following the photo is shown below. Do 2 sets of these.



(3) Fix both sensor structures from step (2) at the left and right hand side of front of POP-BOT chassis by using 3x10mm. screws and 3mm. nuts following the photo below. Next, connect the left sensor cable to A7 port and right sensor to A6 port. You can adjust the sensor arm position to suite your conditions.

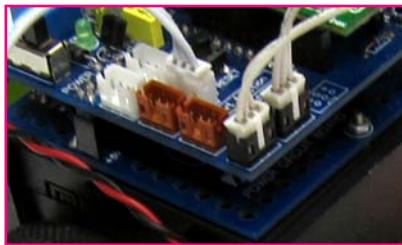
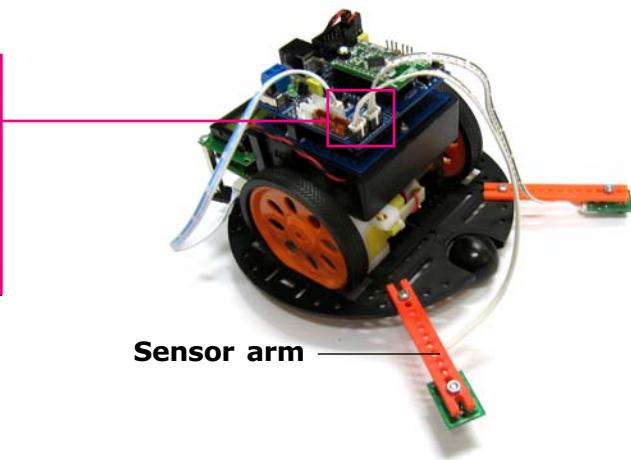


Photo shows the sensor connections on POP-BOT controller board



Activity 13 : POP-BOT Edge detection

This activity demonstrates this interesting behavior; POP-BOT moves on the table and never drop off from the table. By using 2 of infrared reflectors that are fixed at the front of robot, you can detect the outer area of the table. It's similar to line tracking code. If sensors detect the surface, they will give a higher data. Once the sensors are out of the table, there is no infrared ray reflected from the surface to sensor and thus the return value from sensor will be low or near zero.

You can use this behavior to make the code to control the POP-BOT to move on the table and detect the table's edge.

A13.1 Open the Arduino IDE and create the sketch code from Listing A13-1.

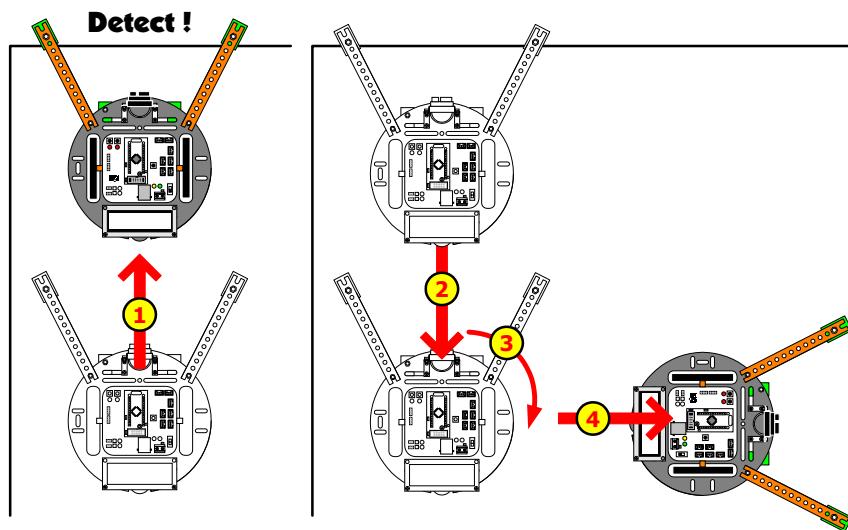
A13.2 Set the POP-BOT into Program mode. Upload the sketch to the robot.

A13.3 Disconnect the download cable.

A13.4 Place the POP-BOT on the table. You must remove all objects from the table. Turn on POP-BOT and observe the robot's movement.

POP-BOT moves forward until the sensor out from the table's edge. POP-BOT will change the movement direction following these scenarios :

1. Both sensors are out from table's edge : POP-BOT moves backward and spin right then moves forward again.



```

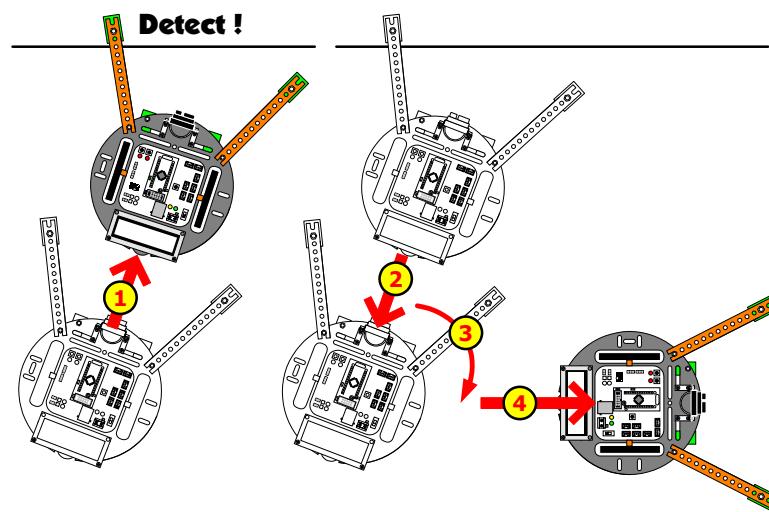
 ****
 * POP-BOT V1.0
 * Filename : EdgeDetect.pde
 ****
int Ref=300;
int Left,Right;
void setup(){
    pinMode(3,OUTPUT);           // Motor A1
    pinMode(5,OUTPUT);           // Motor A2
    pinMode(6,OUTPUT);           // Motor B2
    pinMode(9,OUTPUT);           // Motor B1
}
void loop(){
    Left = analogRead(7);         // Read value from the left ZX-03 sensor
    Right = analogRead(6);        // Read value from the right ZX-03 sensor
    if (Left>Ref && Right>Ref){ // Both sensors are on the table
        Forward(150);
    }
    else if (Left<Ref && Right<Ref){ // Both sensors out of the table
        Backward(150);
        delay(200);
        Spin_Right(150);
        delay(500);
    }
    else if (Left<Ref) {          // Only the left sensor outs of the table
        Backward(150);
        delay(300);
        Spin_Right(150);
        delay(400);
    }
    else if (Right<Ref){          // Only hte right sensor outs of the table
        Backward(150);
        delay(300);
        Spin_Left(150);
        delay(300);
    }
}

/*Movement function*/
void Forward(int speed){
    analogWrite(3,speed);
    digitalWrite(5,LOW);
    analogWrite(6,speed);
    digitalWrite(9,LOW);
}
void Backward(int speed){
    analogWrite(5,speed);
    digitalWrite(3,LOW);
    analogWrite(9,speed);
    digitalWrite(6,LOW);
}
void Spin_Left(int speed){
    analogWrite(5,speed);
    digitalWrite(3,LOW);
    analogWrite(6,speed);
    digitalWrite(9,LOW);
}
void Spin_Right(int speed){
    analogWrite(3,speed);
    digitalWrite(5,LOW);
    analogWrite(9,speed);
    digitalWrite(6,LOW);
}

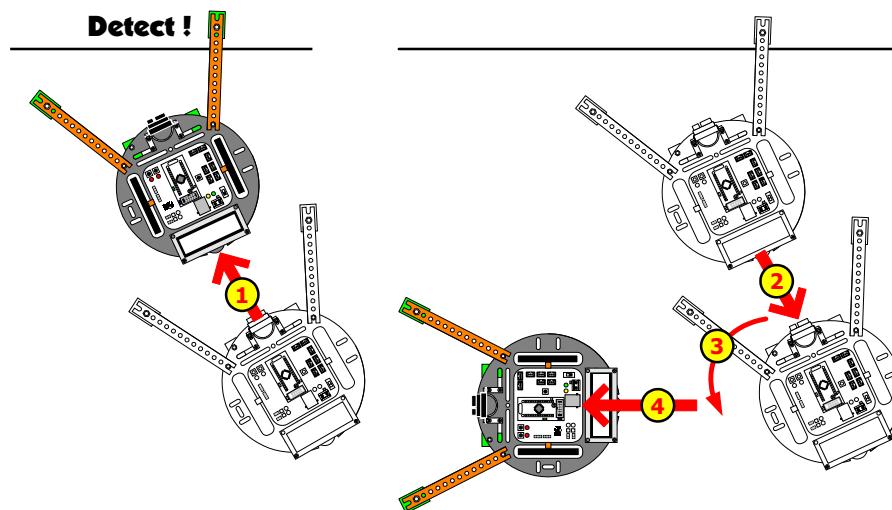
```

Listing A13-1 : EdgeDetect.pde file; the Arduino sketch file for POP-BOT detect and move on the table

2. The left sensor is out from talbe's edge : POP-BOT moves backward and spin right then moves forward again.



3. The right sensor is out from talbe's edge : POP-BOT moves backward and spin left then moves forward again.



9 : POP-BOT touchless object avoiding

9.1 GP2D120 : 4 to 30cm. Infrared distance sensor

From chapter 7, we have many examples about interfacing the Infrared reflector sensors. They are one kind of analog sensor. In this chapter, we will concentrate in interfacing with another analog sensors. It is Infrared distance sensor or Infrared ranger; GP2D120. We have some of example about using this sensor and applications.

One of the special sensors in robotics is the Infrared Distance sensor. Some people call it the IR Ranger. With the GP2D120 module, it gives POP-BOT the ability for distance measurement and obstacle detection using an infrared light. Your POP-BOT can avoid obstacles without having to make any physical contact.

