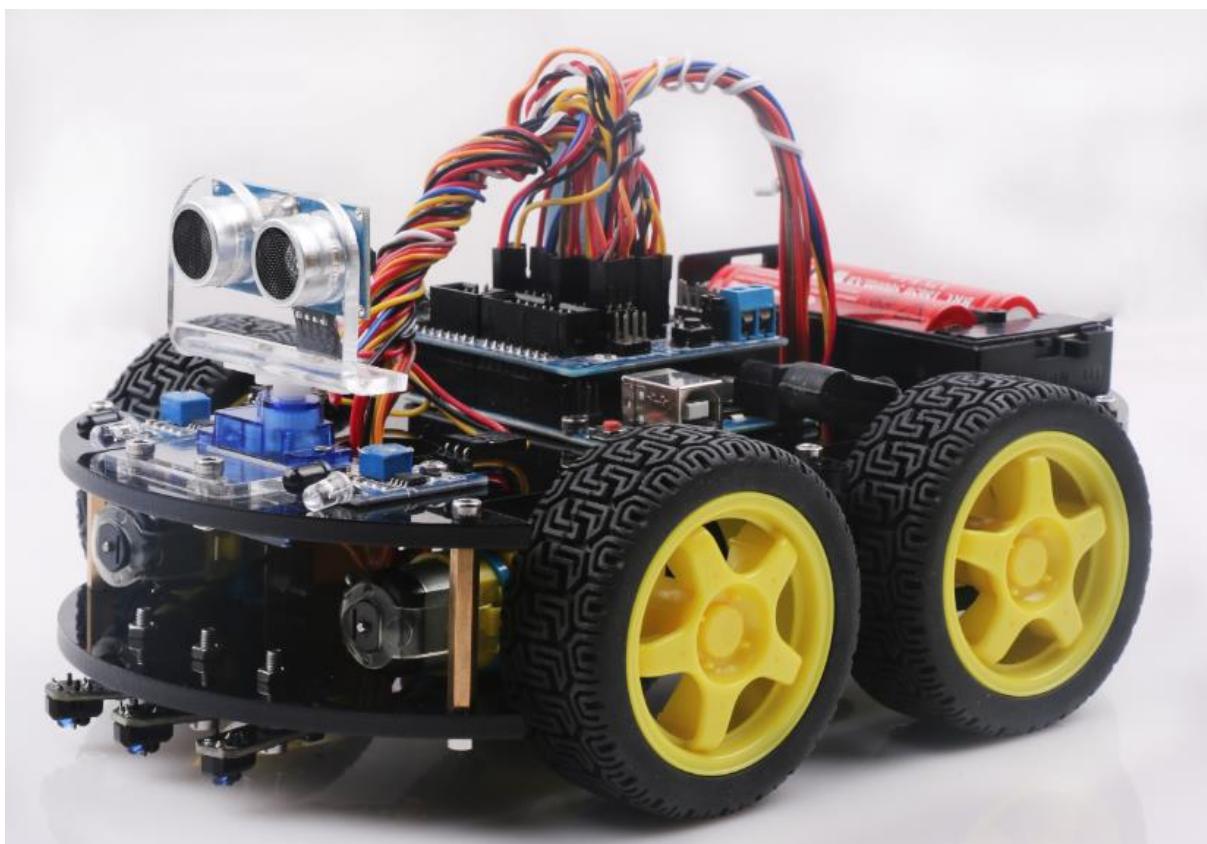


# Hummer-Bot V2.0

## Instruction Manual



Github <https://github.com/keywish/keywish-hummer-bot-v2.0>

Data	Version	Description	Author
2017/9/16	V-1.0	Create	Baron. li
2017/9/23	V-1.1	modify	Ken. chen
2017/10/18	V-1.2	Review	Ken. chen
2017/11/15	V-1.3	Review	Zach. zhou
2017/12/8	V-1.4	Review	Baron. li
2018/3/11	V-1.5	Modifyir/bluetooth module	Ken. chen
2018/4/20	V-1.6	Add device instructions	Baron. li
2018/5/3	V-1.7	Add installation details picture	Baron. li
2018/7/1	V-2.0	Update component list	Ken. chen

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## Chapter1 Introduction

### 1.1 Writing Purpose

The purpose of this manual is to create a fast, practical and convenient development learning platform for the vast number of electronic enthusiasts and let them grasp the Arduino and its extended system design methods and design principles, as well as the corresponding hardware debugging methods.

This manual will lead you to learn every function of "Hummer-Bot" step by step and open a new "Hummer-Bot" journey for you. It is divided into two parts:

1, Preparation chapter, which mainly introduces the use of common Arduino development software and some downloading and debugging skills.

2, Experiment chapter, which contains hardware and software, the former mainly introduces the function and principle of each module; the latter mainly introduces each part of the program and leads you to understand and grasp the principle of Arduino and the car development through written examples step by step.

This manual is a specifications for "Hummer-Bot" , the file whose format is PDF which is in the CD along with our product requires the corresponding software to open. It contains detailed schematic diagrams and complete source codes for all instances, the codes won't have any mistake under our strict test. In addition, the library files used in the source codes are put into the corresponding path, you only need to see corresponding phenomenon of the car and personally experience the process of experiment by downloading the source codes to Arduino via the serial port emulator.

This manual is very suitable for students and electronic enthusiasts to learn, all course videos will be synchronized to <https://github.com/keywish/keywish-hummer-bot-v2.0> , please real-time synchronization of the latest information

### 1.2 Product Introduction

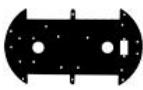
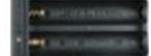
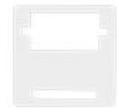
"Hummer-Bot" is a multifunctional car based on the Arduino UNO and L298N motor. Compared with the traditional car, "Hummer-Bot" is also equipped with wireless control (Bluetooth, infrared, WIFI and so on); ultrasonic; infrared. It can trace and avoid obstacles automatically, of course, makers can also automatically control the car with wireless and make full use of each module, as well as integrate all kinds of related sensors to make the car more intelligent, which is more challenging. "Hummer-Bot" has various types of information, technical manuals, routines, etc., which can teach you step by step. Each electronic fan can use it easily to achieve their desired function.

#### Product Features

- ◆ Three groups of black line infrared tracing module
- ◆ Two groups of infrared obstacle avoidance module

- ◆ Ultrasonic obstacle avoidance
- ◆ Four DC motor drive
- ◆ Two 3000mZh, 3.7V rechargeable lithium battery with longer endurance
- ◆ Remaining capacity of battery real-time detection
- ◆ Infrared remote control
- ◆ Bluetooth app control
- ◆ PS2 handle control (optional)

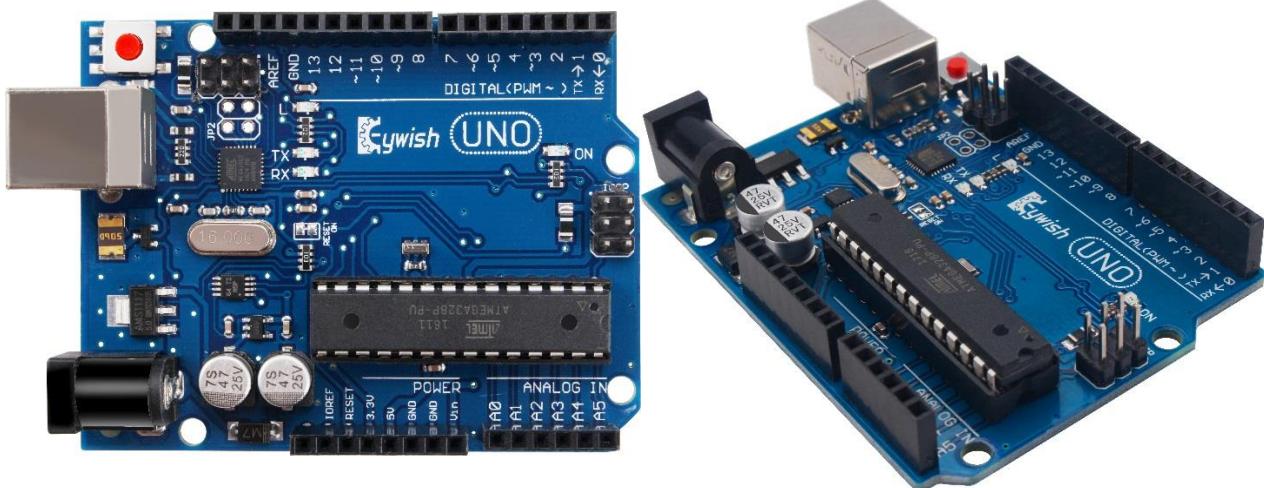
## Product Device List

					
2 x smart car Board	1 x CD-ROM with tutorial	4 x DC geared motor	1 x USB Cable	1 x IR remote control	1 x Keywish UNO R3 MainBoard
					
1 x Arduino extension board	1 x JDY-16 Bluetooth module	1 x Ultrasound Module	2 x Infrared obstacle avoidance module	1 x L298N motor drive board	1 x Infrared receiver module
					
3 x Infrared line tracking module	1 x Power indicator digital tube	1 x 18650 li-battery box	4 x 65mm wheel core	1 x SG90 servo	1 x 18650 battery charger
					Several Cable Tie
					6 x M3*30mm Dual channel copper posts
4 x M3*5+6mm Single channel copper pillar	20 x M3*10mm 10 x M3 *12mm Socket head cap screws	8 x M3x8 Round head screw	40 x M3-Hex nuts 4 x M2-Hex nuts	8 x M3*30MM Crosshead screws	4 x M3*8MM 4 x M2*12MM Crosshead screws

## Chapter2 Preparations

### About Arduino uno r3

- ◆ In "Aurora-Racing", we used the Arduino uno r3 as the main control board, which has 14 digital input/output pins (6 of which can be used as PWM output), 6 analog inputs, and a 16 MHz ceramic resonator, 1 USB connection, 1 power socket, 1 ICSP head and 1 reset button. It contains everything that supports the microcontroller; You just need to connect it to a computer via a USB cable or start with an AC-DC adapter or battery.



Technical specifications:

Working voltage: 5V

Input voltage: USB powered or external 7V~12V DC input

Output voltage: 5V DC output and 3.3V DC output and external power input

Microprocessor: ATmega328 (Chip data sheet is in the documentation)

Bootloader: Arduino Uno

Clock frequency: 16 MHz

Support USB interface protocol and power supply (without external power supply)

Support ISP download function

Digital I/O port: 14 (4 PWM output ports)

Analog input port: 6

DC Current I/O Port: 40mA

DC Current 3.3V Port: 50mA

Flash memory: 32 KB (ATmega328) (0.5 KB for bootloader)

SRAM : 2 KB (ATmega328)

EEPROM: 1 KB (ATmega328)

Size: 75x55x15mm

## 2.1 Development environment Arduino IDE

### 2.1.1 Install the IDE

ArduinoIDE is an open source software and hardware tool written by open source software such as Java, Processing, and avr-gcc. It is an integrated development environment that runs on a computer. It can write and transfer programs to the board. The major feature of the IDE is cross-platform compatibility for Windows, MaxOSX, and Linux. Only a simple code base is needed, and the creators can create personalized home internet solutions through the platform, such as remote home monitoring and constant temperature control and so on.

In this tutorial, we use the version is 1.6.0, download address is:<https://www.arduino.cc/en/Main/OldSoftwareReleases#previous>, After opening the link, we can see the interface as shown in Figure 2.1.1. In this interface, we can see the different versions of the IDE and different operating environments. Everyone can download according to their own computer system, of course, There will be a downloaded installation package on our companion CD, but only the Windows version, because this tutorial is all running under Windows system.

1.8.1	<a href="#">Windows Windows Installer</a>	<a href="#">MAC OS X</a>	<a href="#">Linux 32 Bit Linux 64 Bit Linux ARM</a>	<a href="#">Source code on Github</a>
1.8.0	<a href="#">Windows Windows Installer</a>	<a href="#">MAC OS X</a>	<a href="#">Linux 32 Bit Linux 64 Bit Linux ARM</a>	<a href="#">Source code on Github</a>
1.6.13	<a href="#">Windows Windows Installer</a>	<a href="#">MAC OS X</a>	<a href="#">Linux 32 Bit Linux 64 Bit Linux ARM</a>	<a href="#">Source code on Github</a>
1.6.12	<a href="#">Windows Windows Installer</a>	<a href="#">MAC OS X</a>	<a href="#">Linux 32 Bit Linux 64 Bit Linux ARM</a>	<a href="#">Source code on Github</a>
1.6.11	<a href="#">Windows Windows Installer</a>	<a href="#">MAC OS X</a>	<a href="#">Linux 32 Bit Linux 64 Bit Linux ARM</a>	<a href="#">Source code on Github</a>
1.6.10	<a href="#">Windows Windows Installer</a>	<a href="#">MAC OS X</a>	<a href="#">Linux 32 Bit Linux 64 Bit Linux ARM</a>	<a href="#">Source code on Github</a>
1.6.9	<a href="#">Windows Windows Installer</a>	<a href="#">MAC OS X</a>	<a href="#">Linux 32 Bit Linux 64 Bit Linux ARM</a>	<a href="#">Source code on Github</a>
1.6.8	<a href="#">Windows Windows Installer</a>	<a href="#">MAC OS X</a>	<a href="#">Linux 32 Bit Linux 64 Bit</a>	<a href="#">Source code on Github</a>
1.6.7	<a href="#">Windows Windows Installer</a>	<a href="#">MAC OS X</a>	<a href="#">Linux 32 Bit Linux 64 Bit</a>	<a href="#">Source code on Github</a>

Figure 2.1.1 ArduinoIDE download interface

After the downloading, we will get a compressed package as shown in Figure 2.1.2. The compressed package will be decompressed. After decompression, the files in Figure 2.1.3 are extracted. The “drivers” is the driver software. When the “Arduino.exe” is installed, it will be Install the driver automatically. Because the installation of "arduino.exe" is very simple, it will not be explained here. It is recommended to exit the anti-virus software during the installation process, otherwise it may affect the installation of the IDE. After

the installation is complete, click "arduino.exe" again to enter the IDE programming interface.

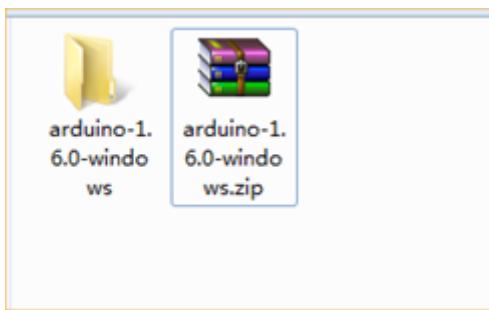


Figure 2.1.2 Arduino IDE Installation Package

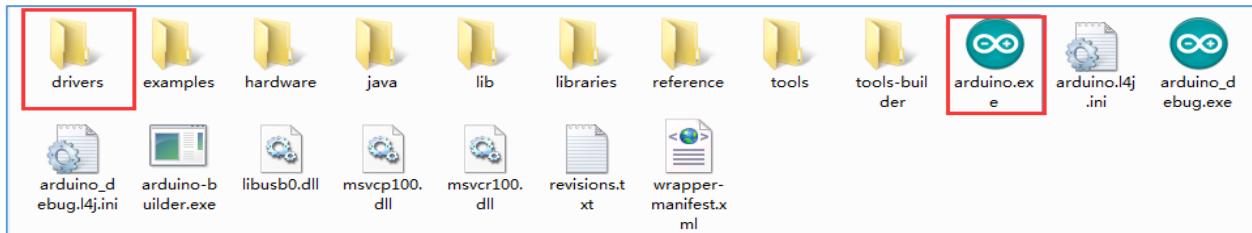


Figure 2.1.3 Extracted files

When finish the installation of the IDE, connect to the Arduino motherboard, click “My Computer” → “Properties” → “Device Manager” → “Viewing Ports (COM and LTP)”, If you can see as the Figure 2.1.4

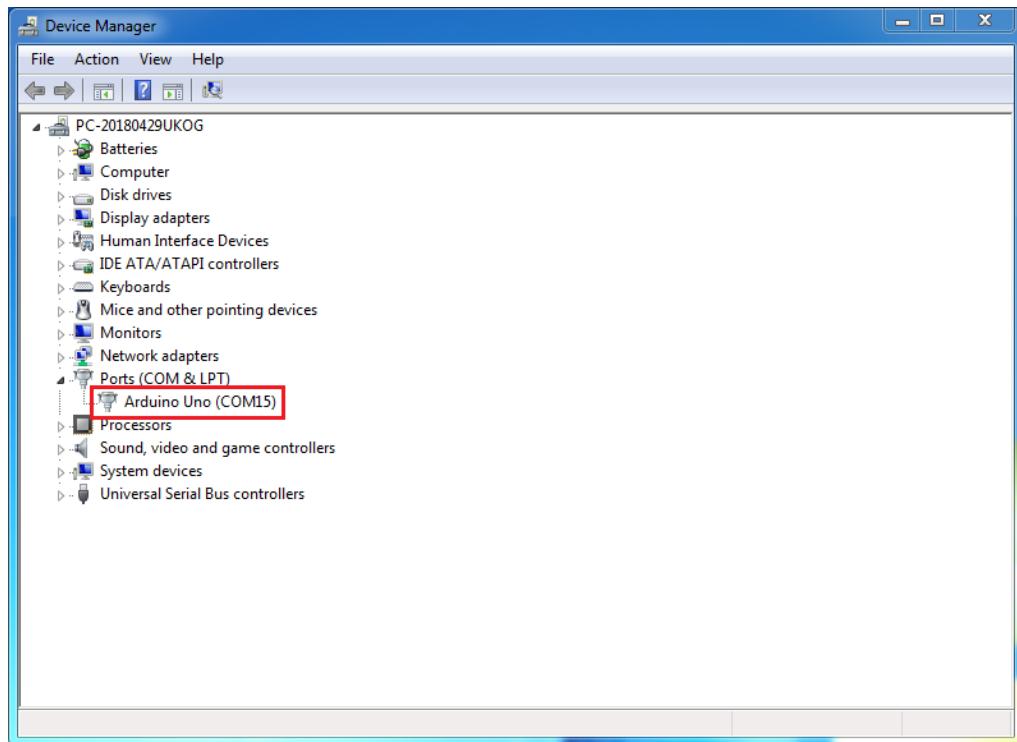


Figure 2.1.4 Driver installation success interface

that indicates the driver has been installed successfully, At this time we open the IDE, select the corresponding development board model and port in the toolbar to use normally. If you see Figure 2.1.5, it means that the computer does not recognize the development board and you need to install the driver yourself.