9.1.1 GP2D120 features

- Uses Infrared light reflection to measure range
- Can measure a range from 4 to 30 cm.
- 4.5 to 5 V power supply and 33mA electric current
- The output voltage range is 0.4 to 2.4V when supplied by +5V

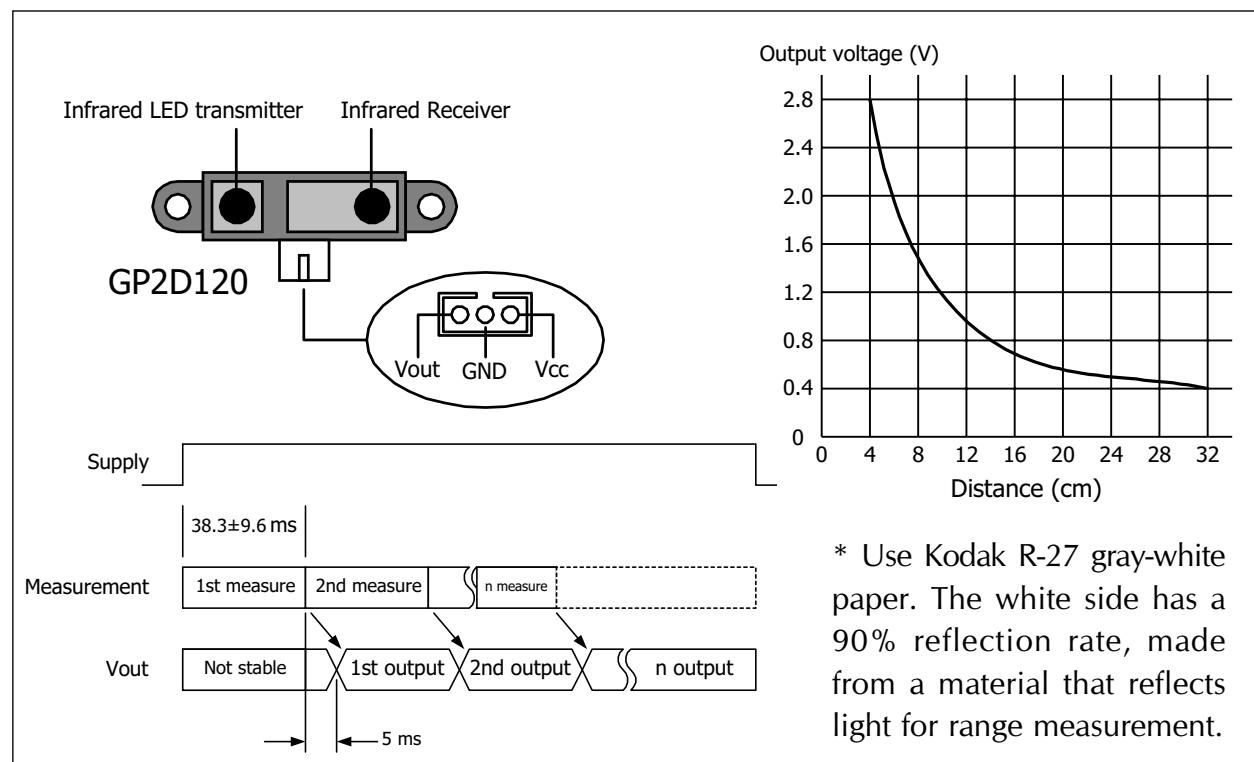


Figure 9-1 : GP2D120 pin assignment, operation and characteristic curve

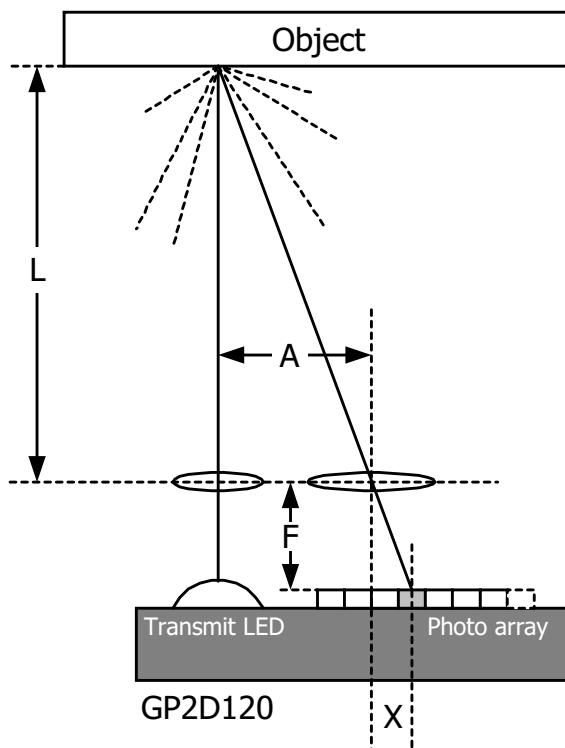
GP2D120 Infrared Ranger module has 3 terminals : Supply input (Vcc), Ground (GND) and Voltage output (Vout). To read the voltage values from the GP2D120, you must wait until after the acknowledgement period which is around 32 to 52.9 ms.

The output voltage of GP2D120 at a range of 30 cm. and +5V power supply is between 0.25 to 0.55V, with the mean being 0.4V. At the range of 4 cm., the output voltage will change at $2.25V \pm 0.3V$.

9.1.2 How the IR Ranger Module works

Measuring range can be done in many ways. The easiest to understand is through ultra sonic where sound waves are sent to the object and the time it takes to reflect back is measured. This is because sounds waves do not travel fast, and can be measured by present day equipment. However, in the case of infrared light, the time it takes to hit an obstacle and reflect back can not be measured because infrared light travels fast. No measurement equipment is available yet. Therefore, the following theory must be used.

The infrared light is sent out from a transmitter to the object in front, by passing through a condense lens so that the light intensity is focused on a certain point. Refraction occurs once the light hits the surface of the object. Part of the refracted light will be sent back to the receiver end, in which another lens will combine these lights and determine the point of impact. The light will then be passed on to an array of photo-transistors. The position in which the light falls can be used to calculate the distance (L) from the transmitter to the obstacle using the following formula:



$$\frac{L}{A} = \frac{F}{X}$$

Therefore, L equals

$$L = \frac{F \times A}{X}$$

Thus, the distance value from the phototransistors will be sent to the Signal Evaluation Module before it is changed to voltage, resulting in a change of voltage according to the measured distance.

9.1.3 Reading GP2D120 with A/D converter

The GP2D120's output voltage will change according to the detection distance. For example, Vout 0.5V is equal 26cm. distance and Vout 2V is equal 6cm. distance. The table 9-1 shows the summary of GP2D120's Vout and Distance relation.

For interfacing with A/D converter module within microcontroller, the result is raw data from the A/D conversion. The user will need to use the software to convert the raw data to the exact distance. You can calculate the approximate distance from the formula below.

$$R = \frac{2914}{V+5} - 1$$

Thus, R as Distance in Centimetre unit

V as Digital data from A/D conversion

For example, see the Table 9-1. The raw data from conversion is 307. It is equal 8cm. distance.

Warning for the signal cable of the GP2D120

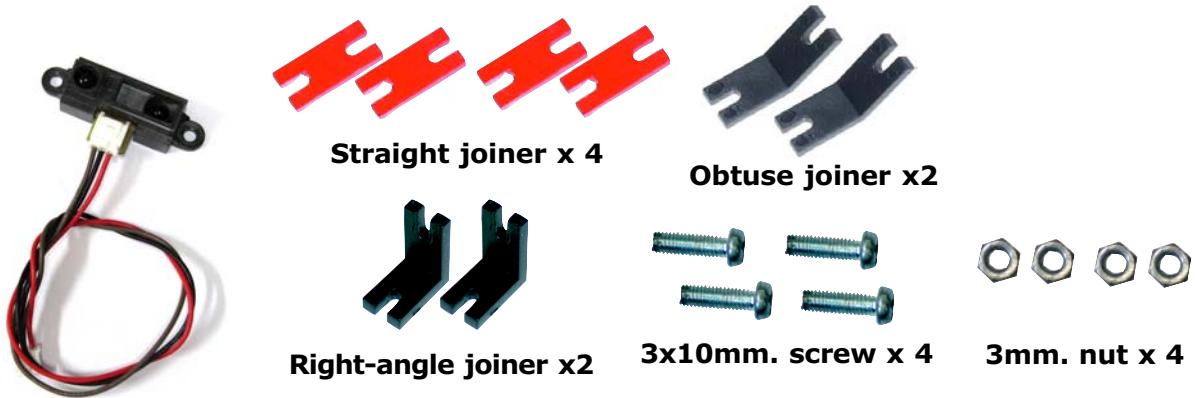
The GP2D120 module has a different pin arrangement than that of the POP-BOT controller board, even though it looks similar. Therefore, a special signal cable has already been connected to the GP2D120 module. The user just needs to connect the other end of the cable to the connection points of the POP-BOT controller board. DO NOT remove the cable from the module, and do not replace it with signal cables from other sensor modules.

GP2D120 output voltage (V)	10-bit A/D converter result	Distance (cm.)
0.4	82	32
0.5	102	26
0.6	123	22
0.7	143	19
0.8	164	16
0.9	184	14
1.0	205	13
1.1	225	12
1.2	246	11
1.3	266	10
1.4	287	9
1.5	307	8
1.6	328	8
1.7	348	7
1.8	369	7
1.9	389	6
2.0	410	6
2.1	430	6
2.2	451	5
2.3	471	5
2.4	492	5
2.5	512	5
2.6	532	4

Table 9-1 : The relation of GP2D120 output voltage, A/D converter result and Measured distance.

9.2 POP-BOT modification for GP2D120

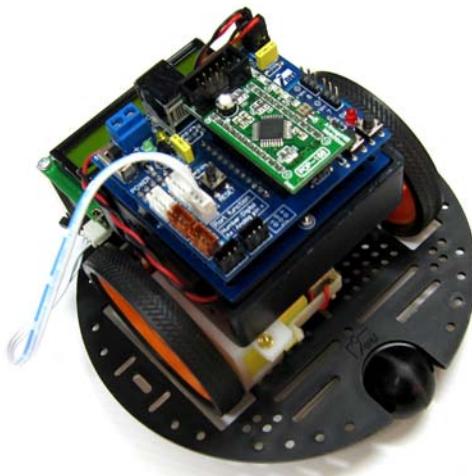
9.2.1 Additional part list



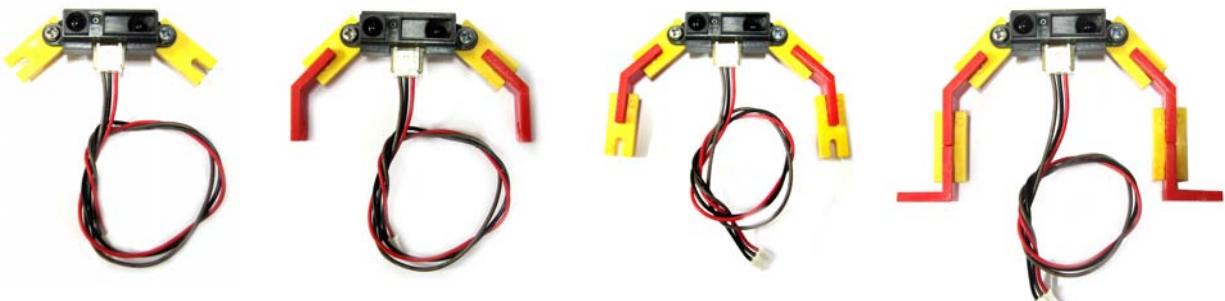
GP2D120 with cable

9.2.2 Modify procedure

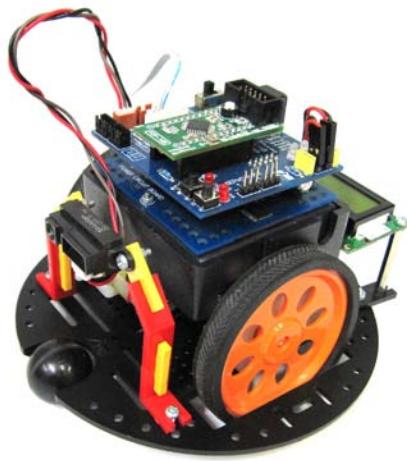
(1) Remove all sensors from POP-BOT chassis. Now we have the simplest form of the POP-BOT mobile robot.



(2) Attach 2 pieces of Straight joiner with the hole of GP2D120 module by using 3x10mm. screws and 3mm. nuts. Next, connect the Obtuse joiners at the end of each Straight joiner following Straight joiners and Right-angle joiners.



(3) Fix the GP2D120 structure from step (2) at the front of POP-BOT chassis by using 3x10mm. screw and 3mm. nut at the position following the photo below. Connect the GP2D120 cable to **19/SCL/A5** of POP-BOT controller board. **Now the POP-BOT with IR ranger is ready for programming.**



9.3 How to read data from GP2D120 of POP-BOT

POP-BOT has POP-168 microcontroller module. It works with Arduino software. Arduino has a special function to read the value from analog port. It is **analogRead()** function. The value in braces is analog input number (0 to 7). For POP-BOT provides only 3 to 7. The **analogRead()** function is return the integer data from 0 to 1023. It is 10-bit A/D converter result.

You can calculate the raw data in Volt unit (V) following this formula

$$\text{volt} = \text{Raw data} \times 5 / 1023$$

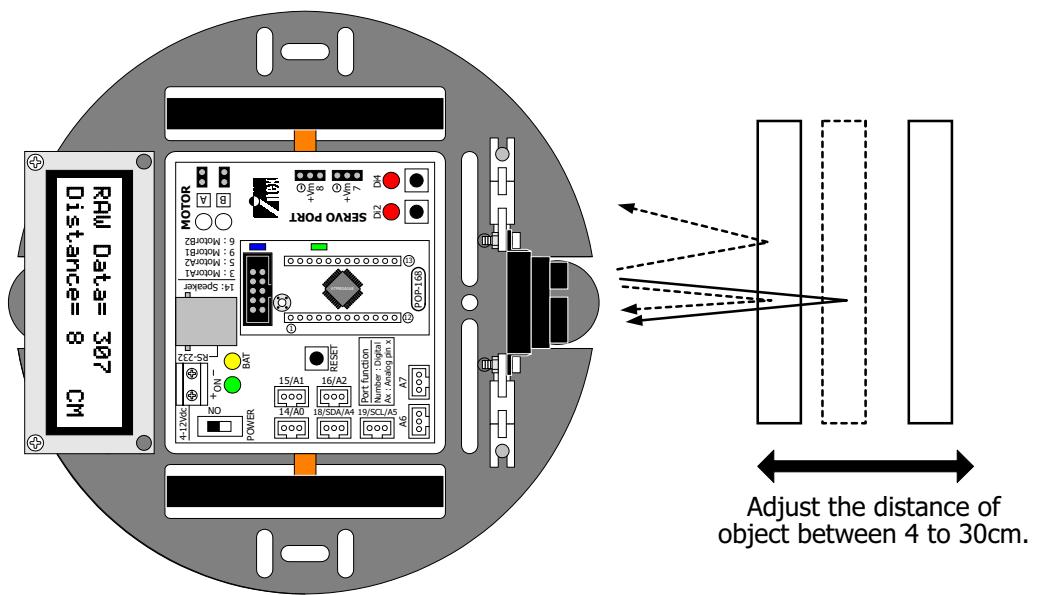
Activity 14 : Reading GP2D120 data

A14.1 Open the Arduino IDE and create the sketch code from Listing A14-1.

A14.2 Set the POP-BOT into Program mode. Upload the sketch to the robot.

A14.3 Disconnect the download cable.

A14.4 Place the POP-BOT on the table. Put an object in front of the GP2D120. Turn on the POP-BOT. Try to move an object in and out from GP2D120 sensor. Observe the result at SLCD screen.



```
*****
* POP-BOT V1.0
* Filename : GP2D120withSLCD.pde
* Show GP2D120 data on SLCD16x2 module
*****
#include <SoftwareSerial.h>
#define rxPin 16           // SLCD pin
#define txPin 16           // Same pin
SoftwareSerial MySerial = SoftwareSerial(rxPin,txPin);
int gp2;
float distance;
void setup(){
  pinMode(txPin,OUTPUT);
  MySerial.begin(9600);
  delay(1000);
}
void LCD_CMD(int Command){
  MySerial.print(0xFE,BYTE);      // Command
  MySerial.print(Command,BYTE);
}
void loop(){
  gp2=analogRead(5);
  distance=(2914/(gp2+5))-1;    // Convert to Centimetre unit
  LCD_CMD(0x80);               // Select LCD first Line
  MySerial.print("RAW Data=");   // Show raw data
  LCD_CMD(0x8A);
  MySerial.print(gp2,DEC);

  LCD_CMD(0xC0);               // Select LCD second Line
  MySerial.print("Distance=");   // Show distance in Centimetre unit
  LCD_CMD(0xCA);
  MySerial.print(distance,DEC);
  LCD_CMD(0xCE);
  MySerial.print("CM");
  delay(200);
}
```

Program description

- (1) Initial the serial data communication. Set 16/A2 pin to serial port.
- (2) Loop to read the analog signal at An5 port of POP-BOT controller board and display at SLCD screen.
- (3) Convert raw data to distance data in centimetre unit by using this formular $cm = (2914/(gp2+5)) - 1$
- (4) Convert the result to ASCII format and send to SLCD16x2 module for displaying
- (5) Loop to get data from GP2D120 every 0.2 second.

Listing A14-1 : GP2D120_LCD.pde file; the Arduino sketch file for GP2D120 reading of POP-BOT



Activity 15 : touchless object avoiding robot

With the GP2D120 module, it adds the distance measuring and Obstacle detection using infrared light feature to your robot. Your POP-BOT can avoid obstacles without having to make any physical contact.

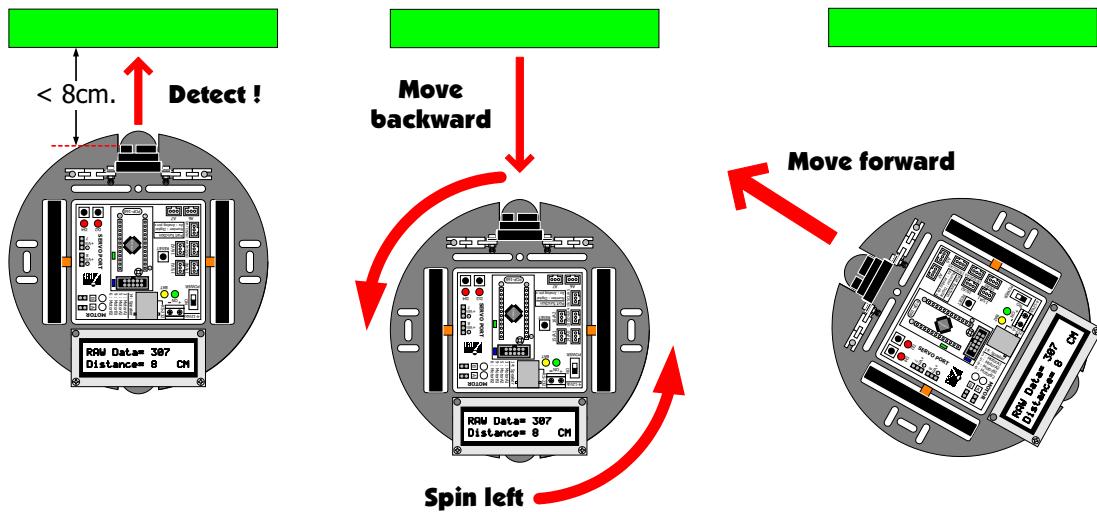
A15.1 Open the Arduino IDE and create the sketch code from Listing A15-1.

A15.2 Set the POP-BOT into Program mode. Upload the sketch to the robot.

A15.3 Disconnect the download cable.

A15.4 Place the POP-BOT on the floor. Try to place any object at the front of the robot and see its operation.