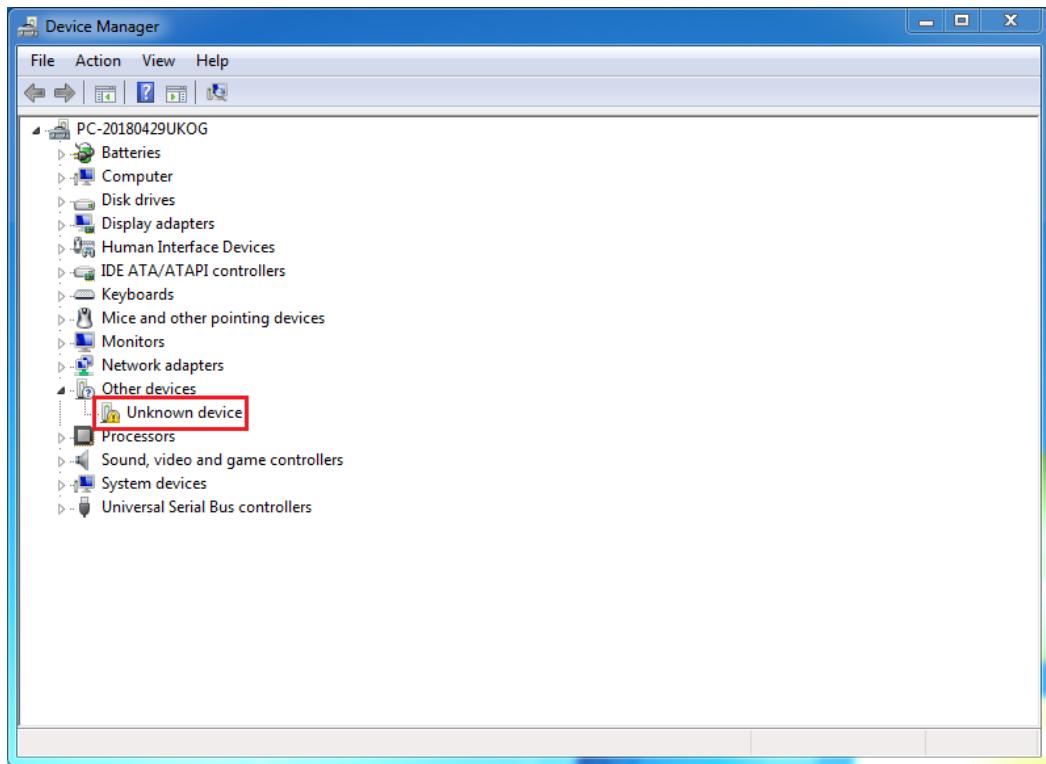


Figure 2.1.5 Driver is not successfully installed interface

**Notice:**

- 1) If you connect the controller board to the computer, the computer does not respond. Right-click "My Computer" and select Open Device Manager then find viewing port (com & lpt). If there is no com or lpt, or only an unknown device, there is a problem with the controller board or the USB cable.
- 2) Right-click "My Computer" and select Device Manager, find the viewing ports (COM and LPT). If there is a yellow Arduino UNO exclamation point, this means you need to install the driver yourself.
- 3) If you install the driver again and again, it eventually fails. Please uninstall the driver and re-install> install the driver automatically> restart the computer.

## 2.1.2 Install Driver

If your computer is a Windows 7 system

- 1) Right-click on "My Computer" and open the Device Manager, find viewing the ports (COM and LPT). At this point you will see a "USB Serial Port", right-click "USB Serial Port" and select the "Update Driver Software" option.

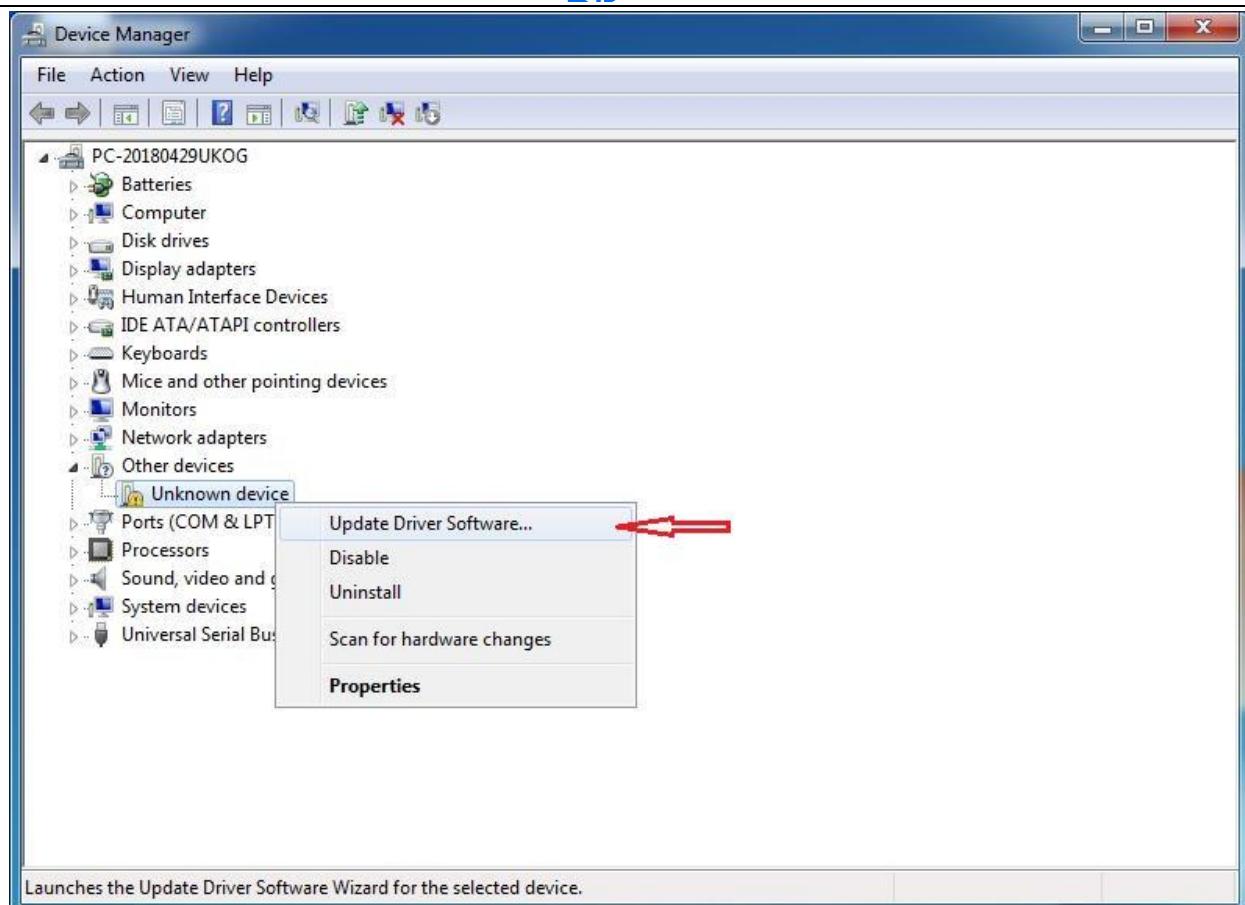


Figure 2.1.6 Updated Driver Interface

2) Next, select the "Browse my computer for driver software" option.

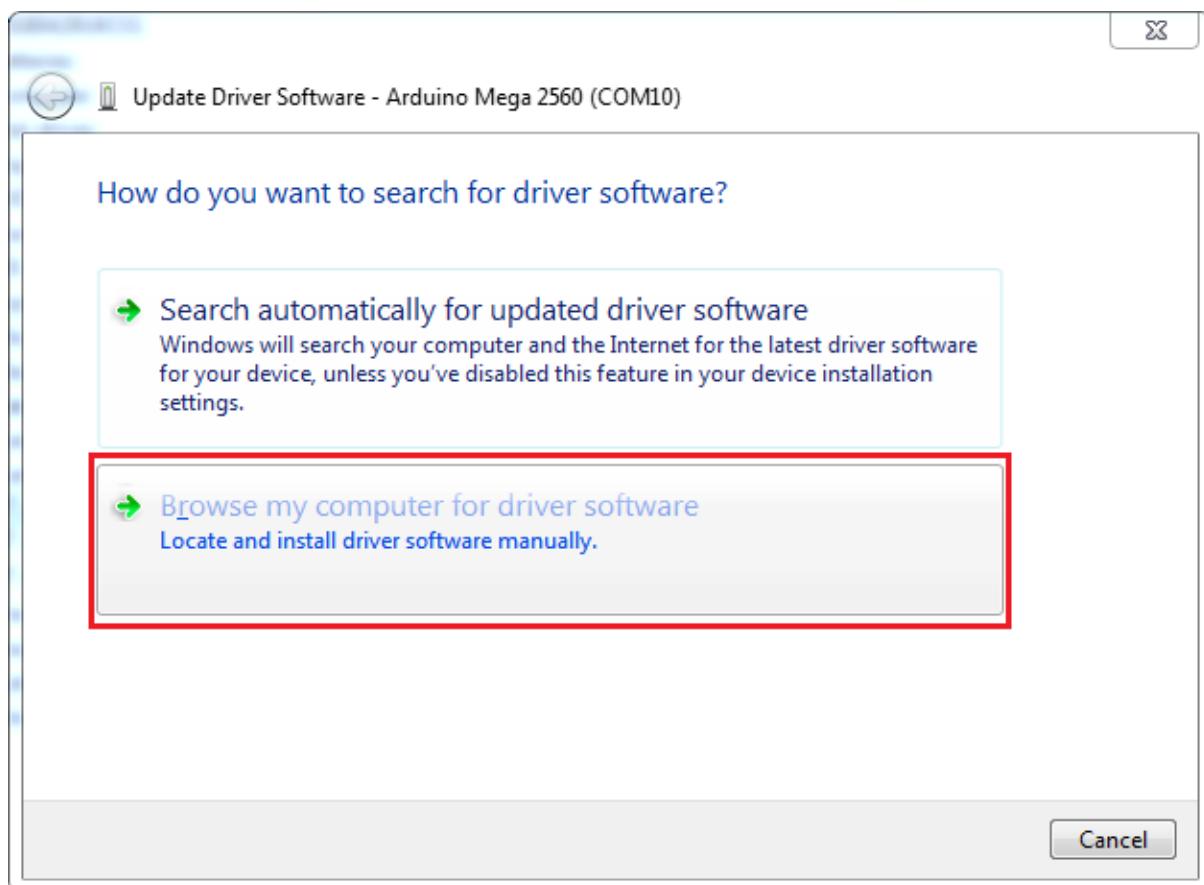


Figure 2.1.7 Driver Update Selection Screen

- 3) Finally select the driver file named "FTDI USB Drivers" located in the "Drivers" folder of the Arduino software download.

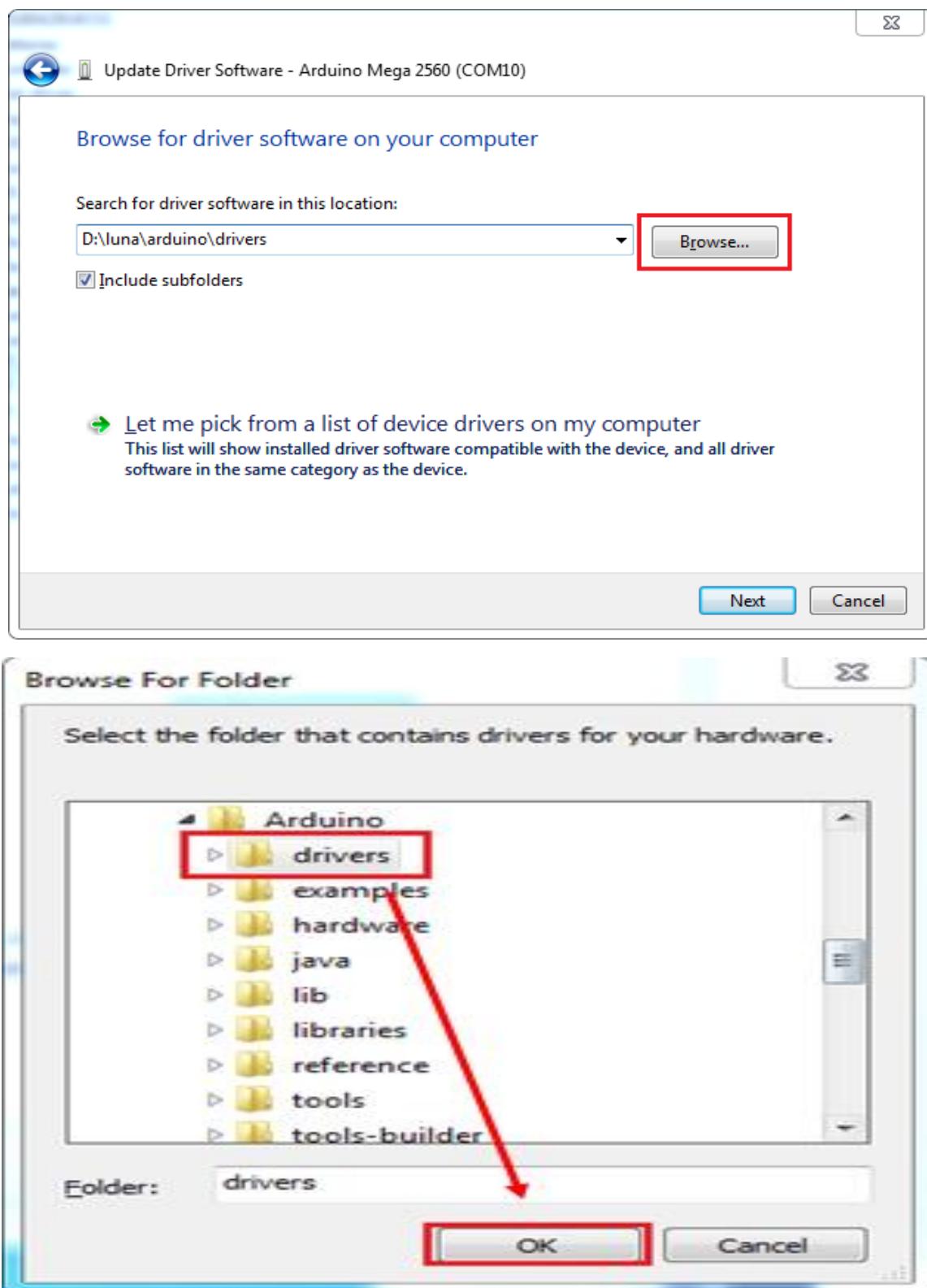


Figure 2.1.8 Driver file selection interface

- 4) If you have already installed, the following figure will automatically inform you that the driver was successful.

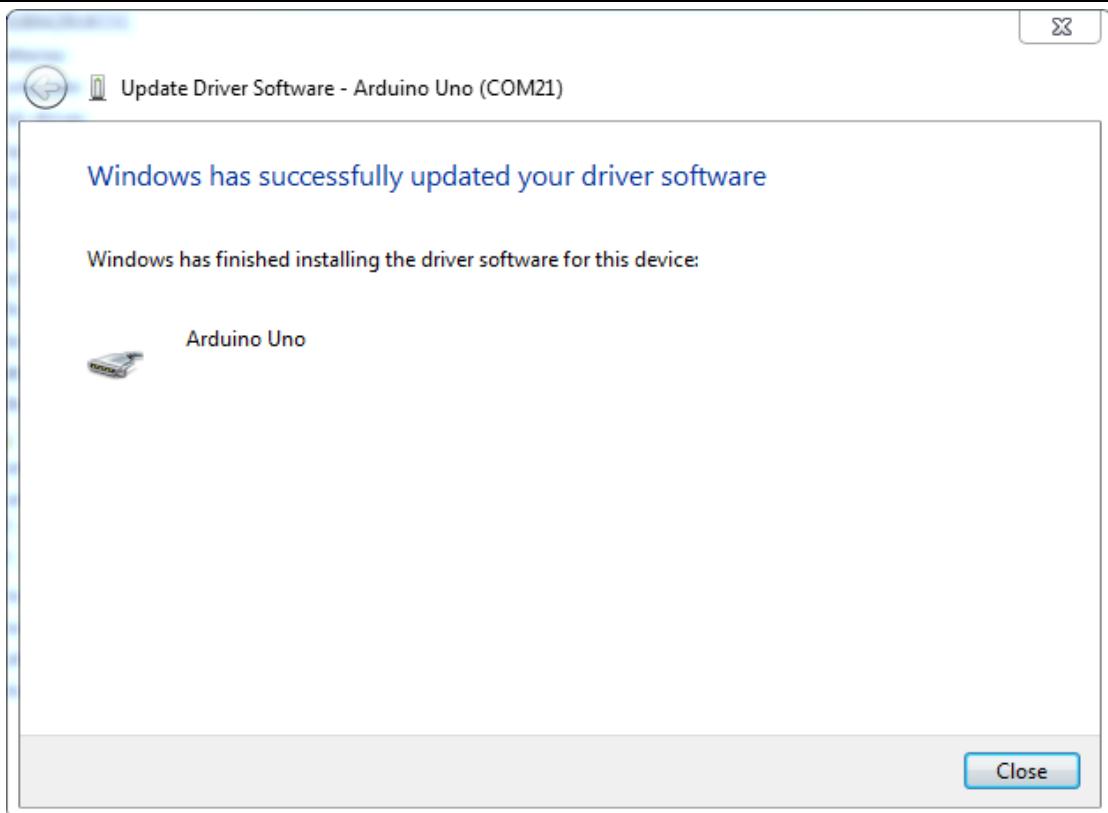


Figure 2.1.9 Driver Installation Successful Interface

At this time, we return to the "Device Manager" interface, the computer has successfully identified Arduino, as shown in the below Figure 2.1.10 .then open the Arduino compilation environment, you can open the Arduino trip.

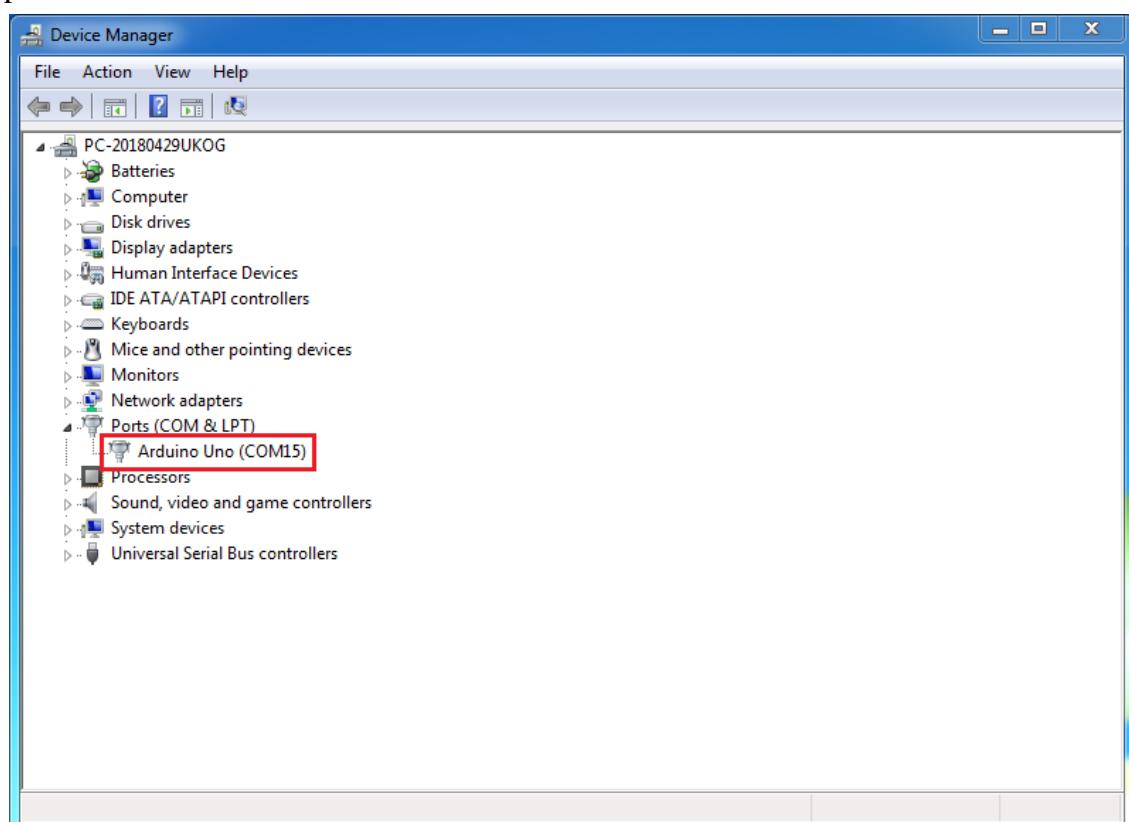


Figure 2.1.10 Driver Success Recognition Interface

Notice In Win10 system, some Arduino are connected to the computer (non-genuine chips are difficult to identify), the system will automatically download the corresponding driver, so you can not install the driver yourself, but in the Win7 system, you have to do it yourself.

In addition, we can see that the USB serial port is identified as COM15 in the above figure, but it may be different with different computer, you may be COM4, COM5, etc., but USB-SERIAL CH340, this must be the same. If you do not find the USB serial port, you may have installed it incorrectly or the system is incompatible.

2、 If your computer is a Windows 8 system: Before installing the driver, you should save the files you are editing because there will be several shutdowns during the operation.

- 1) Press "Windows key" + "R"
  - 2) Input shutdown.exe / r / o / f / t 00
  - 3) Click the "OK" button.
  - 4) The system will reboot to the "Select an option" screen
  - 5) Select "Troubleshooting" from the "Select an option" screen
  - 6) Select "Advanced Options" from the "Troubleshoot" screen
  - 7) Select "Windows startup settings screen" from "Advanced Options"
  - 8) Click the "Restart" button
  - 9) The system will reboot to the "Advanced Boot Options" screen
  - 10) Select "Disable Driver Signature Enforcement"
  - 11) Once the system is booted, you can install Arduino driver the same as Windows7
- 3、 If your computer is a Windows XP system: The installation steps are basically the same as for Windows 7, please refer to the above Windows 7 installation steps.

### 2.1.3 IDE Interface Introduction

Nextly,we introduce the Arduino IDE interface, firstly enter the software directory. Then you can see the arduino.exe file and double-click to open the IDE. As shown in Figure 2.1.11.

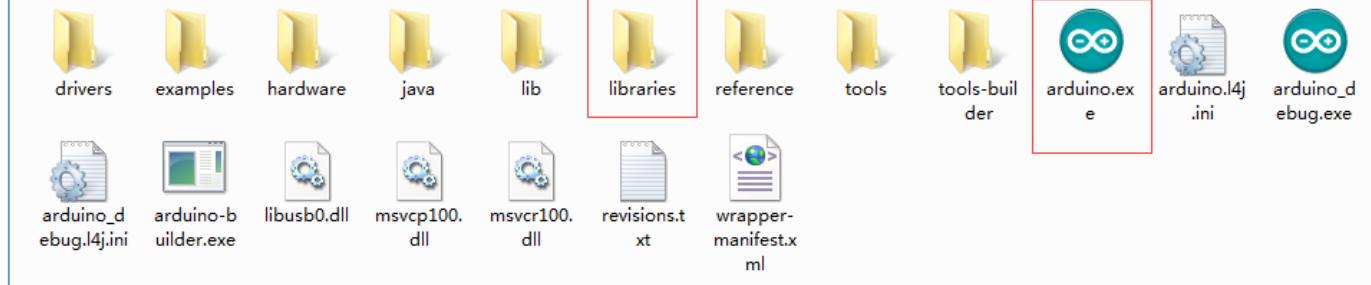


Figure 2.1.11 Software Catalog

- 1、 The first thing you can see is the interface of the following figure. The functions of the toolbar buttons are "Compile" - "Upload" - "New Program" - "Open Program" - "Save Program" - "Serial Monitor" , as shown in Figure 2.1.12.

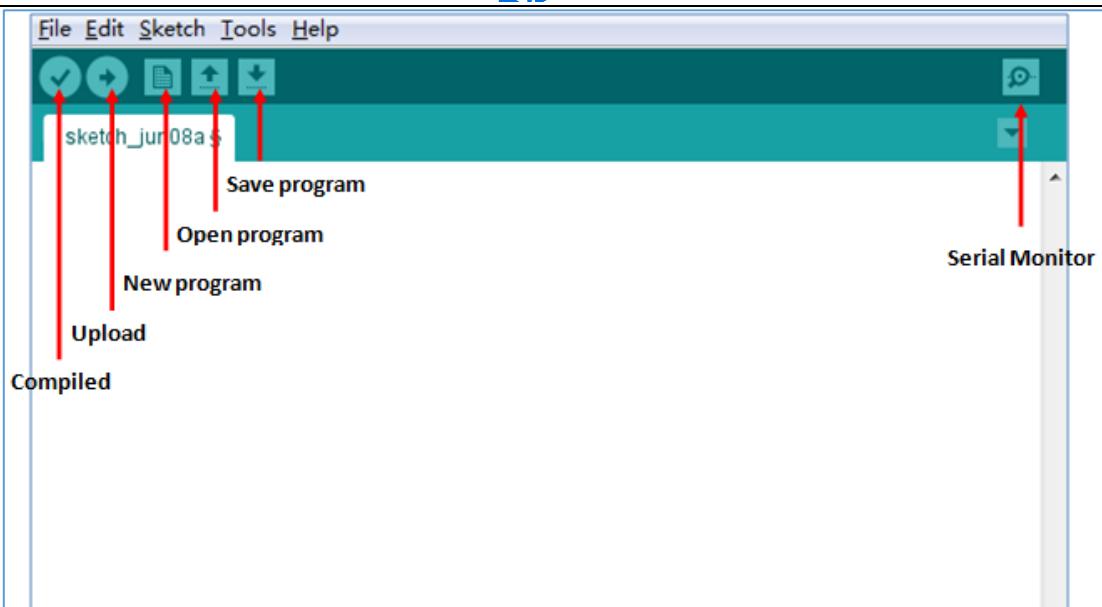


Figure 2.1.12 Arduino IDE Interface

2. There are 5 menus on the menu bar, but we mainly introduce File and Tools. Click File, the interface as shown in Figure 2.1.13 will be displayed, you can see the Examples and Preference options. The Examples are some of the Arduino's own programs, these are compiled without errors, the normal use of the program, a great help for beginners. The Preference option, It's mainly about the parameter settings, such as language, fonts and so on.

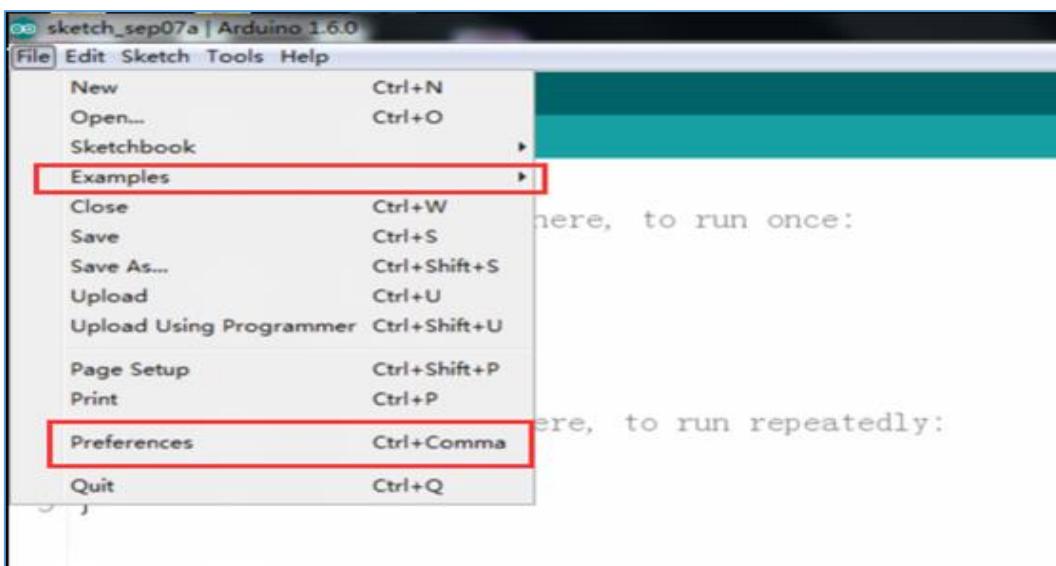


Figure 2.1.13 File Menu Bar Options

3、Click Tools, the interface shown in Figure 2.1.14 will pop up. Here we can see two options: Board and Port. In the board option, we can see the commonly used Arduino development board model, we only need to choose according to their own development board. In the Port option, the USB serial port is mainly selected, as shown in Figure 2.1.15. If you are not sure, you can check it in the "Device Manager" and select the corresponding COM port.

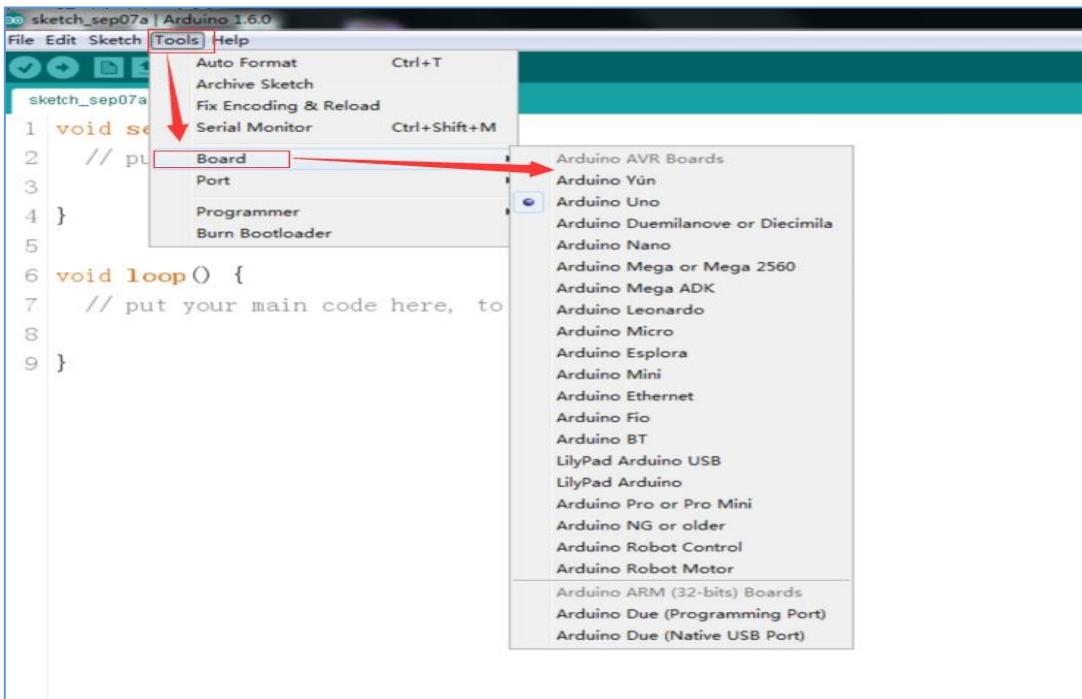


Figure 2.1.14 Tools interface

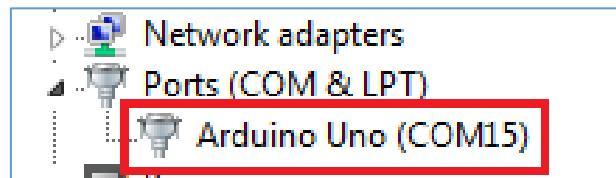
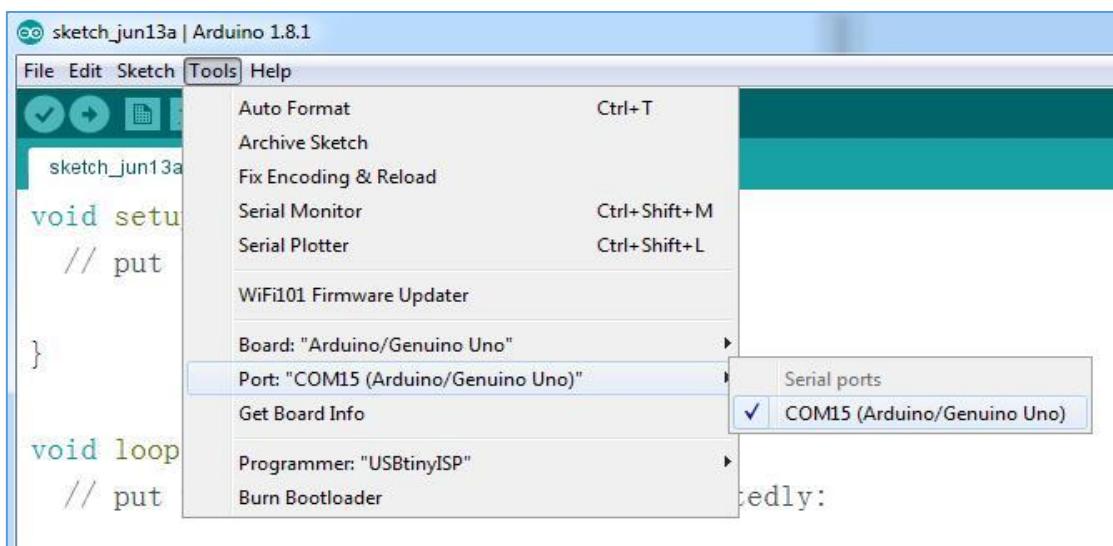


Figure 2.1.15 USB serial port selection

So far, we have basically completed all the work. The next step is actual experiments. Open any program in Examples. First compile the program. If it is compiled correctly, it can be directly downloaded to the development board and the corresponding device of the connection number. With wires, you can see the corresponding phenomenon.

### 3.1 Assembly of the Car

#### 3.1.1 Bottom Mounting of the Car

Firstly, we open the box, take out the car body (two black acrylic), screwdriver, M4x12 screws, six angle coupling and matching set screws, four black&red welding wires and four motor and wheels.

The first step is to Mounting motor mount.

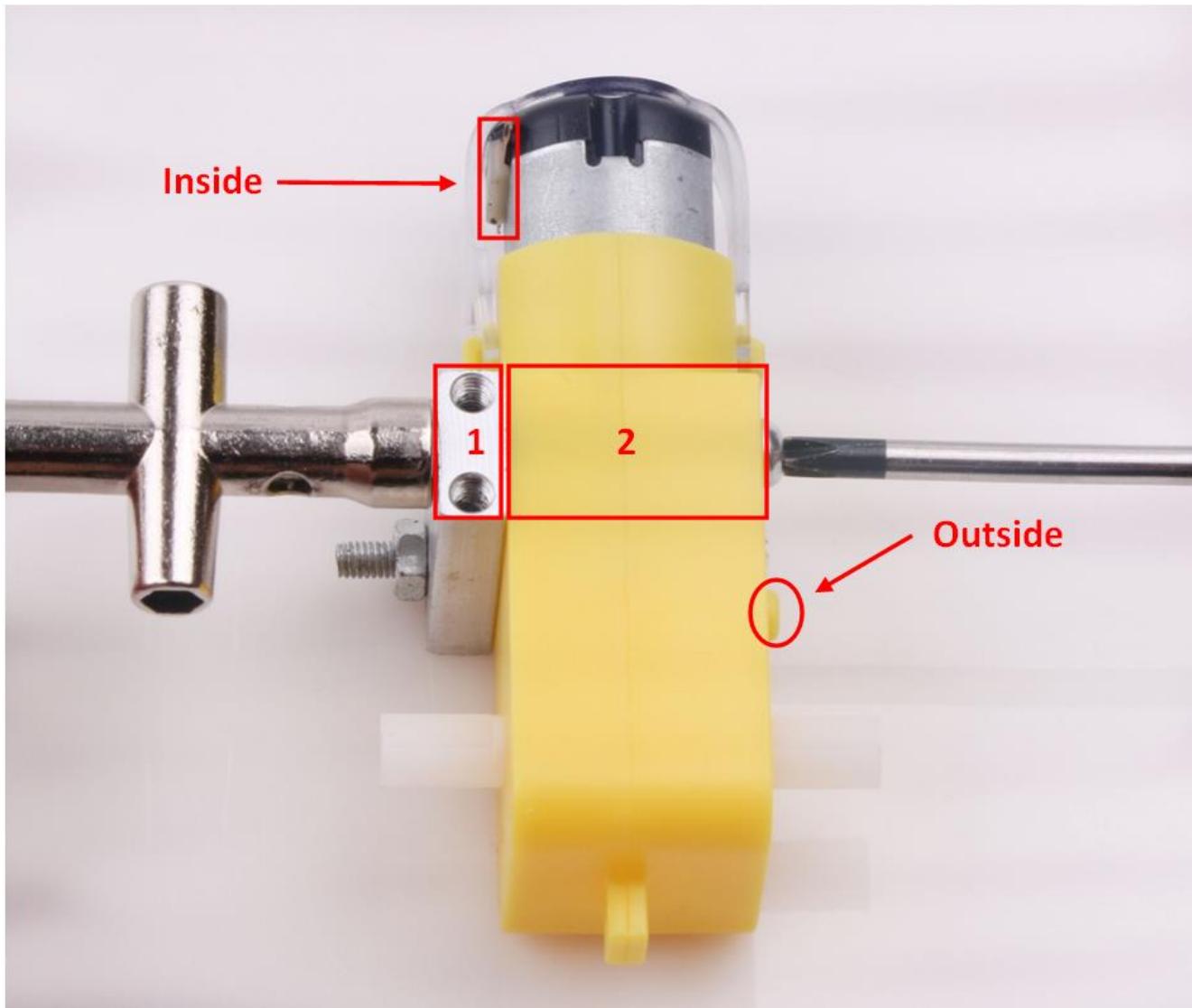


Figure 3.1.1 Mounting Schematics

**Note: One side of the bump is the outside, and the copper side of the motor is the inside. The fixing bracket should be installed on the copper side of the motor.**

**The "1" plane of the mounting bracket and the "2" plane of the motor should be in the same horizontal plane, to avoid instability of the motor when the rear mounting is not horizontal.**

**The screws of the fixing frame are installed from the outside to the inside. If it is installed in the opposite direction, the protruding screw will affect the rotation of the wheel.**