The robot will check the distance of the object in 8cm. range. If not any obstacle, robot will move forward continue. If found the object, it will move backward, turn left and move forward again.



```
/*
 * POP-BOT V1.0
 * Filename : TouchlessObjectRobot.pde
 */
int gp2;
void setup() {
    pinMode(3,OUTPUT); // sets the digital pin as output
    pinMode(5,OUTPUT);
    pinMode(6,OUTPUT);
    pinMode(9,OUTPUT);
}
void Forward(int speed) {
    analogWrite(3,speed);
    digitalWrite(5,LOW);
    analogWrite(6,speed);
    digitalWrite(9,LOW);
}
void Backward(int speed){
    analogWrite(5,speed);
    digitalWrite(3,LOW);
    analogWrite(9,speed);
    digitalWrite(6,LOW);
}
void Spin_Left(int speed){
    analogWrite(3,speed);
    digitalWrite(5,LOW);
    analogWrite(9,speed);
    digitalWrite(6,LOW);
}
void loop(){
    int i;
    for (i=0;i<5;i++){ // Loop 5 times for noise filter
        gp2=(gp2+analogRead(5));
    }
    gp2=gp2/5;
    if (gp2>290){ // Found object
        Backward(200); // Move backward to change direction
        delay(300);
        Spin_Left(200); // Change direction
        delay(350);
    } else{
        Forward(200); // Moving forward
    }
}
```

Program description

- (1) Starting, POP-BOT beep at once. You can use this signal to check the RESET state of robot when its battery is low. If the robot beep during movement, it means robot's battery is low.
- (2) Read value from GP2D120 to store into **gp2** variable 5 times. Calcultes to get the average value for protecting the error reading from movement.
- (3) Check the **gp2** value more than 290 or not ?. If yes, it means now robot far from object less than 8cm. (approximation). Program will control the robot to move backward 0.25 second and spin left 0.5 second to change the direction for avoiding the object.
- (4) If **gp2** value is less than 290, robot still moves forward.

Listing A15-1 : Robot_Survey.pde file; the Arduino sketch file for POP-BOT touchless object avoiding demonstration



10 : POP-BOT with Servo motor activity

POP-BOT features more of the RC servo motor output. POP-BOT can drive 2 of small RC servo motors simultaneously. POP-BOT controller supplies the servo motor supply voltage to Servo output headers already. User does not require additional batteries for servo motor. It is important features of POP-BOT robot. POP-BOT can drive 4 motors; 2 of DC motors and 2 of servo motors.

10.1 Servo motor introduction

Figure 10-1 shows a drawing of a Standard Servo. The plug is used to connect the servo motor to a power source (V_{dd} and V_{ss}) and a signal source (a microcontroller I/O pin). The cable conducts V_{dd} , V_{ss} and the signal line from the plug into the servo motor. The horn is the part of the servo that looks like a four-pointed star. When the servo is running, the horn is the moving part that the microcontroller controls. The case contains the servo's control circuits, a DC motor, and gears. These parts work together to take high/low signals from the microcontroller and convert them into positions held by the servo horn.

Figure 10-2 shows the servo motor cable assignment. It has 3 wires with difference color; Black for GND or V_{ss} or Negative pole, Red for V_{dd} or Servo motor supply voltage and White (sometime is yellow or brown) wire for signal.

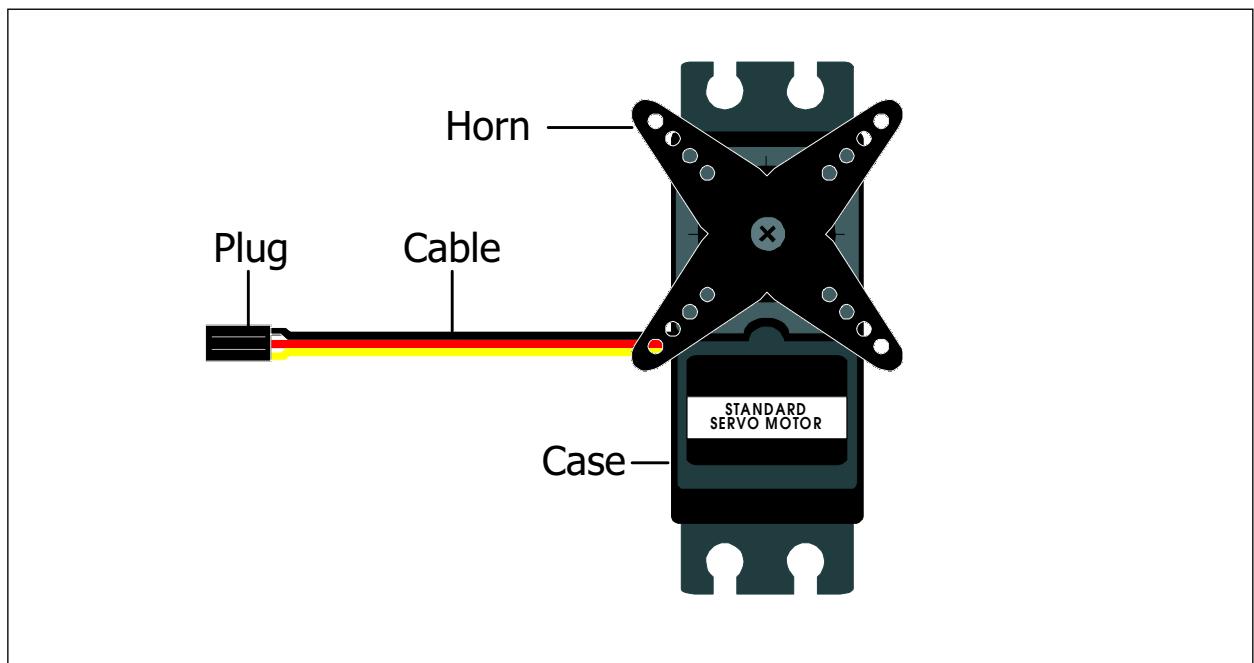


Figure 10-1 Standard servo motor physical

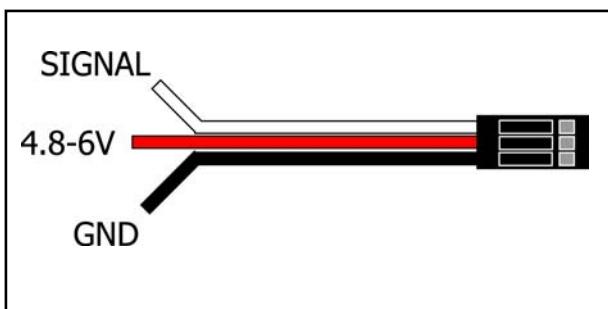


Figure 10-2 Standard Servo motor cable assignment

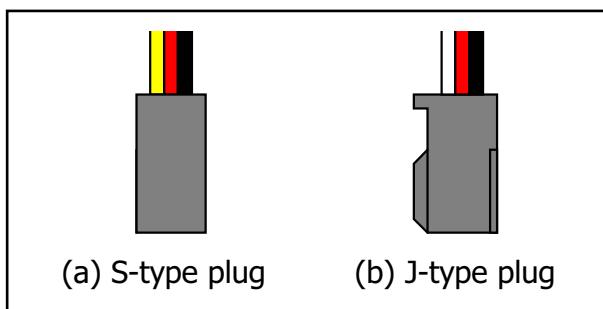


Figure 10-3 Standard Servo motor plug type

The servo motor plug standard has 2 types; S-type and J-type are shown in the figure 10-3.

Controlling of the servo motors is used using pulse controlling. The control pulse is positive going pulse with length of 1 to 2 ms which is repeated about 50 to 60 times a second. You can check the details in the figure 10-4. Start with generate pulse with period 20 millisecond and adjust the positive pulse width 1 millisecond. The servo motor move horn to last left position. The pulse width 1.5 millisecond move the servo horn to center and pulse width 2 millisecond cause servo horn to last right position.

*The important specification of servo motor are 2 points as **Speed** or Servo turn rate or transit time and **Torque**. The servo turn rate, or transit time, is used for determining servo rotational velocity. This is the amount of time it takes for the servo to move a set amount, usually 60 degrees. For example, suppose you have a servo with a transit time of 0.17sec/ 60 degrees at no load. This means it would take nearly half a second to rotate an entire 180 degrees. More if the servo were under a load. This information is very important if high servo response speed is a requirement of your robot application. It is also useful for determining the maximum forward velocity of your robot if your servo is modified for full rotation. Remember, the worst case turning time is when the servo is at the minimum rotation angle and is then commanded to go to maximum rotation angle, all while under load. This can take several seconds on a very high torque servo.

Torque is the tendency of a force to rotate an object about an axis. The torque unit is **ounce-inches (oz-in)** or **kilogram-centimetre (kg-cm)**. It tell you know about this servo motor can drive a load weight in 1 oz. to move 1 inche or 1kg. weight to moved 1 centimeter (1oz. = 0.028kg. or 1kg. = 25.274oz.). Normally the RC servo motor has 3.40 kg-cm/47oz-in torque.