After the completion as show

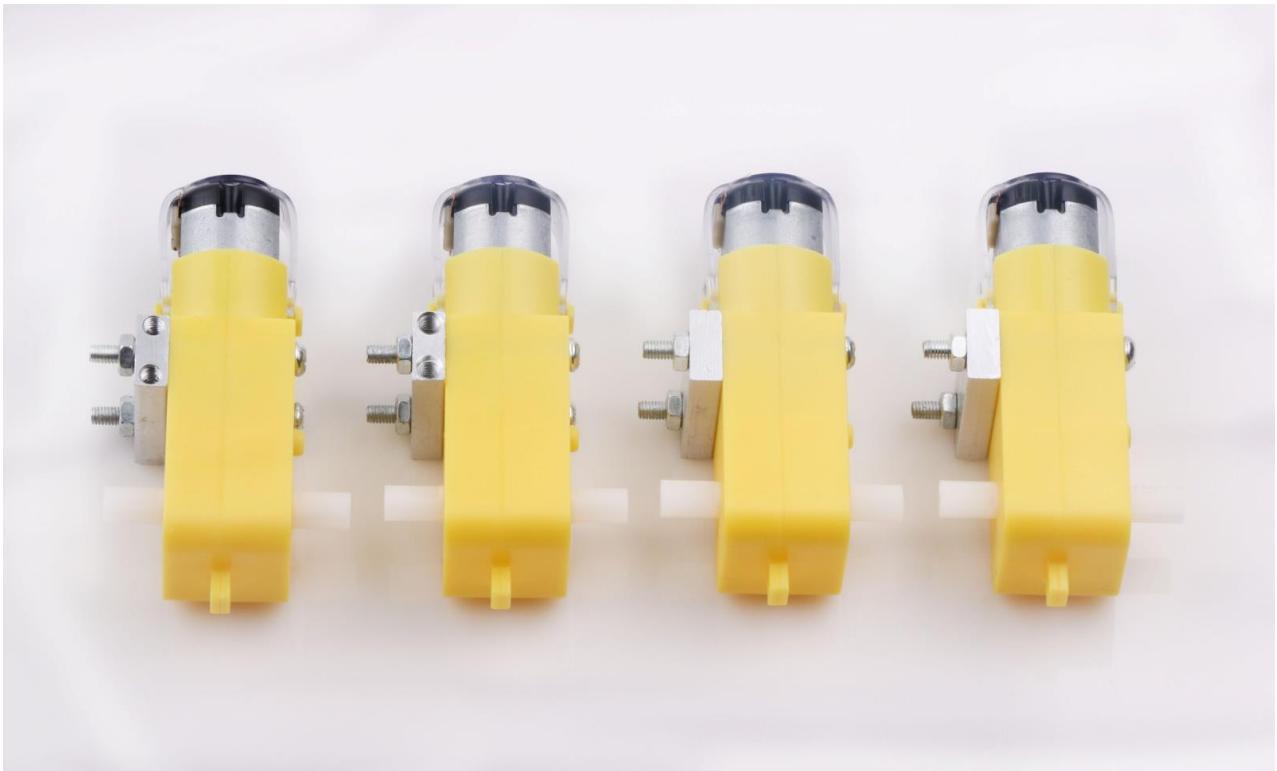


Figure 3.1.2 Fixture Installation Completed

The second step is to Welding wire on the motor.

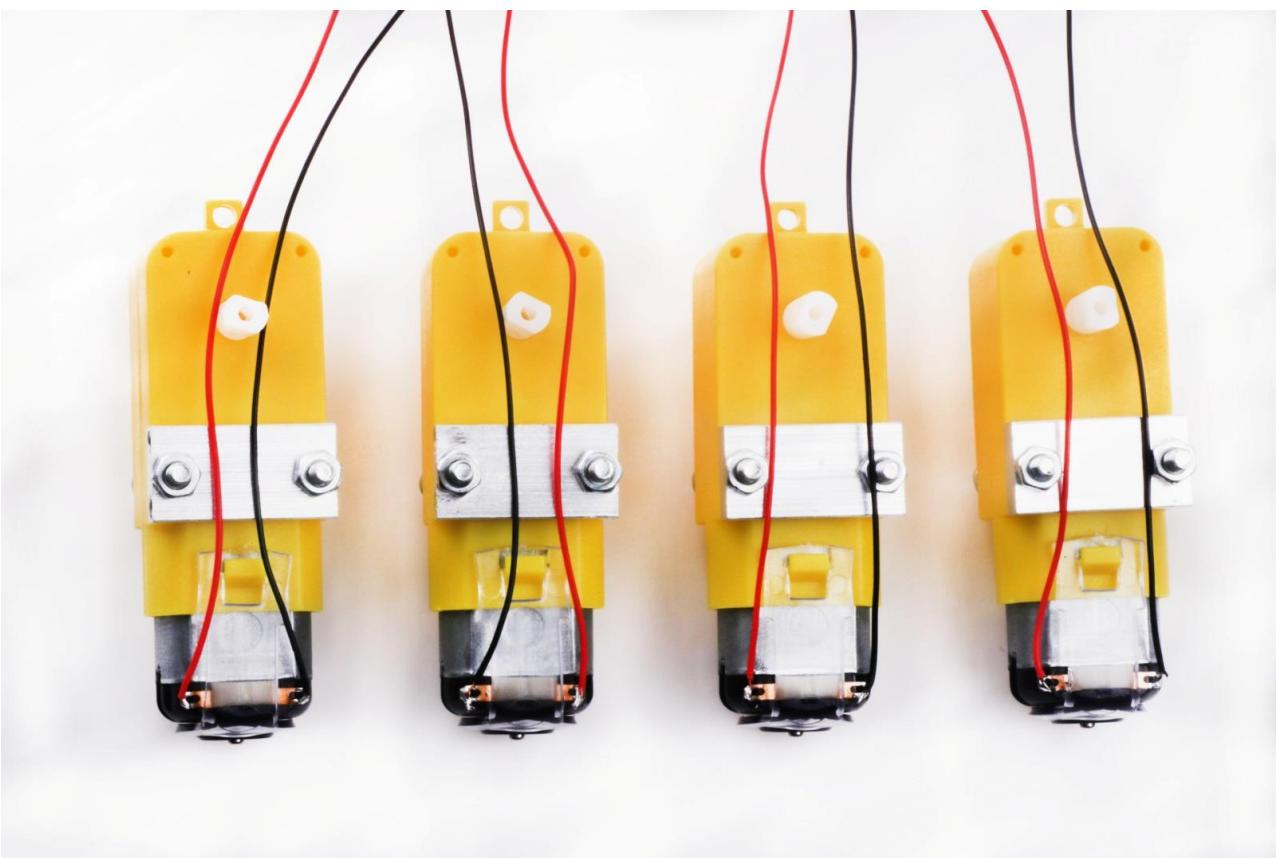


Figure 3.1.3 Wire Installation Diagram

The third step is to fix the wire on the motor with tie tape.

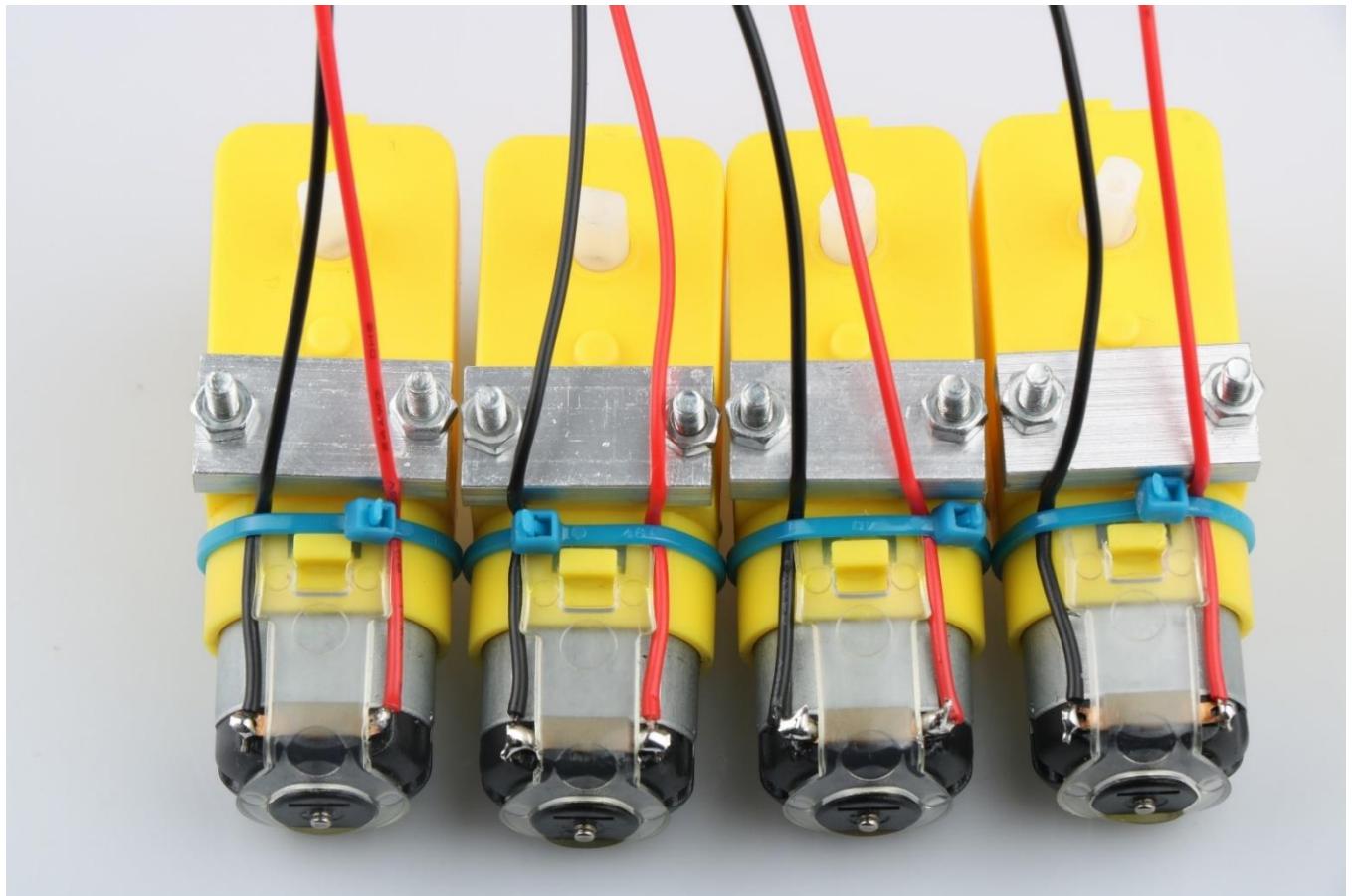


Figure 3.1.4 Wire fixing diagram

The fourth step is to Mount aluminum alloy brackets on acrylic plates. first removing the protective film on the acrylic, and then fixing it according to the corresponding space.

**Note:** Be sure to align the screw holes on the bracket with the screw holes on the acrylic board when installing in Figure 3.1.5.



Figure 3.1.5 Aluminum Alloy Bracket Installation

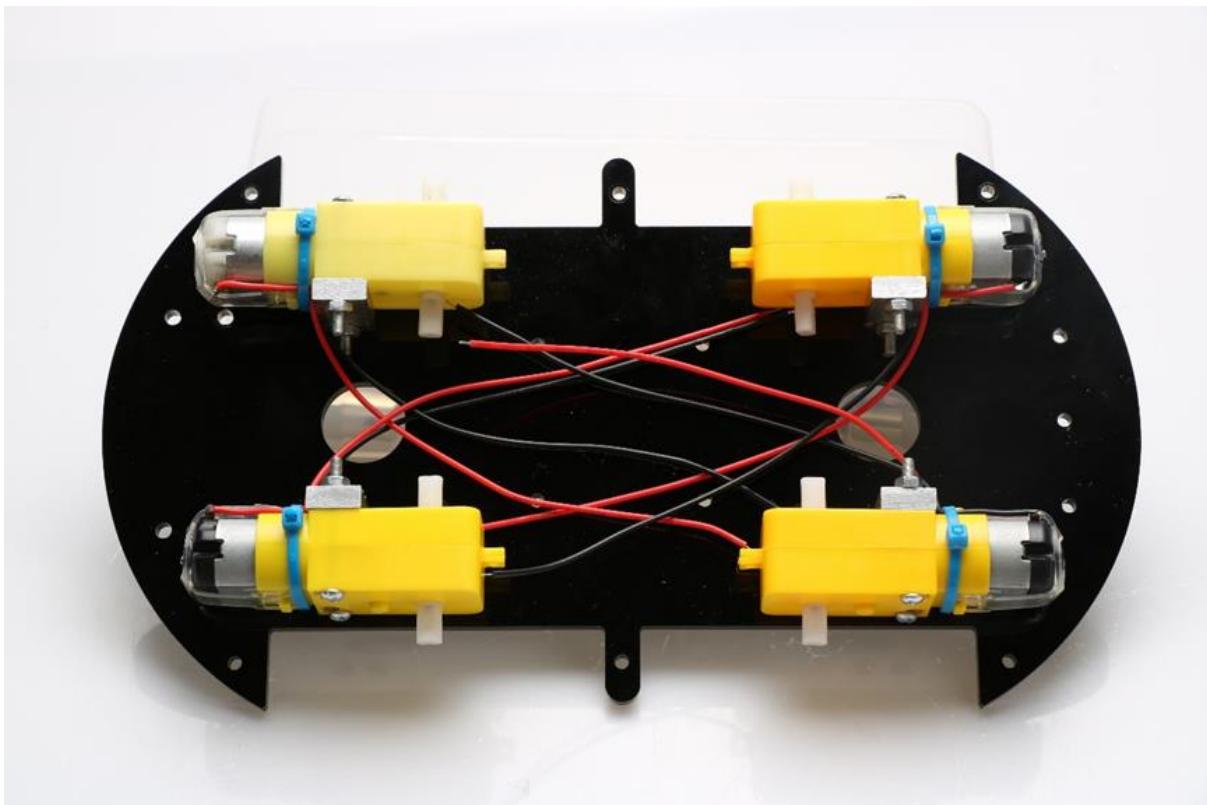


Figure .3.1.6 Front view of motor installation

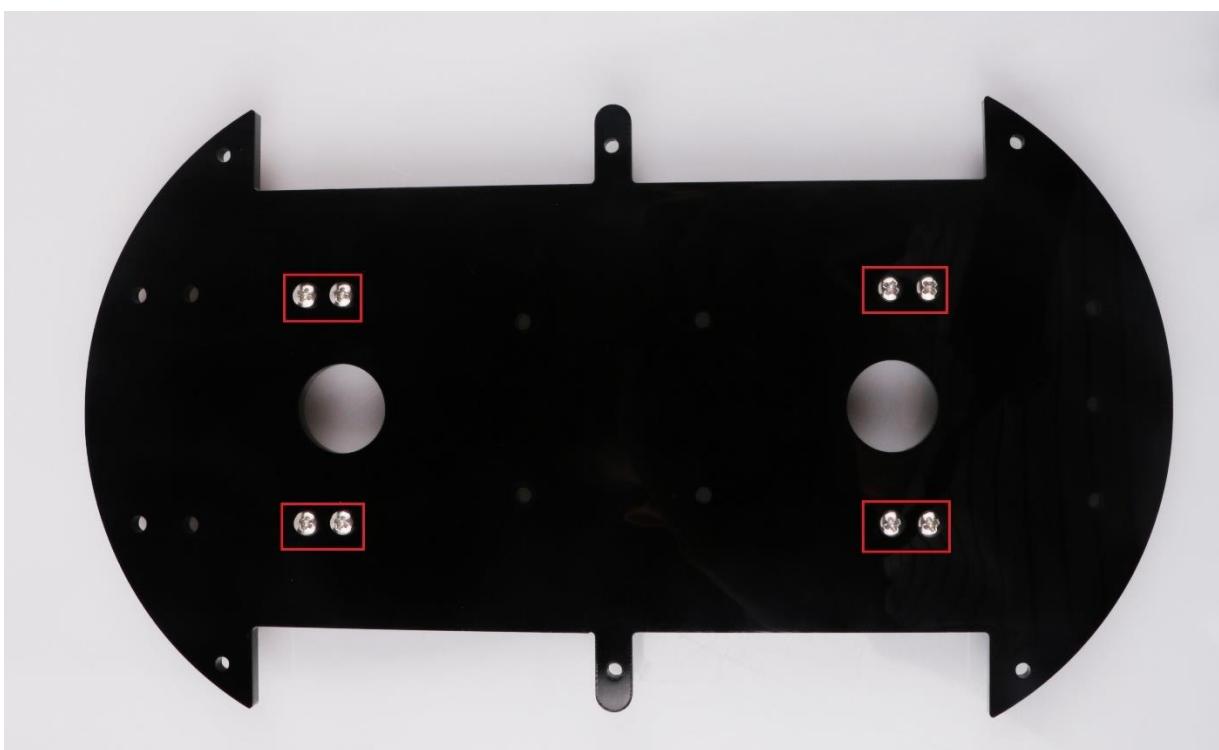


Figure .3.1.5 Rear fixing screws

### 3.1.2 Mounting Wheel

"Hummer-Bot" uses racing wheels which grip stronger, less friction, more stable than the traditional wheels. The wheel mounting method is relatively simple. , align the connecting shaft and wheel to insert. As shown in Figure 3.1.8, the installed wheels may be slightly inclined. At this time, we need to manually adjust the motor by hand until the wheels become parallel to the acrylic and tighten the screws.