* http://www.societyofrobots.com/actuators_servos.shtml

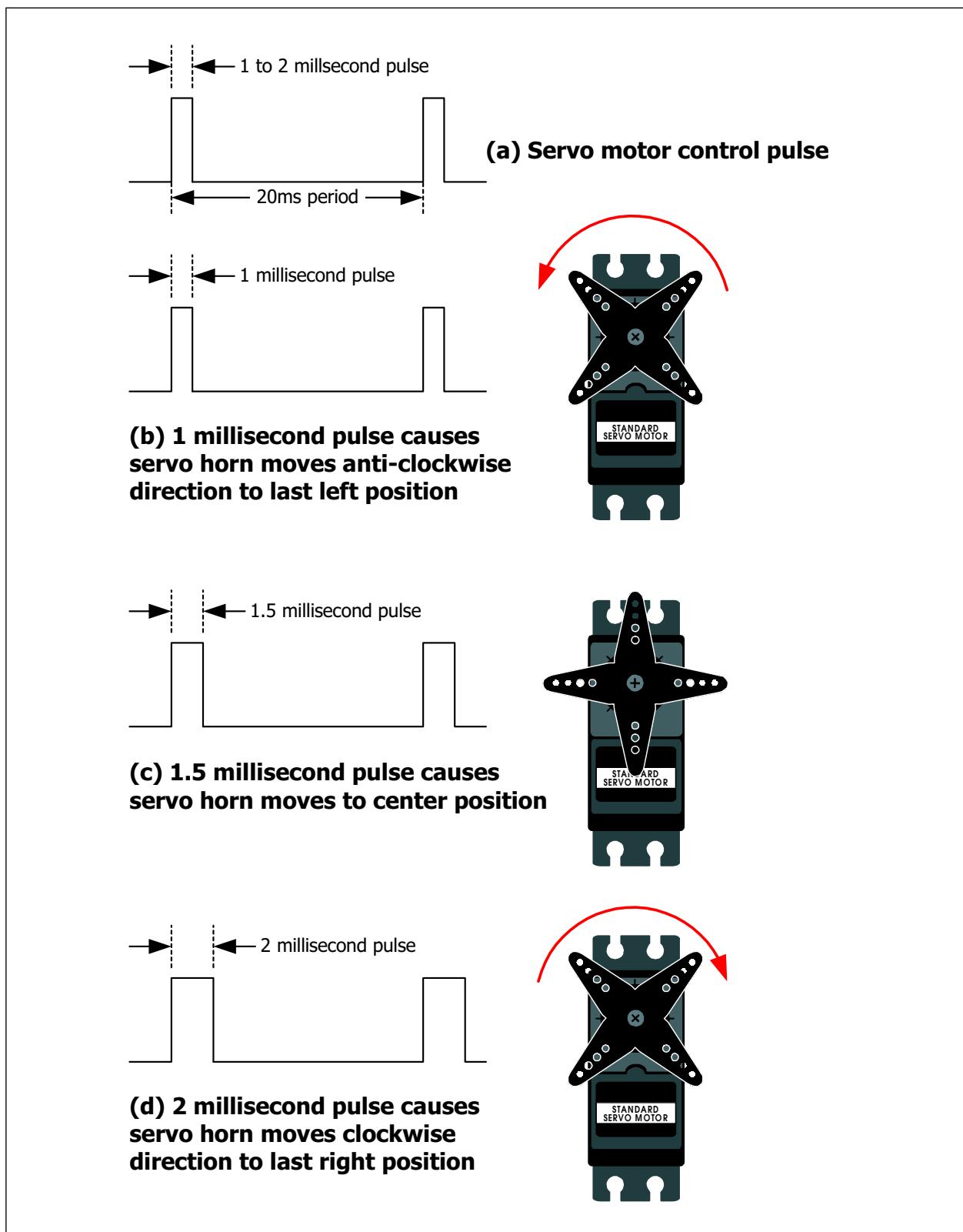


Figure 10-4 Timing diagram of pulse control servo motor

10.2 Arduino with Controlling servo motor *

The heart of controlling the servo motor of Arduino POP-168 is SoftwareServo library. Because POP-BOT hardware does not use the PWM pin to make the servo motor output. We use general purpose port to servo output; Di7 and Di8.

The SoftwareServo library can drive servos on all of your pins simultaneously. The API is patterned after the wiring.org servo library but the code is different. You are not limited to 8 servos, but you must call the **SoftwareServo :: refresh()** method at least once every 50ms or so to keep your servos updating.

10.2.1 Standard Methods

attach(int)

Turn a pin into a servo driver. Calls pinMode. Returns 0 on failure.

detach()

Release a pin from servo driving.

write(int)

Set the angle of the servo in degrees, 0 to 180.

read()

return that value set with the last write().

attached()

return 1 if the servo is currently attached.

10.2.2 Extra Methods

refresh()

You must call this at least once every 50ms to keep the servos updated. You can call it as often as you like, it won't fire more than once every 20ms. When it does fire, it will take from .5 to 2.5 milliseconds to complete, but won't disable interrupts.

setMinimumPulse(uint16_t)

set the duration of the 0 degree pulse in microseconds. (default minimum value is 544 microseconds)

setMaximumPulse(uint16_t)

set the duration of the 180 degree pulse in microseconds. (default maximum pulse value is 2400 microseconds)

* <http://www.arduino.cc/playground/ComponentLib/Servo>

10.2.3 Safety Quirk

Even though you attach a servo, it won't receive any control signals until you send its first position with the **write()** method to keep it from jumping to some odd arbitrary value.

10.2.4 Size

The library takes about 850 bytes of flash and 6+(8 x servos) bytes of SRAM.

10.2.5 Limitations

This library does not stop your interrupts, so **millis()** will still work and you won't lose incoming serial data, but a pulse end can be extended by the maximum length of your interrupt handles which can cause a small glitch in the servo position. If you have a large number of servos there will be a slight (1 to 3 degrees) position distortion in the ones with the lowest angular values.

10.2.6 An Example

The following code lets you control Servo on pin7 by potentiometer on analog 2

```
#include <SoftwareServo.h>
SoftwareServo myservo; // create servo object to control a servo
int potpin = 2; // analog pin used to connect the potentiometer
int val; // variable to read the value from the analog pin
void setup() {
    myservo.attach(7);
    // attaches the servo on pin 7 to the servo object
}

void loop() {
    val = analogRead(potpin);
    // reads the value of the potentiometer (value between 0 and 1023)
    val = map(val, 0, 1023, 0, 179);
    // scale it to use it with the servo (value between 0 and 180)
    myservo.write(val);
    // sets the servo position according to the scaled value
    delay(15); // waits for the servo to get there

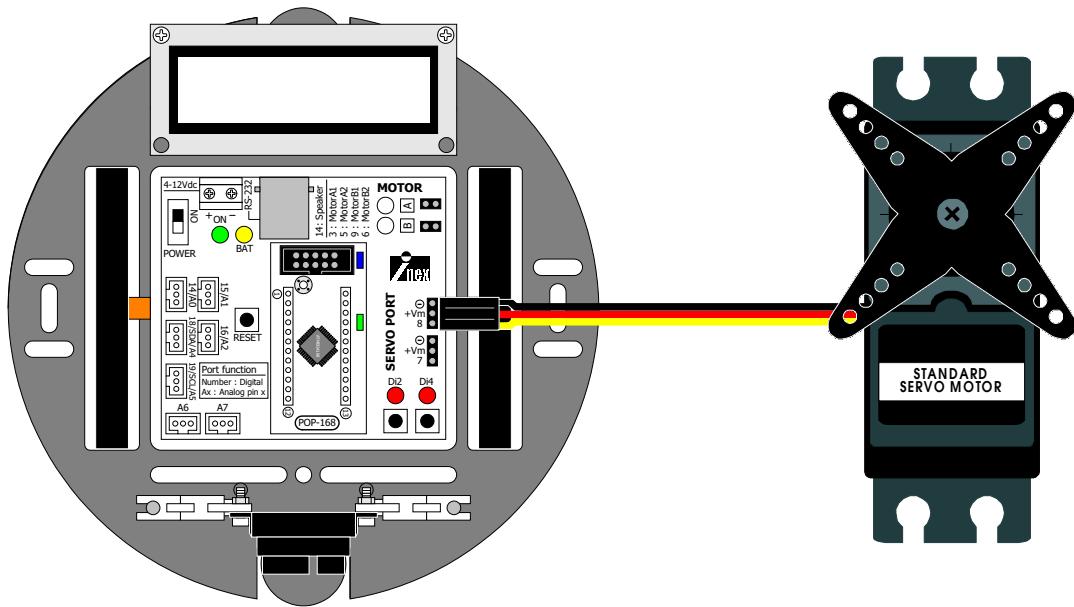
    SoftwareServo::refresh();
}
```

Activity 16 : POP-BOT controls servo motor

This activity demonstrates the simple example about control the standard RC servo motor with POP-BOT controller board.

Activity 16-1 Simple servo controlling

- A16.1 Open the Arduino IDE and create the sketch code from Listing A16-1.
- A16.2 Set the POP-BOT into Program mode. Upload the sketch to the robot.
- A16.3 Disconnect the download cable.
- A16.4 Connect the standard RC servo motor to SERVO PORT 7 or 8 of POP-BOT controller board.



- A16.5 Turn on the POP-BOT. See its operation.

After power-on, Servo motor is driven by POP-BOT. The horn motion is moving from last left to last right position and back to last left position continually.

```
*****  
* POP-BOT V1.0  
* Filename : SimpleServo.pde  
* Simple servo motor controlling  
*****  
int i;  
  
void setup(){  
//---- Servo Motor ----//  
    pinMode(8,OUTPUT);           // Servo Motor  
    pinMode(7,OUTPUT);           // Servo Motor  
}  
void loop(){  
    for (i=0;i<100;i++){  
        digitalWrite(7, HIGH);      // Set Servo Di7  
        digitalWrite(8, HIGH);      // Set Servo Di8  
        delayMicroseconds(500);     // Positive Delay  
        digitalWrite(7,LOW);  
        digitalWrite(8,LOW);  
        delay(20);                 // Negative delay  
    }  
    for (i=0;i<100;i++){  
        digitalWrite(7, HIGH);      // Set Servo Di7  
        digitalWrite(8, HIGH);      // Set Servo Di8  
        delayMicroseconds(2300);    // Positive delay  
        digitalWrite(7,LOW);  
        digitalWrite(8,LOW);  
        delay(20);                 // Negative delay  
    }  
}
```

Listing A16-1 : SimpleServo.pde file; the Arduino sketch file for POP-BOT control servo motor demonstration



Activity 16-2 : POP-BOT button control servo motor

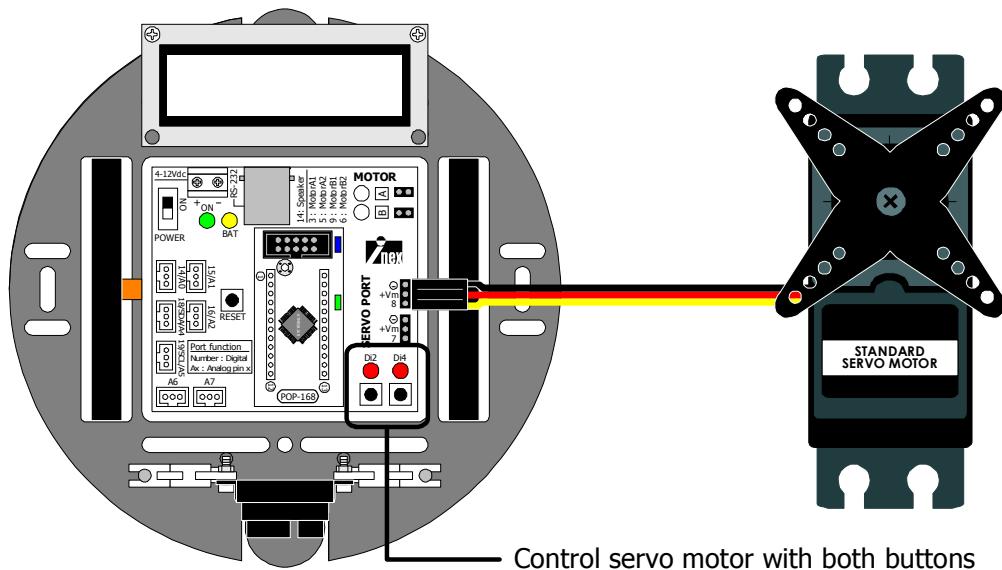
This activity add more codes to improve the controlling servo motor by buttons on POP-BOT controller board .

A16.6 Open the Arduino IDE and create the sketch code from Listing A16-2.

A16.7 Set the POP-BOT into Program mode. Upload the sketch to the robot.

A16.8 Disconnect the download cable.

A16.9 Connect the standard RC servo motor to SERVO PORT 7 or 8 of POP-BOT controller board.



A16.10 Turn on the POP-BOT. Press the button at Di2 and Di4 and see the servo motor operation.

Di2 button is used to control Servo motor moving to last right position.

Di4 button is used to control Servo motor moving to last left position.

When the servo horn moves to the last ending, POP-BOT will beep a sound to inform user know about the final position.

You can press and hold or press and release to control servo position.

```

/*
 * POP-BOT V1.0
 * Filename : SwitchControlServo.pde
 * Control a servo motor with 2 button switches at Di2 and Di4. Show on SLCD
 */
#include <SoftwareSerial.h>
#define rxPin 16
#define txPin 16
SoftwareSerial MySerial = SoftwareSerial(rxPin,txPin);
int Old_i,i=1500,j=0,k;

void setup(){
    pinMode(8,OUTPUT);           // Servo Motor
    pinMode(7,OUTPUT);           // Servo Motor
    pinMode(14,OUTPUT);          // PIEZO Speaker
    pinMode(2,INPUT);            // Left Switch
    pinMode(4,INPUT);            // Right Switch
    pinMode(txPin,OUTPUT);       // SLCD pin
    MySerial.begin(9600);        // Communicate With SLCD
    delay(1000);
    i=1500;                      // Centre value for Servo Motor
}
void loop(){
    if(digitalRead(2)==0){
        if(i<2500){
            i+=20;
        }
        else {Beep();}
    }
    if(digitalRead(4)==0){
        if(i>400){
            i-=20;
        }
        else {Beep();}
    }
    if (i!=Old_i){
        MySerial.print(0xFE,BYTE); // Clear Screen
        MySerial.print(0x01,BYTE);
        MySerial.print(i,DEC);     // Show position on LCD
        Old_i =i ;
    }
    digitalWrite(7, HIGH);        // Set Servo Di7
    digitalWrite(8, HIGH);        // Set Servo Di8
    delayMicroseconds(i);         // Positive pulse delay
    digitalWrite(7,LOW);
    digitalWrite(8,LOW);
    delay(20);                  // Negative pulse delay
}
void Beep(){
    int i;
    for (i=0;i<600;i++){
        digitalWrite(14,HIGH);
        delayMicroseconds(150);
        digitalWrite(14,LOW);
        delayMicroseconds(150);
    }
}

```

Listing A16-2 :SwitchControlServo.pde file; the Arduino sketch file for POP-BOT control servo motor by buttons demonstration

Programming operation

Purpose of this activity is demonstrates the controlling servo motor position by Pushing the buttons. We need to add 2 buttons to change the servo motor position and send the position value to display in Serial LCD of POP-BOT. You can use this value for a reference for servo motor controlling.

The code will check the button pressing both Di2 and Di4 port. If the button at Di2 is pressed, i variable will increase value each 20. If the button at Di4 is pressed, i variable will decrease value each 20. The variable value is used to define the pulse width of servo motor controlling.

When the value is changed to last ending position (both maximum and minimum), beep function will be executed to drive a beep signal to inform developer to know the operation.



11 : POP-BOT object seeking ability

From chapter 10, we learn about how to control servo motor with our POP-BOT. The important factor is SoftwareServo library. In this chapter will concentrate about servo motor control and sensor reading application. The sensor that is used in this chapter is GP2D120. We will modify POP-BOT to Object seeking mobile robot.

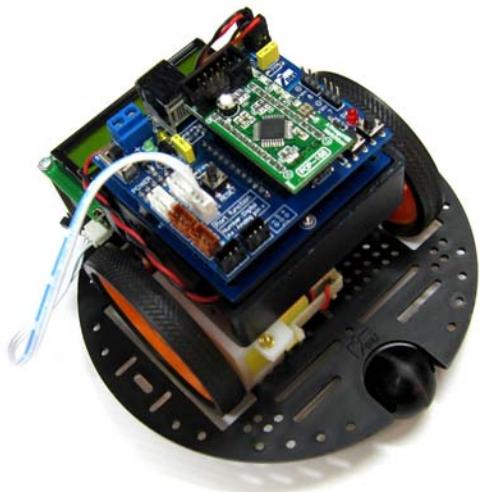
11.1 POP-BOT modification to Object seeking mobile robot.

11.1.1 Additional part list

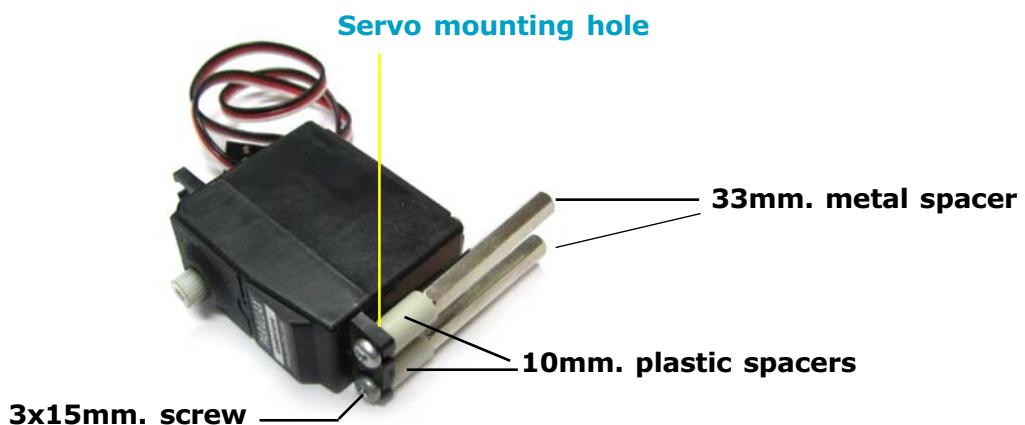


11.1.2 Modify procedure

(1) Remove all sensors from POP-BOT chassis. Now we have the simplest form of the POP-BOT mobile robot.



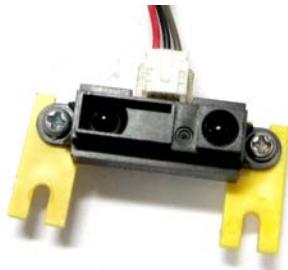
(2) Remove the servo horn. Attach 2 of 33mm. metal spacers and 10mm. plastic spacers with both mounting holes of servo motor by using 3x15mm. screws following the photo that is shown below.



(3) Mount the servo motor that is attached spacers from step (2) with the robot chassis at the front by using 3x10mm.screws. Tighten the screws from bottom.



(4) Attach 2 pieces of Straight joiner with the hole of GP2D120 module by using 3x10mm. screws and 3mm. nuts.



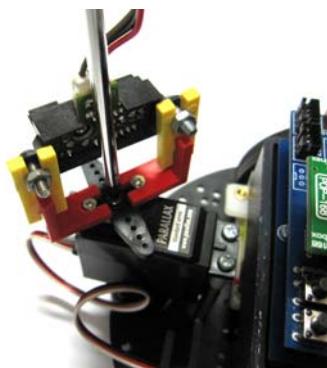
(5) Attach 2 pieces of Right -angle joiner with the servo horn at the inside hole position by using 2mm. self-tapping screws.



(6) Connect the GP2D120 structure from step (4) at the end of Right-angle joiners.



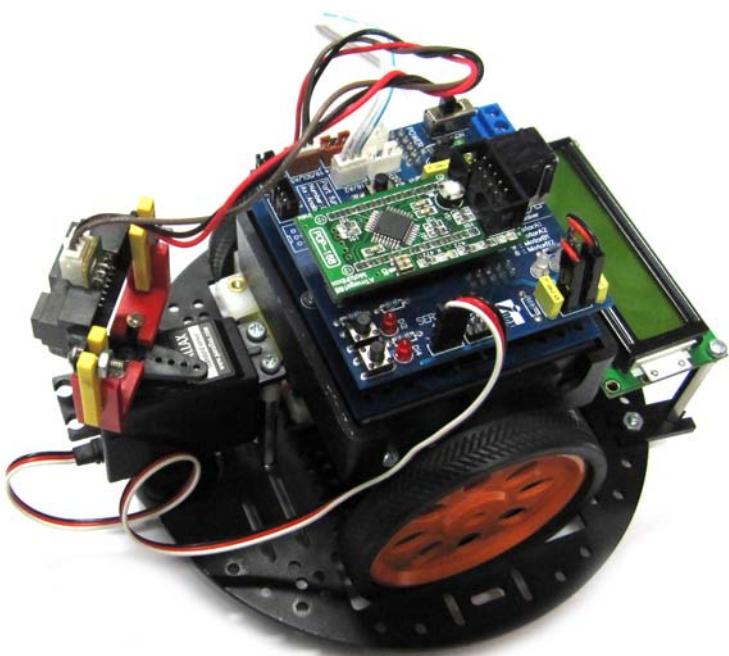
(7) Attach the GP2D120 and servo horn structure from step (6) with servo shaft. Tighten it with a servo screw.