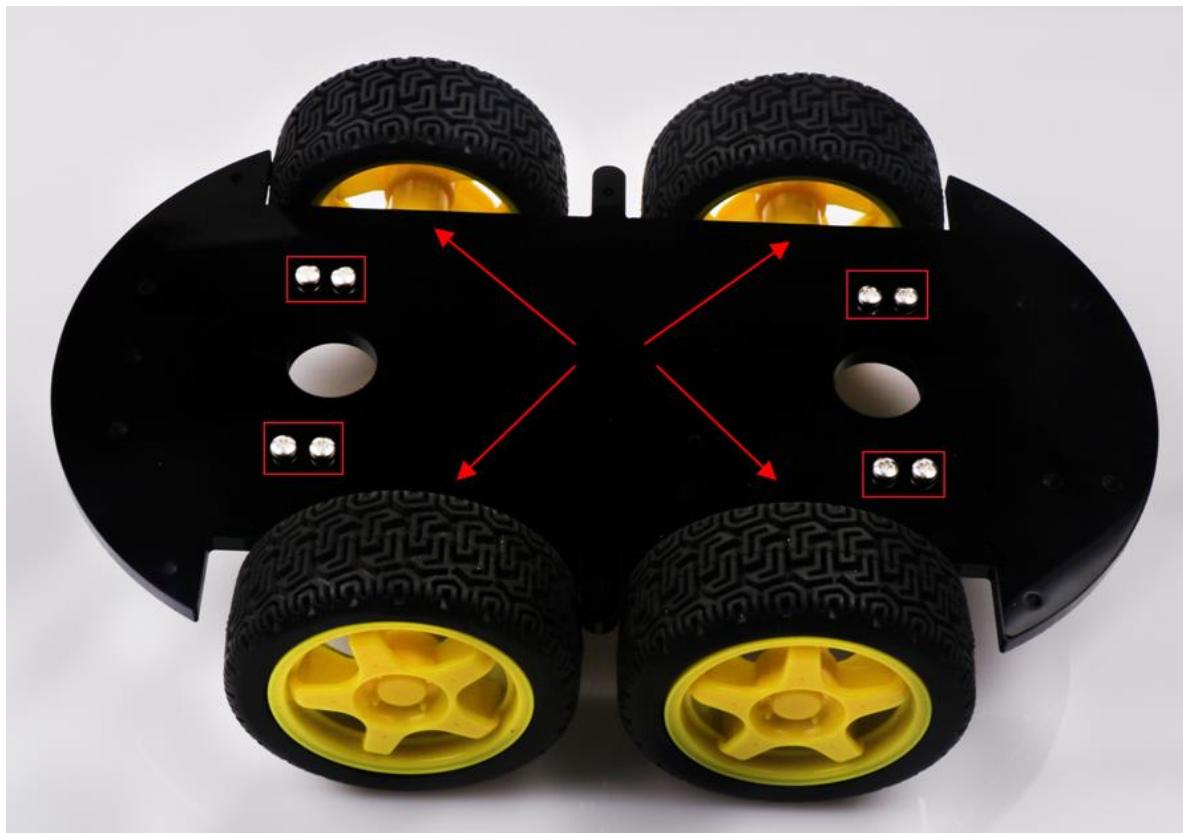


Figure 3.1.8 Wheel adjustment and tighten the screws

### 3.1.3 Motor Drive Installation

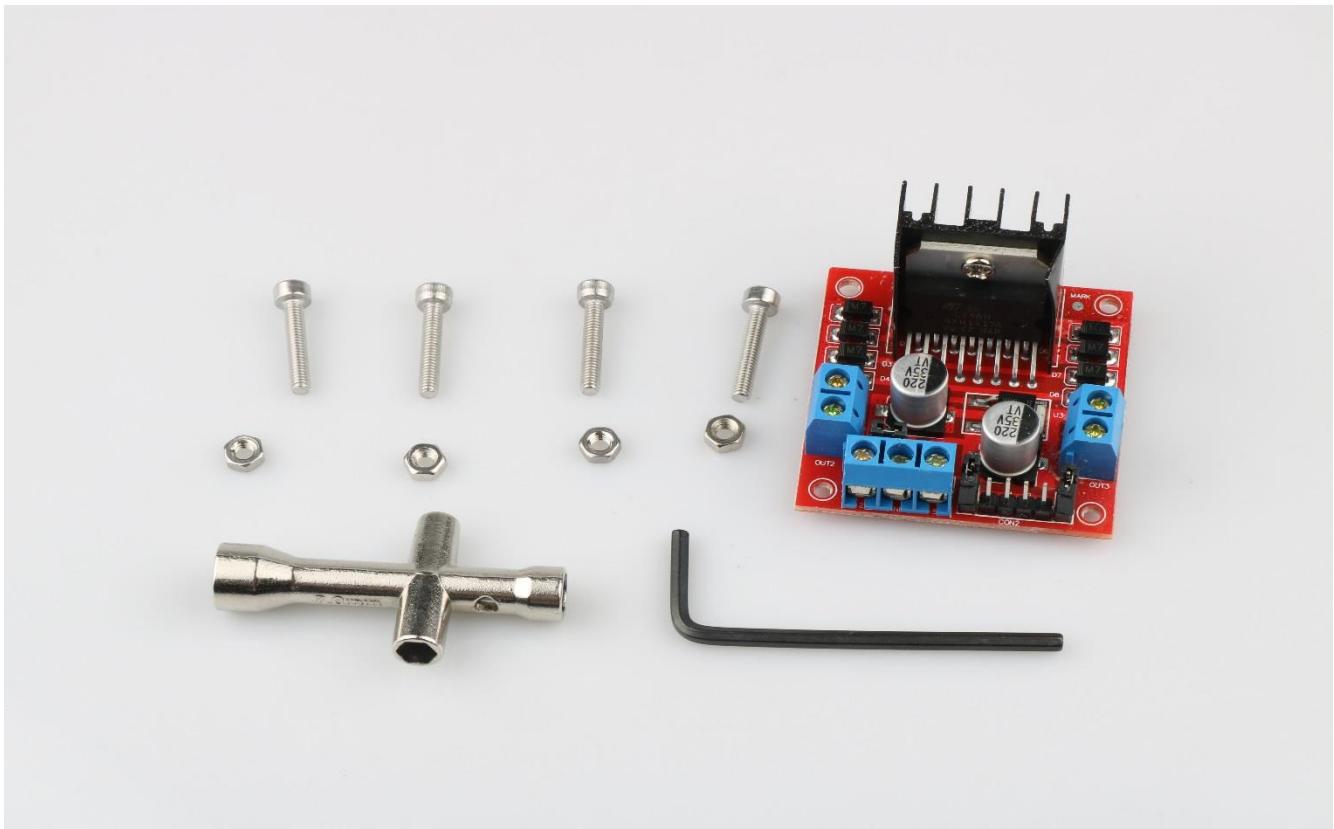


Figure 3.1.9 Driver Board Installation

Firstly, fix the M3\*14mm screws on the motor driver board. For the smooth installation, we place a nut between the driver board and the bottom board to separate as shown in Figure 3.1.10.

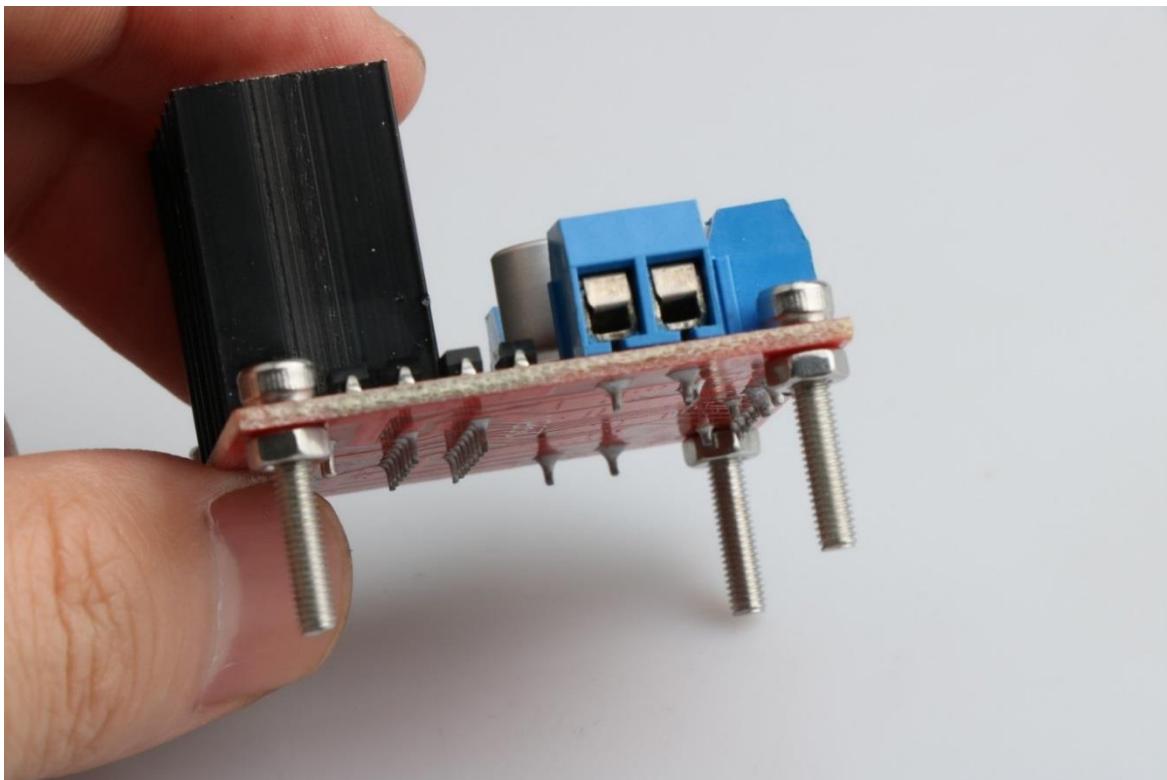


Figure 3.1.10 Driver Board Mounting Screws

Then install the motor driver board on the acrylic board, as shown below

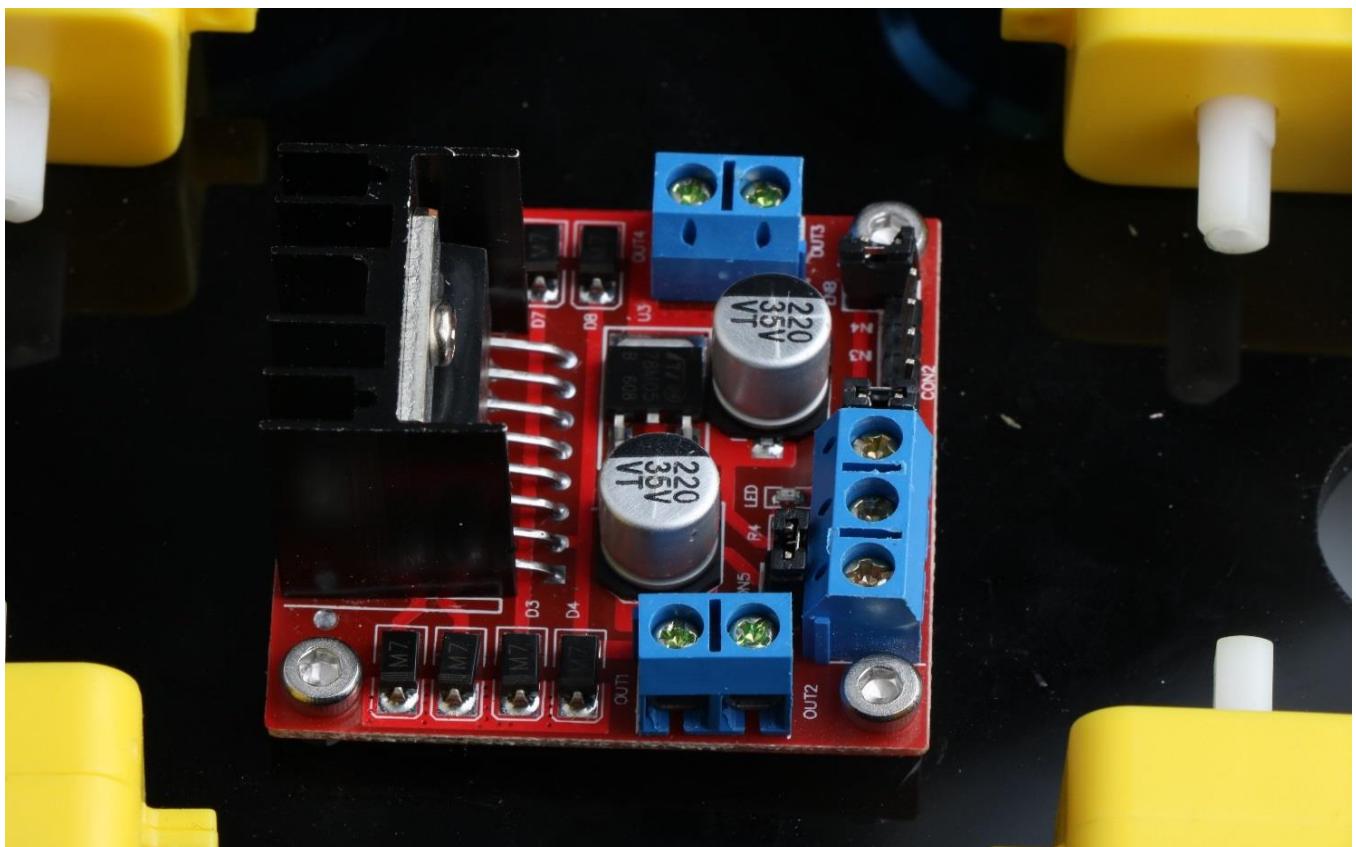


Figure .3.1.11 Diagram of Motor Drive Installation

Finally, connect the motor wires to the drive, note that the rotation direction of the two motors require to be identical, so we should modify and debug the program first when wiring. Connecting the motor to any motor driver board, as shown in Fig. 3.1.13, then connecting the two wires on battery box to the motor drive +12v (red) and GND (black). and leading a wire from +5V to "3" or "4" in the figure (IN1&IN2 is a motor set, IN3&IN4 is another set). Observing rotation directions of the motors, if the rotation directions are not the same, you only need to change "1" and "2" in the figure. The physical map is shown in Fig. 3.1.14.