(8) Connect the servo motor plug to Servo out port 7. Be sure the servo motor plug correctly. Lastly, connect GP2D120 to 19/SCL/A5 port of POP-BOT.

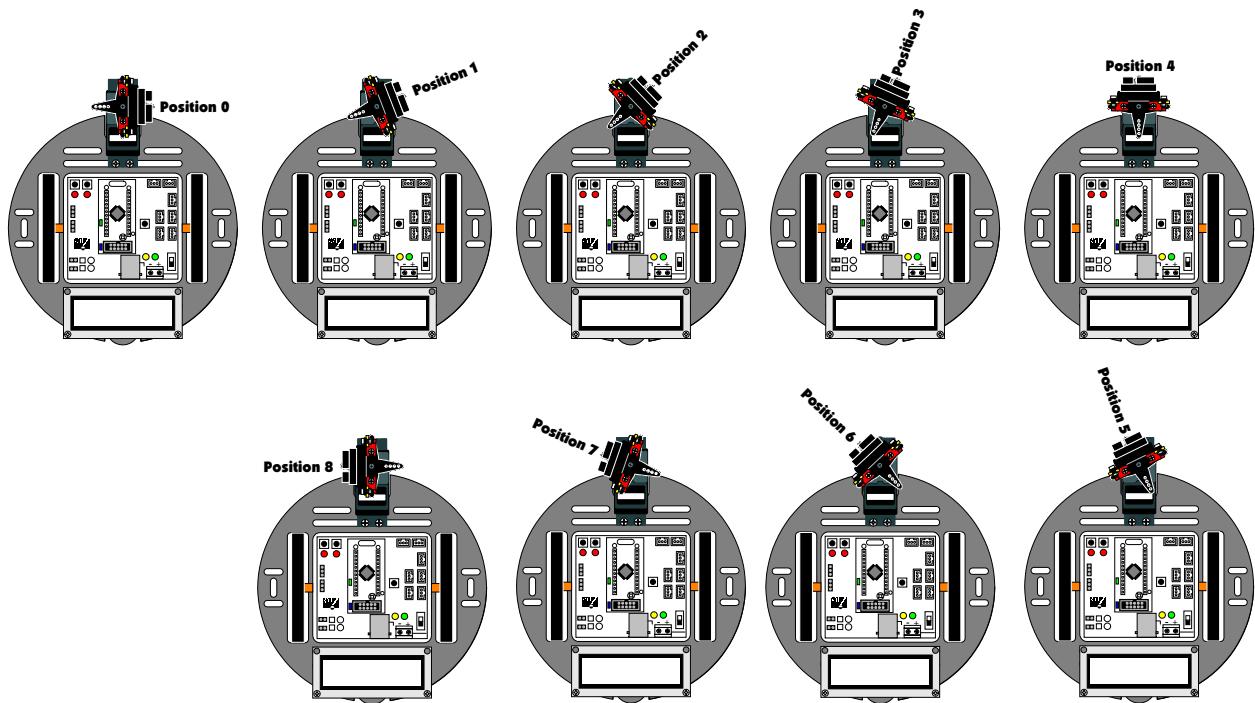


(9) Now the POP-BOT is modified and ready for programming.



Activity 17 : POP-BOT Object seeking

This activity demonstrates how to seek an object by moving the servo motor. The POP-BOT that is attached the GP2D120 with servo motor horn will move the servo and check the distance from sensor to the target object. There is 9 steps in moving and checking following the illustration below.



POP-BOT will read the sensor detection value in each step and show on the SLCD16x2 screen. After checking all 9 positions, the controller will select the highest value as result. Because sensor gives the highest value at target position. Thus, the result of this activity is POP-BOT can detect the right direction of target object.

A17.1 Open the Arduino IDE and create the sketch code from Listing A17-1.

A17.2 Set the POP-BOT into Program mode. Upload the sketch to the robot.

A17.3 Disconnect the download cable.

A17.4 Set the target object position. For example 67.5 degree angle and 15 cm. far from POP-BOT.

```

 ****
 * POP-BOT V1.0
 * Filename : SeekingObject.pde
 * Moves servo and seek object position to show the result on SLCD
 ****
#include <SoftwareSerial.h>
#define rxPin 16
#define txPin 16
SoftwareSerial MySerial = SoftwareSerial(rxPin,txPin);
int PosValue[] = {460,610,760,1050,1340,1500,1660,1940,2220};
                                         // Servo position value
int GP2[9];
int j,Maximum,MAX_Point;

void setup() {
//---- Servo Motor ----//
    pinMode(7,OUTPUT);                      // Servo Motor
    pinMode(14,OUTPUT);                     // PIEZO Speaker
    pinMode(txPin,OUTPUT);                  // SLCD pin
    MySerial.begin(9600);                   // Communication With SLCD
    delay(1000);
    LCD_Clear();                           // LCD Clear Screen
}
void loop(){
    for(j=0;j<9;j++) {                    // Check 9 positions
        Servo_Move(PosValue[j]);          // Move servo motor
        GP2[j]=analogRead(5);            // Read value from GP2D120
        LCD_Clear();
        LCD_Show_Text(0x80,"Position");
        LCD_Show(0x89,j);
        LCD_Show_Text(0x8A,:= );
        LCD_Show(0x8D,GP2[j]);           // Show value on SLCD
        delay(1000);
    }
    MAX_Point = GET_Point();
    Servo_Move(PosValue[MAX_Point]);
        // Move servo to target poition.
        // It is selected from the most of 9 sensor values
    LCD_Clear();
    LCD_Show_Text(0x80,"Selected :");     // Show maximum value
    LCD_Show(0x8A,MAX_Point);
    LCD_Show_Text(0xC0,"Value = ");
    LCD_Show(0xC8,Maximum);
    Beep();delay(5000);
    LCD_Clear();                         // Clear LCD screen
}

/** Calculate target position ***/
int GET_Point(){
    int i,Old=0,max_;
    for(i=0;i<9;i++){
        if(GP2[i]>Old){
            Old=GP2[i];
            max_=i;
        }
    }
    Maximum=Old;
    return(max_);
}

```

```

/** Servo position control */
void Servo_Move(int val){
    int i;
    for(i=0;i<20;i++){
        digitalWrite(7, HIGH);           // Set port 7 to servo port
        delayMicroseconds(val);         // Positive pulse delay
        digitalWrite(7,LOW);
        delay(20);                     // Negative pulse delay
    }
}

/** Beep function */
void Beep(){
    int i;
    for (i=0;i<600;i++){
        digitalWrite(14,HIGH);
        delayMicroseconds(150);
        digitalWrite(14,LOW);
        delayMicroseconds(150);
    }
}

/** SLCD Function */
void LCD_Show(int Position,int x){
    MySerial.print(0xFE,BYTE);          // Clear Screen
    MySerial.print(Position,BYTE);
    MySerial.print(x,DEC);             // Show Data in Decimal
}
void LCD_Show_Text(int Position,char* x){
    MySerial.print(0xFE,BYTE);          // Clear Screen
    MySerial.print(Position,BYTE);
    MySerial.print(x);                // Show text
}
void LCD_Clear(){
    MySerial.print(0xFE,BYTE);          // Clear Screen
    MySerial.print(0x01,BYTE);
}
/*****************************************/

```

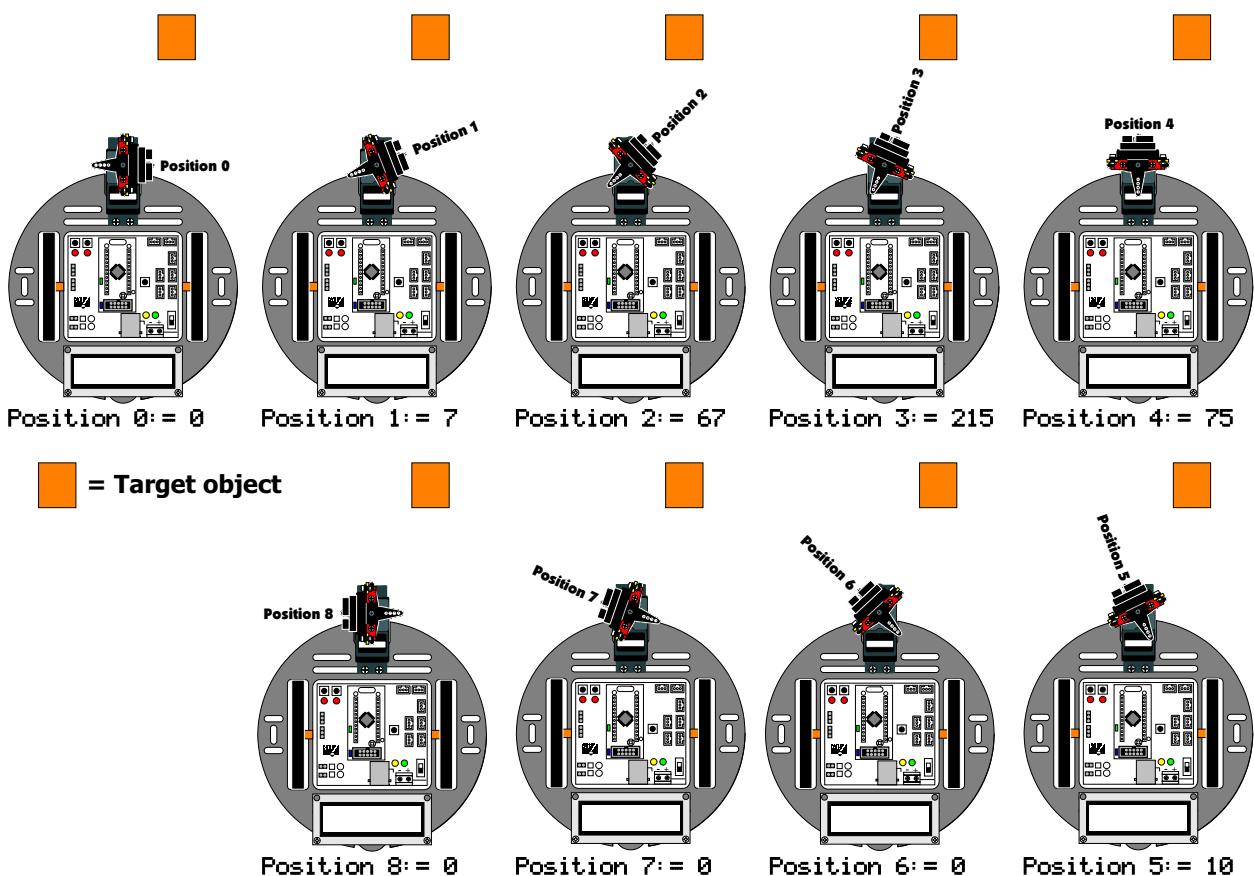
Listing A17-1 : SeekingObjectTest.pde file; the Arduino sketch file for POP-BOT object seeking operation testing.

A17.5 Turn on the POP-BOT. See its operation.

After turning on the power, POP-BOT will drive servo to move the GP2D120 to last right position; Position 0. It's 0 degree angle. POP-BOT controller reads data from GP2D120 and show on the SLCD16x2 screen as follows :

Position 0 := 0 (value can change in any robot)

Next, POP-BOT drives the GP2D120 structure to Position 1 (22.5 degree angle) and reads sensor value and shows on the SLCD screen. The robot will do same until Position 8.



After that, controller will select the highest value position to shows on SLCD Screen as follows :

Selected : 3

Value = 215

It means POP-BOT detects the object at position 3. The angle is about 67.5 degree.



Activity 18 : POP-BOT Ball seeker

This activity is modified from Activity 17. We apply the code to real world application. The POP-BOT moves and seeks the target object; the ball. The mission will be complete when POP-BOT moves to the ball position, stop and beep.

A18.1 Open the Arduino IDE and create the sketch code from Listing A18-1.

A18.2 Set the POP-BOT into Program mode. Upload the sketch to the robot.

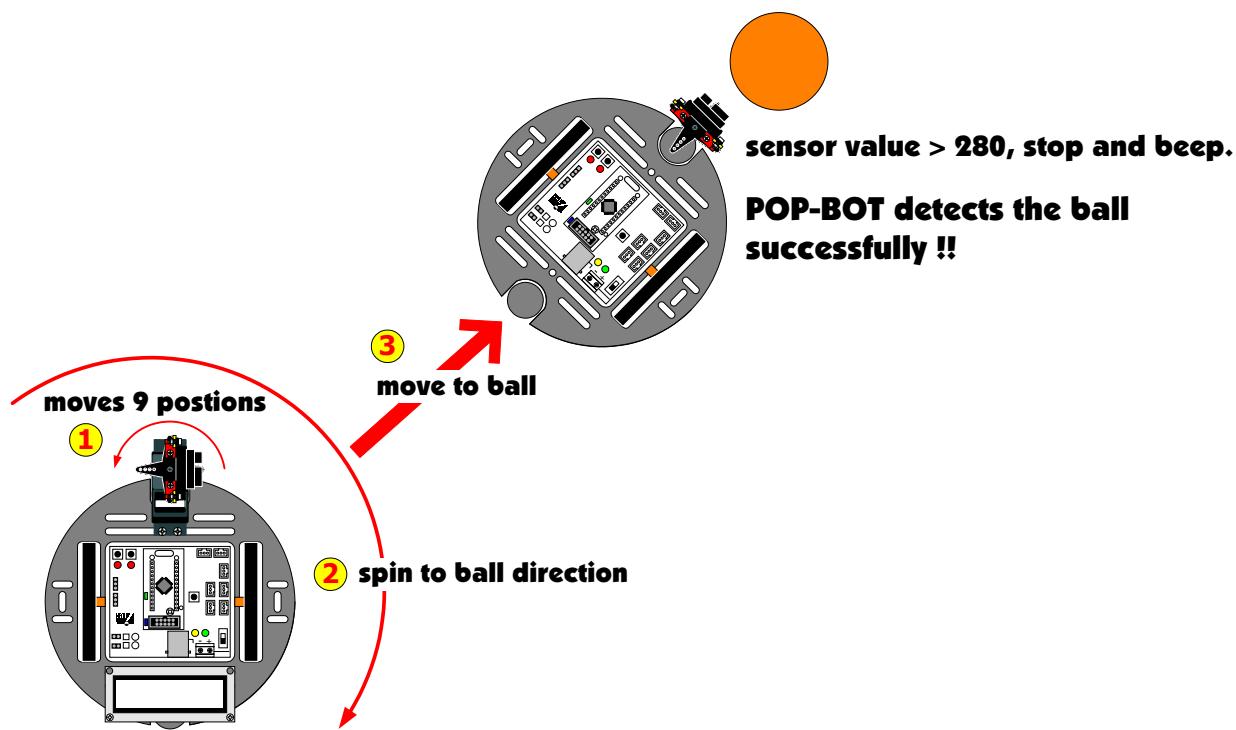
A18.3 Disconnect the download cable.

A18.4 Set the target object position freely on the field. Place the POP-BOT on the field. Turn on and observe operation.

POP-BOT starts with driving the servo motor to seek the ball. The seeking is similar the Activity 17 operation but faster and do not display the value to SLCD. POP-BOT will move to direction that gives the sensor value maximum.

If the sensor value is lower than 20, it's mean no any object on this direction. POP-BOT will turn around to change the opposite direction.

Addition POP-BOT will compare the sensor value as more than 280, it's mean POP-BOT hold the ball ready. Because value over 280 is very near distance from POP-BOT and ball. If the sensor value does not reach to 280, the POP-BOT still seek the ball with same operation.



```

 ****
 * POP-BOT V1.0
 * Filename : BallSeekerRobot.pde
 * Seek ball and move to it.
 ****
int PosValue[] = {460,610,760,1050,1340,1500,1660,1940,2220}; // Servo position value
int GP2[9];
int j,Maximum,Position;

void setup() {
    pinMode(3,OUTPUT); // Motor A1
    pinMode(5,OUTPUT); // Motor A2
    pinMode(6,OUTPUT); // Motor B2
    pinMode(9,OUTPUT); // Motor B1
    pinMode(7,OUTPUT); // Servo Motor
    pinMode(14,OUTPUT); // PIEZO Speaker
    Beep();
    delay(2000);
}

void loop(){
    Motor_Stop();
    Servo_Home();
    for(j=0;j<9;j++){ // Set the seeking point 9 positions
        Servo_Move(PosValue[j]); // Move servo motor
        GP2[j]=analogRead(5); // Read valei from GP2D120
    }
    Position=MAX_Point(); // Check lost object condition
    if(Maximum<20){
        Spin_Right(150);delay(600); // Turn around if value < 20.
    }
    else if(Maximum>280){ // Check ball position
        Servo_Move(PosValue[MAX_Point()]);
        Beep(); // Beep to finish
        while(1);
    }
    else{
        switch(Position){ // Seeking routine
            case 0: Spin_Right(200);
                      delay(320);
                      Forward(200);
                      delay(400-Maximum);
                      break;
            case 1: Spin_Right(200);
                      delay(240);
                      Forward(200);
                      delay(400-Maximum);
                      break;
            case 2: Spin_Right(200);
                      delay(160);
                      Forward(200);
                      delay(400-Maximum);
                      break;
            case 3: Spin_Right(200);
                      delay(80);
                      Forward(200);
                      delay(400-Maximum);
                      break;
        }
    }
}

```

```

        case 4: Forward(200);
        delay(400-Maximum);
        break;
    case 5: Spin_Left(200);
        delay(80);
        Forward(200);
        delay(400-Maximum);
        break;
    case 6: Spin_Left(200);
        delay(160);
        Forward(200);
        delay(400-Maximum);
        break;
    case 7: Spin_Left(200);
        delay(240);
        Forward(200);
        delay(400-Maximum);
        break;
    case 8: Spin_Left(200);
        delay(320);
        Forward(200);
        delay(400-Maximum);
    }
}

/** Calculate the selected position **/
int MAX_Point(){
    int i,Old=0,max_;
    for(i=0;i<9;i++){
        if(GP2[i]>Old){
            Old=GP2[i];
            max_=i;
        }
    }
    Maximum=Old;
    return(max_);
}

/** Servo position control **/
void Servo_Home(){
    Servo_Move(460);
    Servo_Move(460);
    Servo_Move(460);
    Servo_Move(460);
}
void Servo_Move(int val){
    int i;
    for(i=0;i<5;i++){
        digitalWrite(7, HIGH);           // Set port 7 to Servo output port
        delayMicroseconds(val);         // Positive pulse delay
        digitalWrite(7,LOW);
        delay(20);                     // Negative pulse delay
    }
}

```

```
void Forward(int speed){  
    analogWrite(3,speed);  
    digitalWrite(5,LOW);  
    analogWrite(6,speed);  
    digitalWrite(9,LOW);  
}  
void Motor_Stop(){  
    digitalWrite(3,LOW);  
    digitalWrite(5,LOW);  
    digitalWrite(6,LOW);  
    digitalWrite(9,LOW);  
}  
void Spin_Left(int speed){  
    analogWrite(5,speed);  
    digitalWrite(3,LOW);  
    analogWrite(6,speed);  
    digitalWrite(9,LOW);  
}  
void Spin_Right(int speed){  
    analogWrite(3,speed);  
    digitalWrite(5,LOW);  
    analogWrite(9,speed);  
    digitalWrite(6,LOW);  
}  
  
/** Beep function **/  
void Beep(){  
    int i;  
    for (i=0;i<600;i++){  
        digitalWrite(14,HIGH);  
        delayMicroseconds(150);  
        digitalWrite(14,LOW);  
        delayMicroseconds(150);  
    }  
}
```

Listing A18-1 : BallSeekerRobot.pde file; the Arduino sketch file for POP-BOT to seek and catch the ball