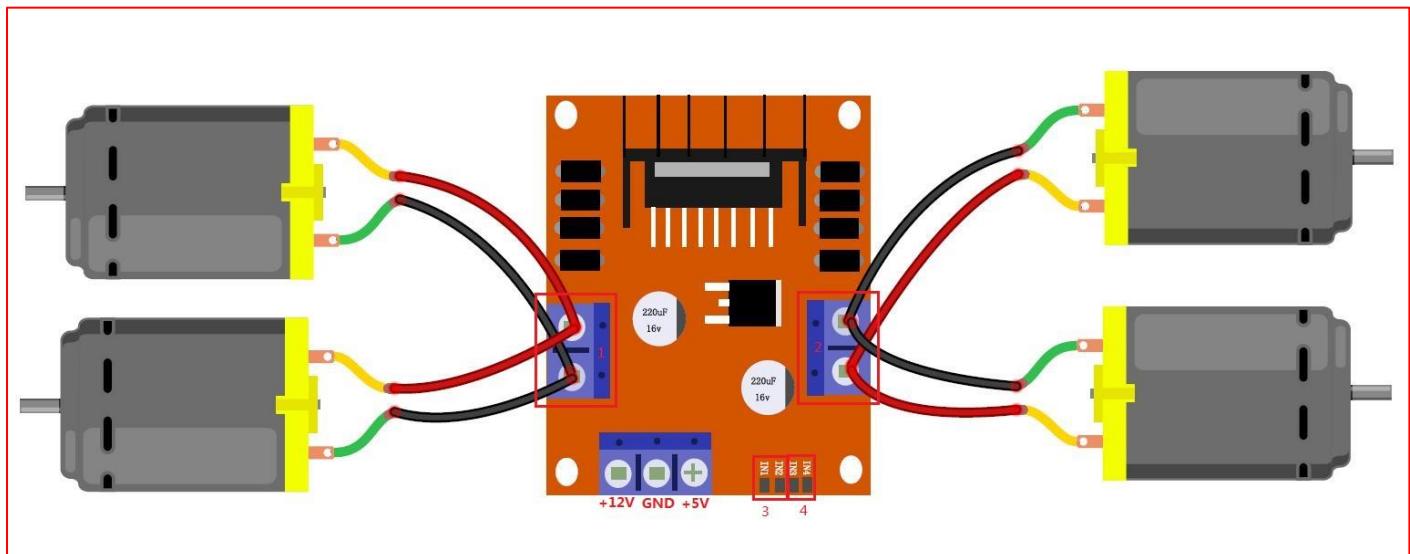


Figure 3.1.12 Diagram of Connection Between Motors and Drive Board

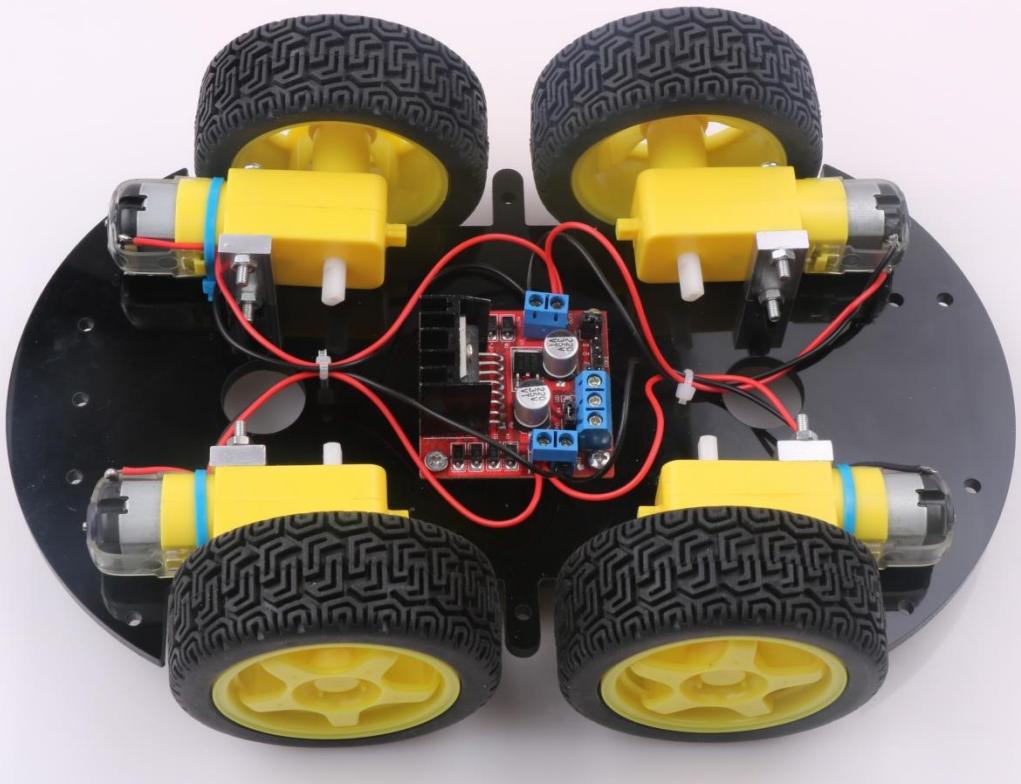


Figure .3.1.13 Diagram of Connection Between Motors and Drive Board

### 3.1.4 Install the tracing module

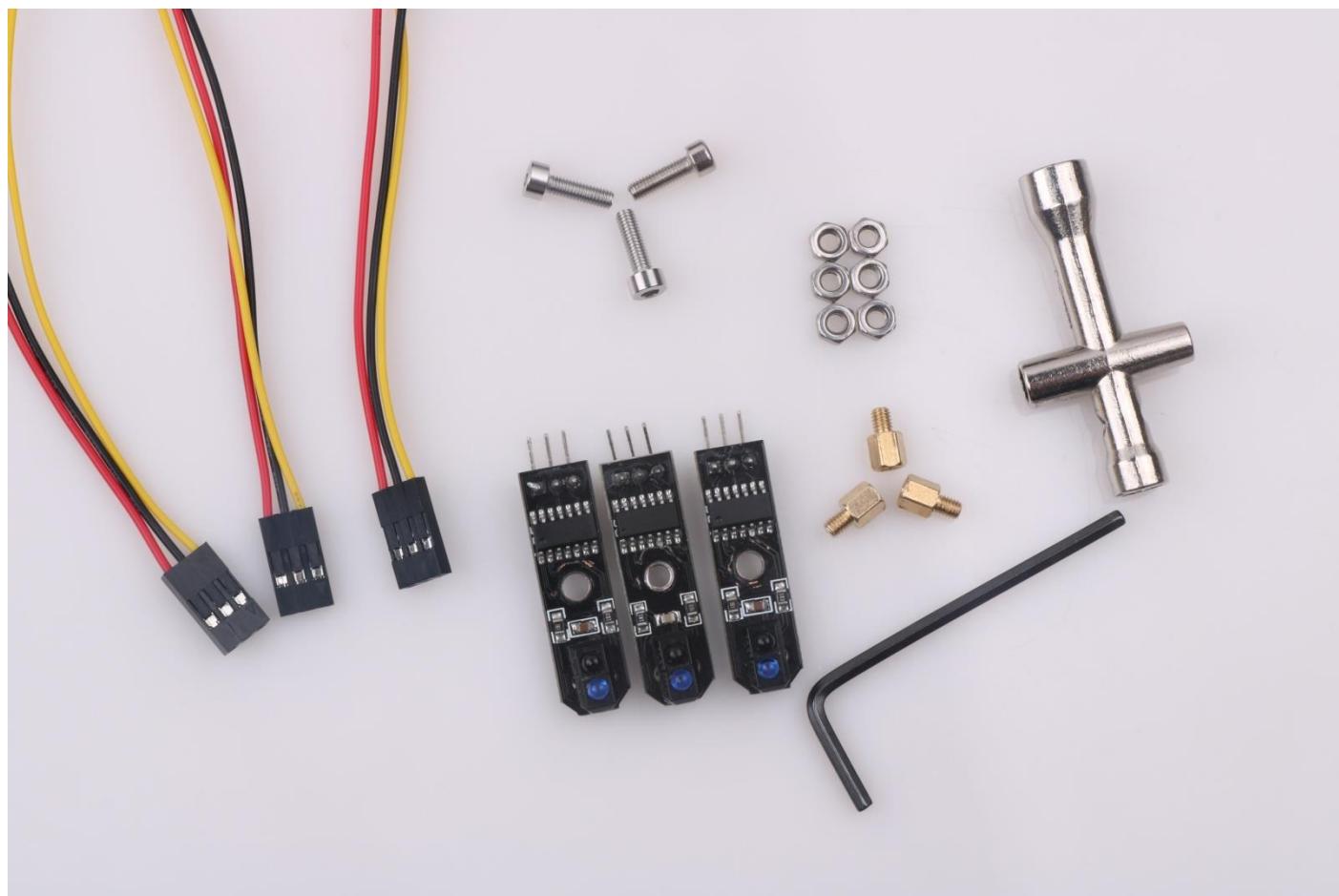


Figure 3.1.14 Tracking Module Installation Checklist

Firstly, screw the nut and the 5mm copper column onto the tracking module, as shown in Figure 3.1.16. Then connect one end of the 3Pin wire to "1" in the figure. Finally, fix the tracing module is fixed to the acrylic plate and screwed on, as shown in Figure 3.1.1

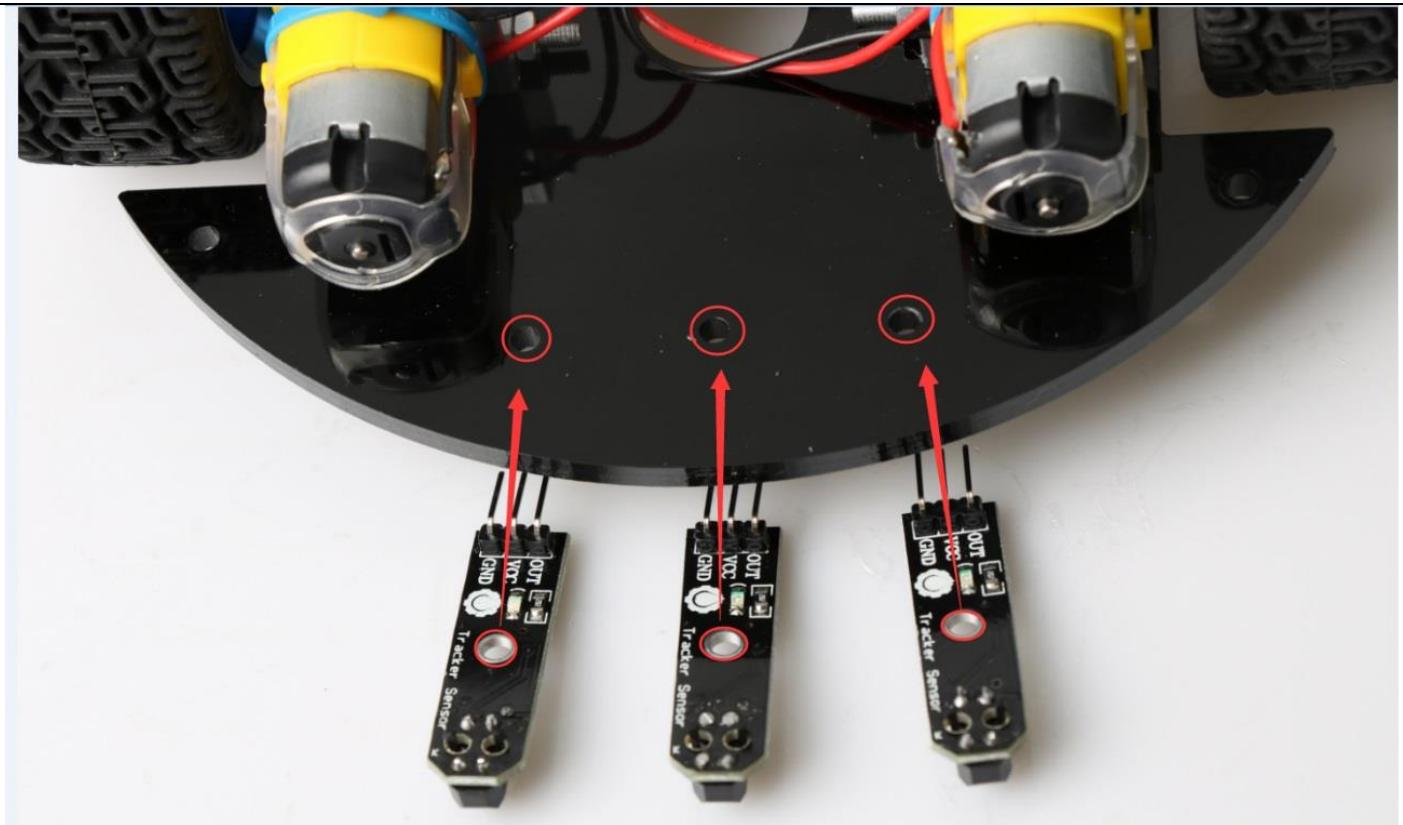


Figure .3.1.15 Diagram of Tracing Module Installation

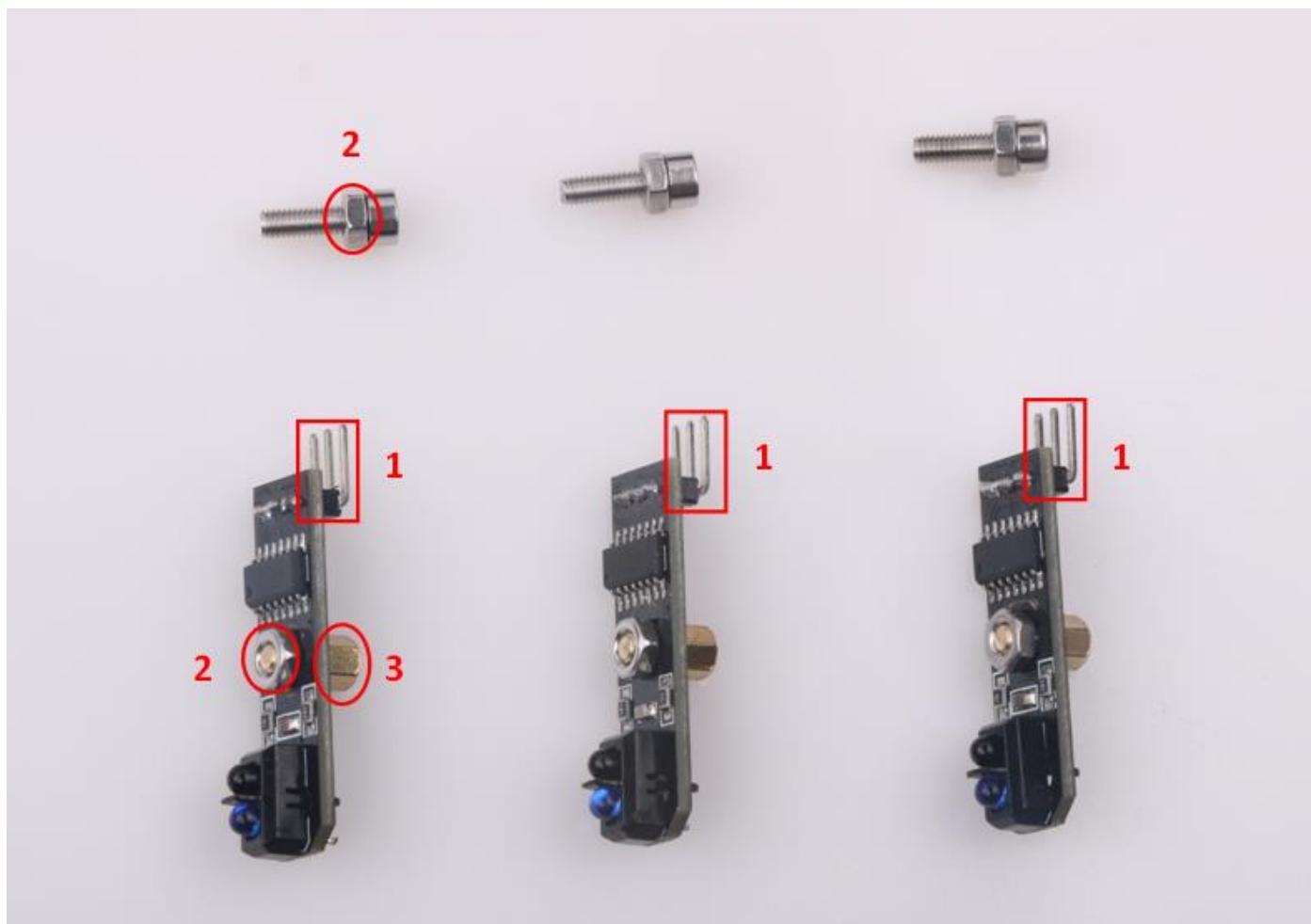


Figure .3.1.16 Diagram of Screw Brackets

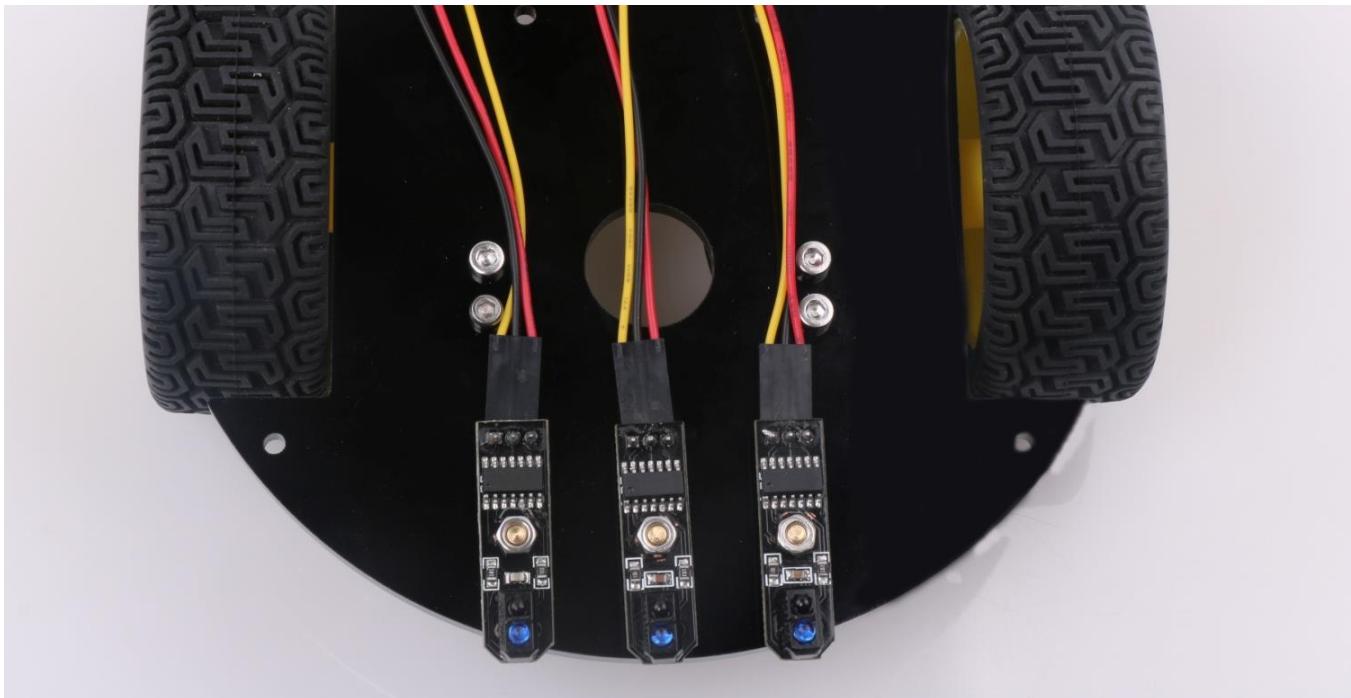


Figure .3.1.17 Tracing module rear schematic

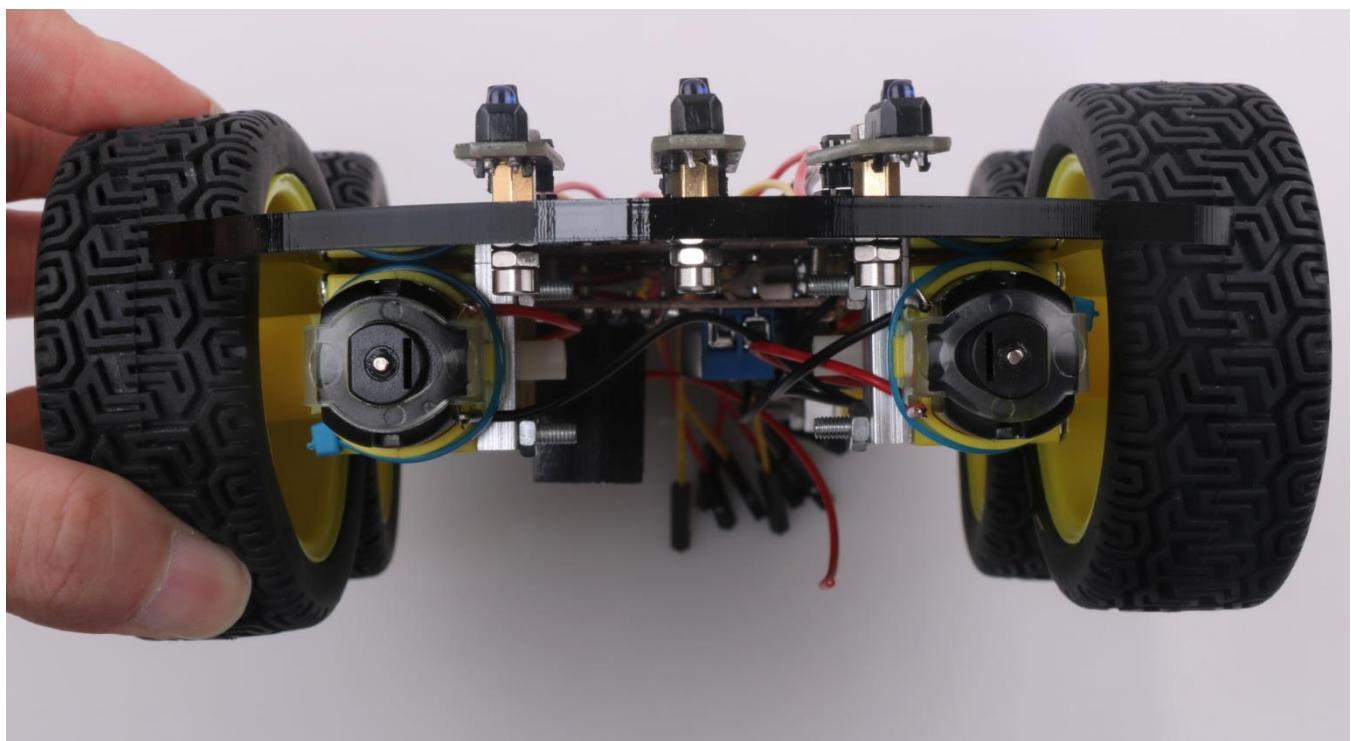


Figure .3.1.17 The completion of the schematic

### 3.1.5 Battery box installation

Install the battery box and the Arduino motherboard is very simple. Note that you need to use the M3 screw to install to “3” and “2” in Figure 3.1.19. After the installation is complete, it is shown in Figure 3.1.20.

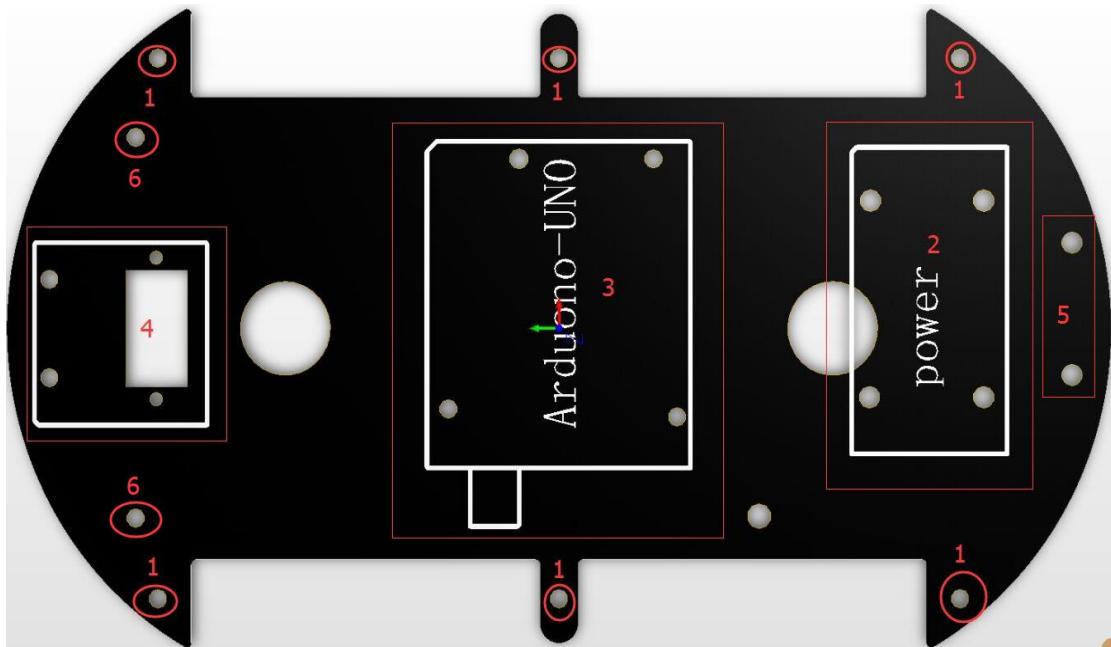


Figure .3.1.19 Diagram of Top Surface Device Installation

### 3.1.6 Keywish Uno R3 Motherboard installation

In order to install flaty, we also install a nut on the UNO baseboard to isolate it as shown below:



Figure 3.1.20 UNO installation diagram

After the completion as shown

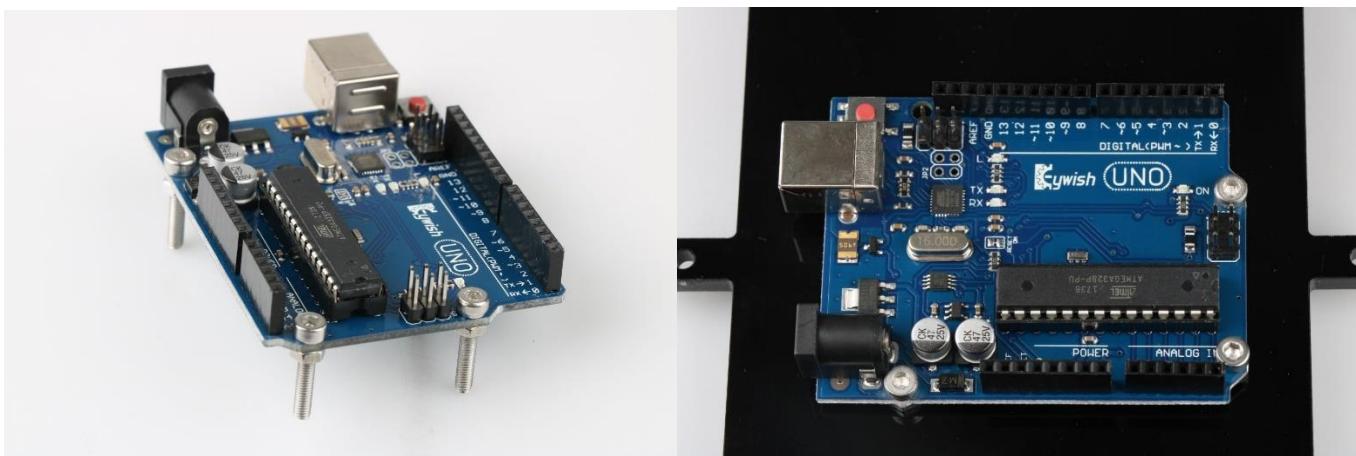


Figure 3.1.21 UNO installation results

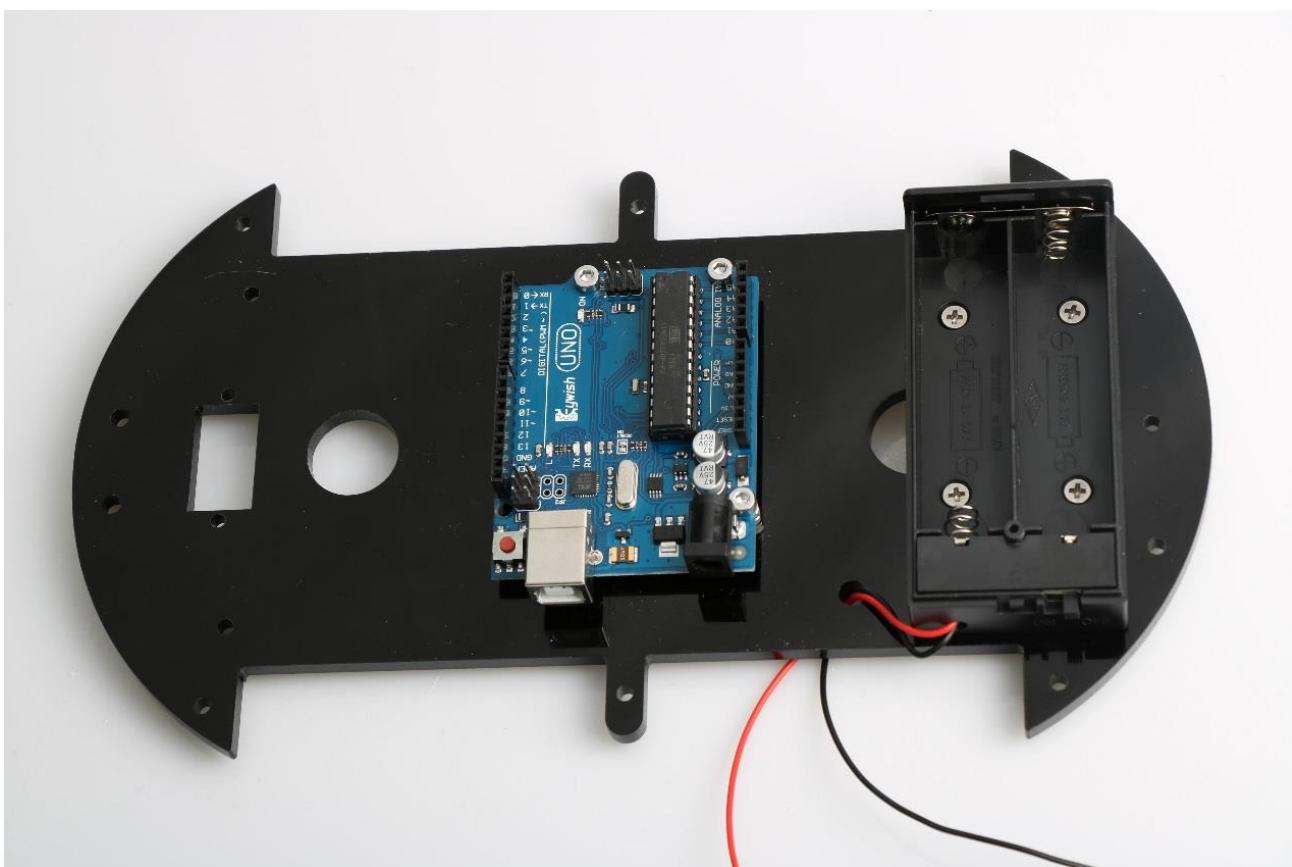


Figure .3.1.22 Diagram of Arduino Mainboard and Battery Box Installation

### 3.1.7 Mounting support screw

The second step is to install the total of 6 support screws which are mainly used to connect two pieces of acrylic board. In Fig .3.1.19, we can see the "1" logo where there are 6 holes, these are the screw fixing holes, The installation is shown in Fig. 3.1.21 and the complete installation is shown in Fig 3.1.22.

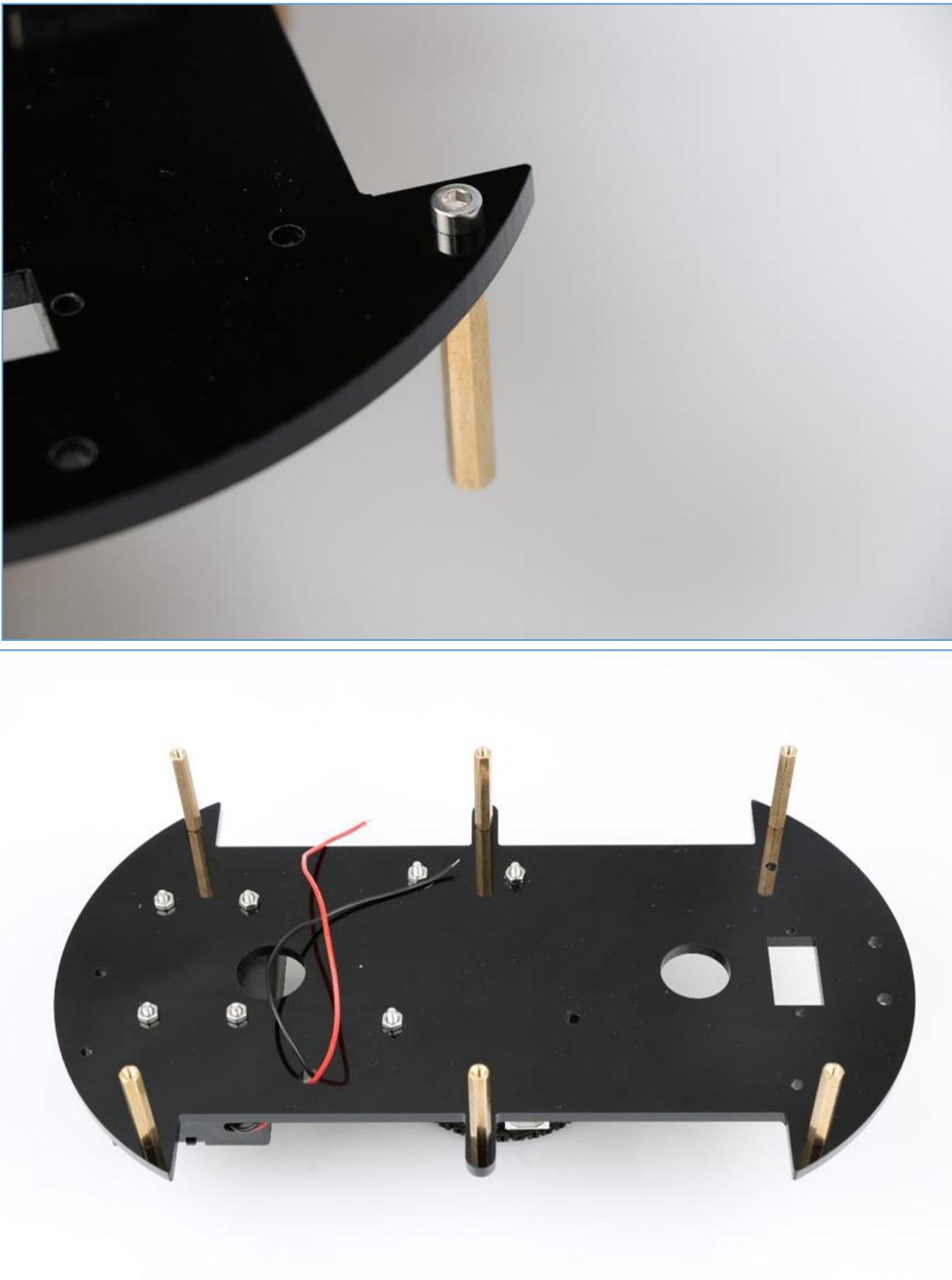


Figure .3.1.23 Diagram of the Pillars

### 3.1.8 Install the Servo and Fixing bracket

In Fig. 3.1.19, the "4" logo is the actuator mounting position. The device used as shown the figure.The complete installation is shown in Fig. 3.1.27.



Figure 3.1.24 Servo Mounting Device List

Step 1, install the servo fixing bracket, that is, install the bracket in the place as shown in the figure, and add the fixing screw.

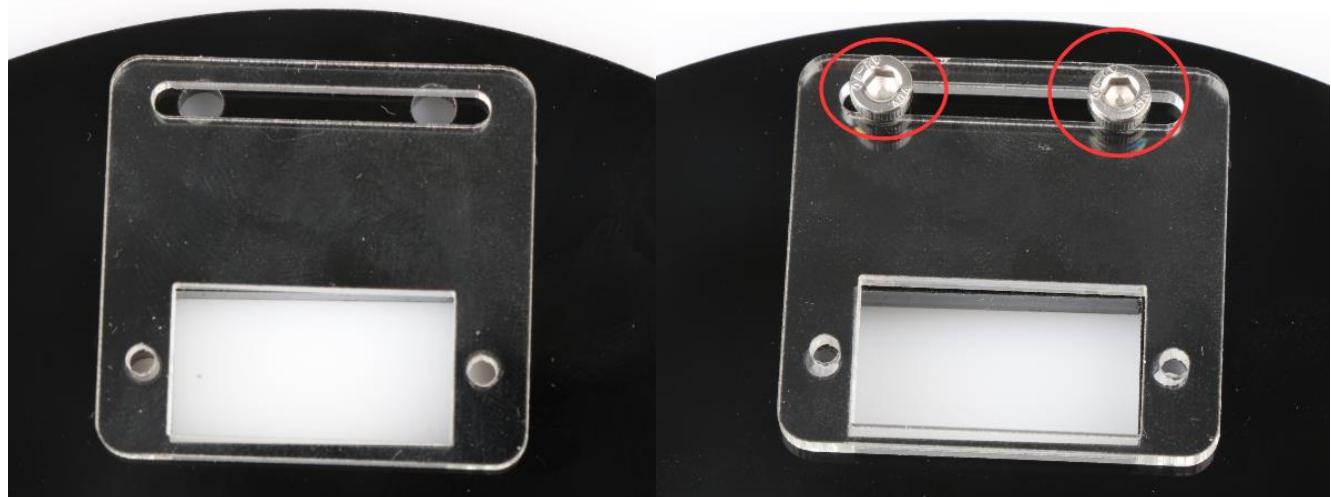


Figure 3.1.25 Servo baseplate Installation

Step 2: Install the servo, install it as shown in the figure.

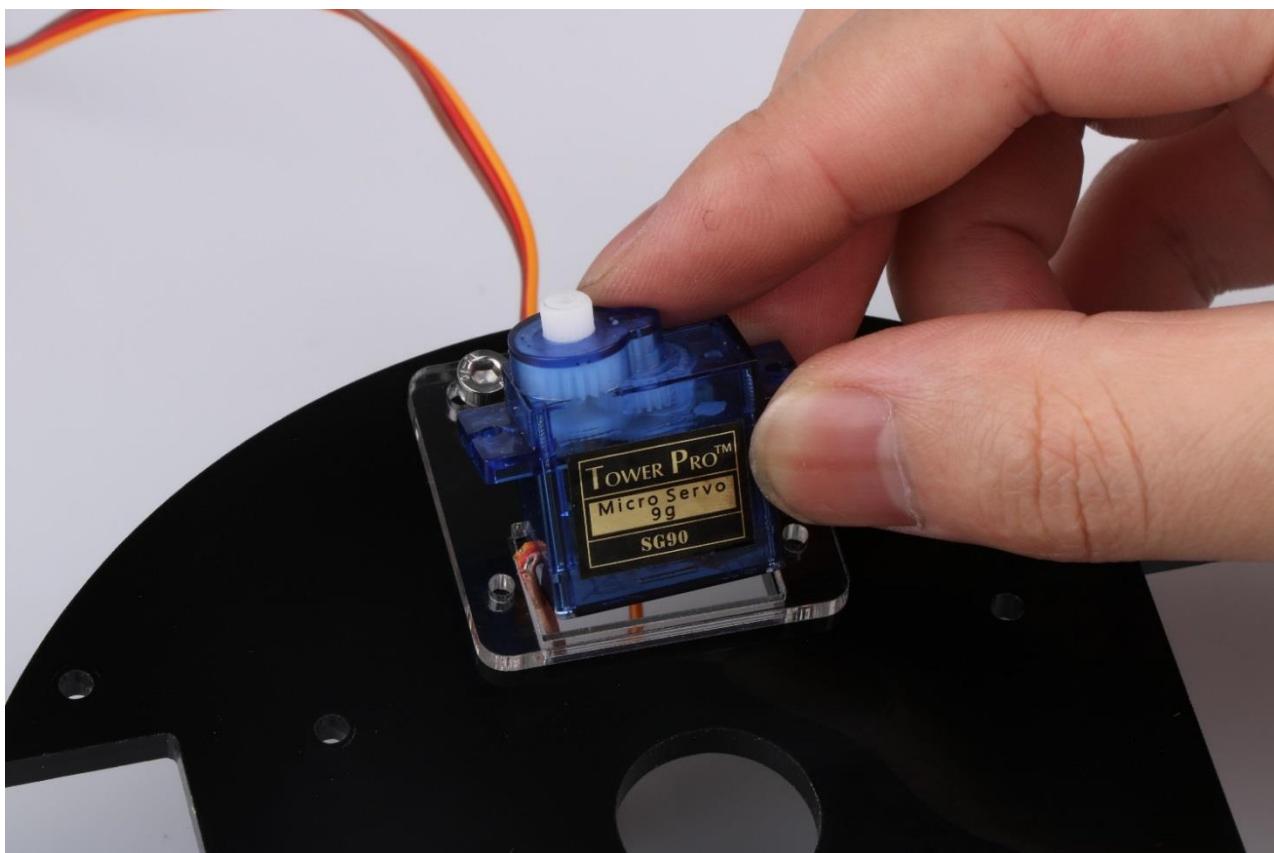


Figure 3.1.26 Servo Installation

Step 3: Use two M2\*12mm screws to fix the servo.

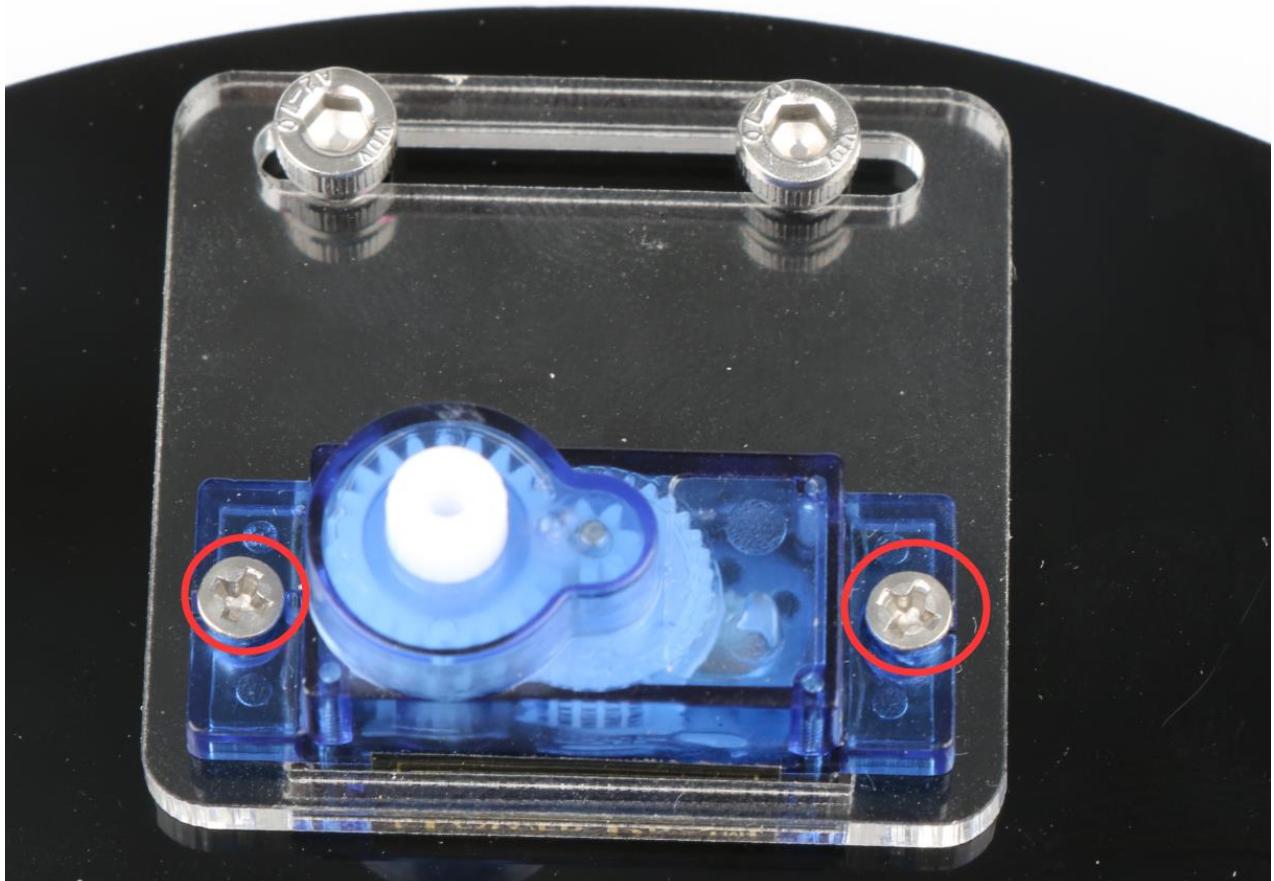


Figure 3.1.27 Servo Fixing

After installing the servo, you can add the ultrasonic module on it. In order to reduce the later steering angle adjustment, we adjust the steering gear to 90 degrees, and copy the following program to the compiler environment (you can also directly open the program in the CD), then connect the signal line(Orange) on steering gear to the 13 IO port on Arduino, After the servo rotates to 90°, we can install the servo bracket on the servo, and after the installation, we can fix it with screws., the installation is shown in Fig.3.1.28.

```
#include <Servo.h>
Servo myservo;// create servo object to control a servo
int pos = 90; // variable to store the servo position
void setup() {
    myservo.attach(13); // attaches the servo on pin 13 to the servo object
}

void loop() {
    myservo.write(pos); // tell servo to go to position in variable 'pos'
    delay(15); // waits 15ms for the servo to reach the position
}
```



Figure 3.1.28 Diagram of Steering Gear Angle Adjustment

### 3.1.9 Installation of ultrasonic

Firstly, fix the bracket on the servo as shown in the figure 3.1.29, and then fix the ultrasonic on the bracket.

Note: To facilitate the ultrasonic connection, it is best to have the ultrasonic module with the terminals facing up.



Figure .3.1.29 Diagram of Ultrasonic Bracket Installation

### 3.1.10 Install infrared obstacle avoidance module

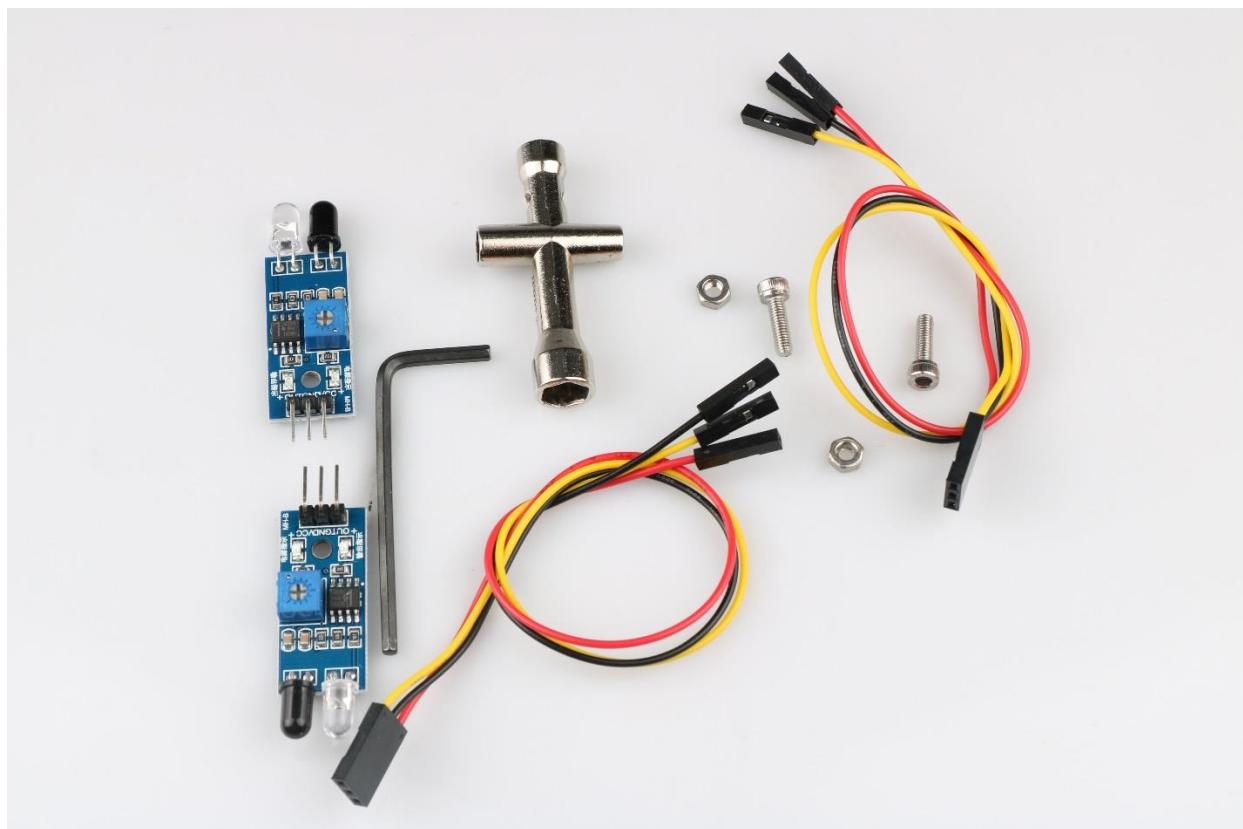


Figure 3.1.30 Infrared Obstacle Avoidance Device List

Install infrared obstacle avoidance module in the two holes marked as "6" in Fig.3.1.19, as shown in Fig.3.1.31.

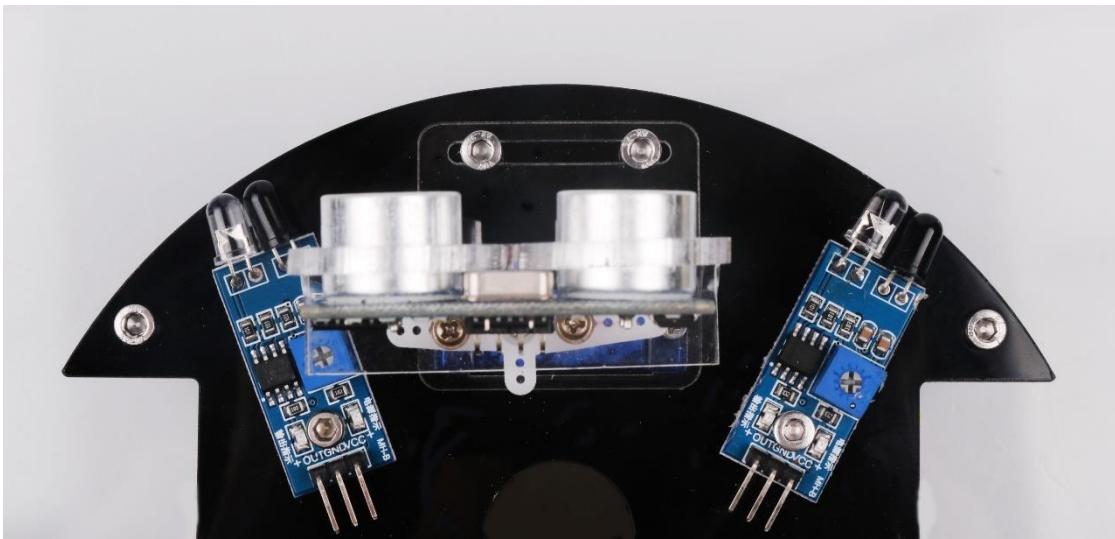


Figure .3.1.31 Diagram of Infrared Obstacle Avoidance Installation

### 3.1.11 Installing infrared remote control receiver

Install infrared remote control receiving head on the Arduino extended board and fixed it with a screw, as shown in Fig.3.1.32. Pay attention to the installation direction.

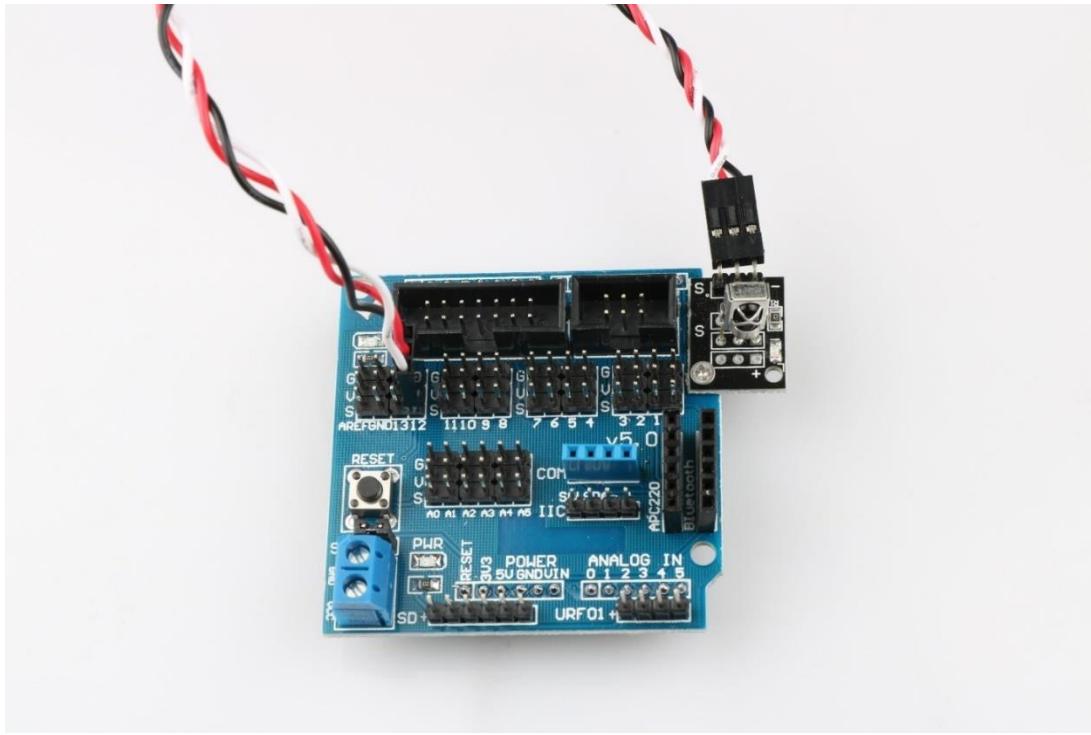


Figure .3.1.32 Diagram of Infrared Remote Control Receiving Head Installation

### 3.1.12 Install voltage display module

Install the voltage display module in the back of battery box to logo "A" marked in Fig.3.1.23, and insert the wire into the hole identified as "B" and out from the hole marked as "C". The complete installation is as shown in Fig.3.1.34.



Figure .3.1.33 Diagram of Voltage Display Module Installation

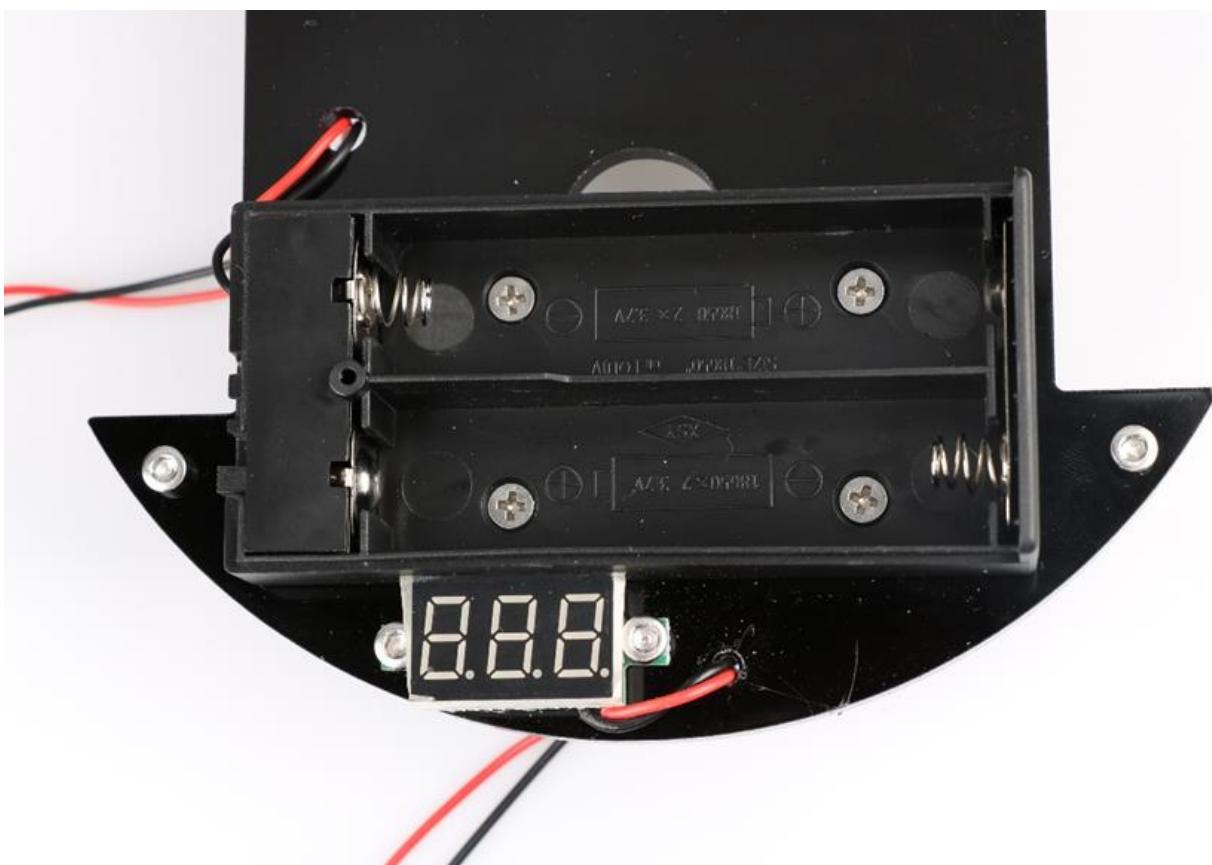


Figure .3.1.34 Diagram of Voltage Display Module Installation

### 3.1.13 Welding power cord

Connect the power cable: Firstly, find the matching two power cables (the same as the wires used by the motor, one red and one black) and connect the two cables to the DC power head. The DC power

connector is shown in Figure 3.1.35. The rubber ring marked as "1" can be removed to open the shell, as shown in Fig.3.1.36. Soldering the wires to the +12V and GND, as shown in Fig.3.1.37.

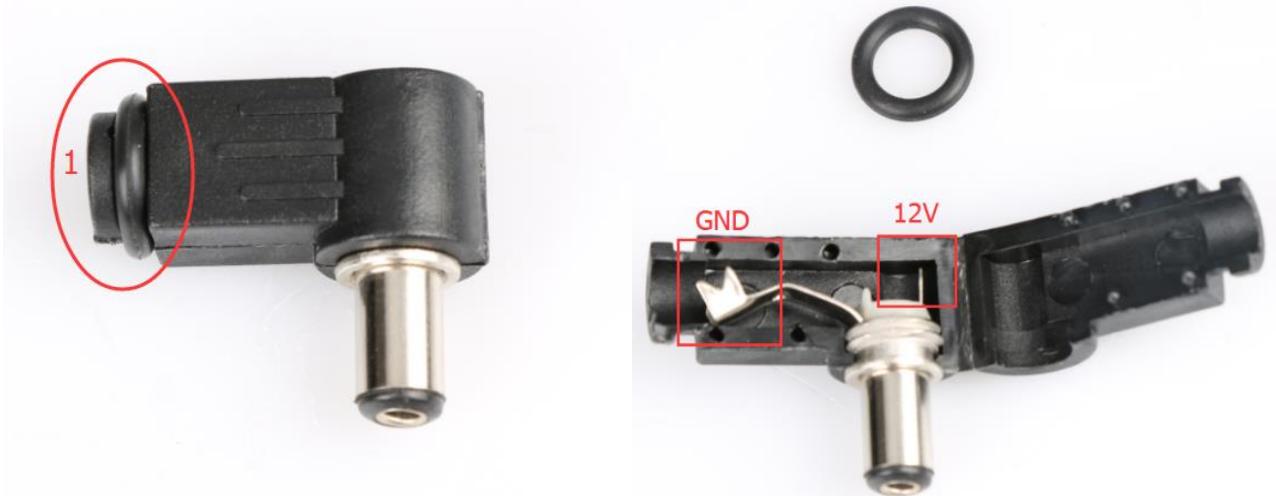


Figure .3.1.35& Figure .3.1.36 DC Power Head



Figure .3.1.37. Wire welding schematic

### 3.1.14 Whole Assembly

The last step is the whole assembly, firstly, inserting the 4Pin wire into IN1-IN4 on the motor drive, and threading the other end wire of the tracing module from the bottom to the top of the car. Then connecting two wires of the battery box and the voltage display module、DC power head to the +12V (red) and GND (black) on the motor drive board.(And the other end of the wire in the ninth step is here) At last, aligning the six columns with the six holes as shown in Fig.3.1.33, then screwing the screws tightly from the bottom and the assembly is completed which is shown in Fig3.1.34 and Fig3.1.35(details of wires connection will be introduced later).

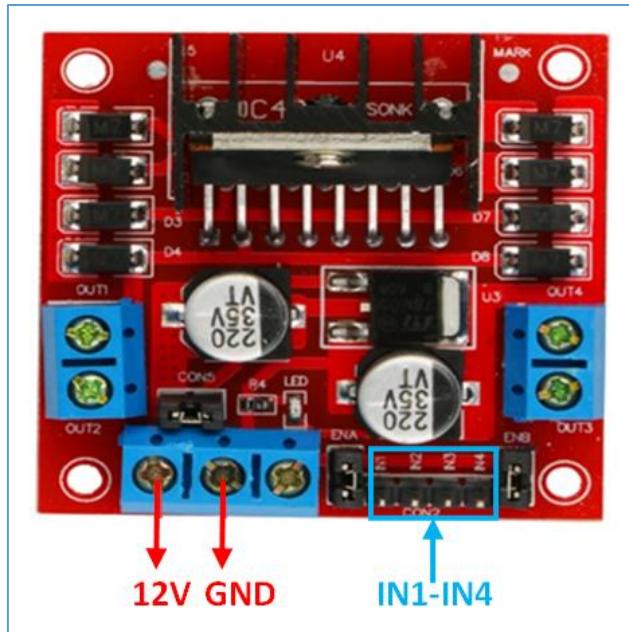


Figure 3.1.38 Motor Drive Connection Diagram

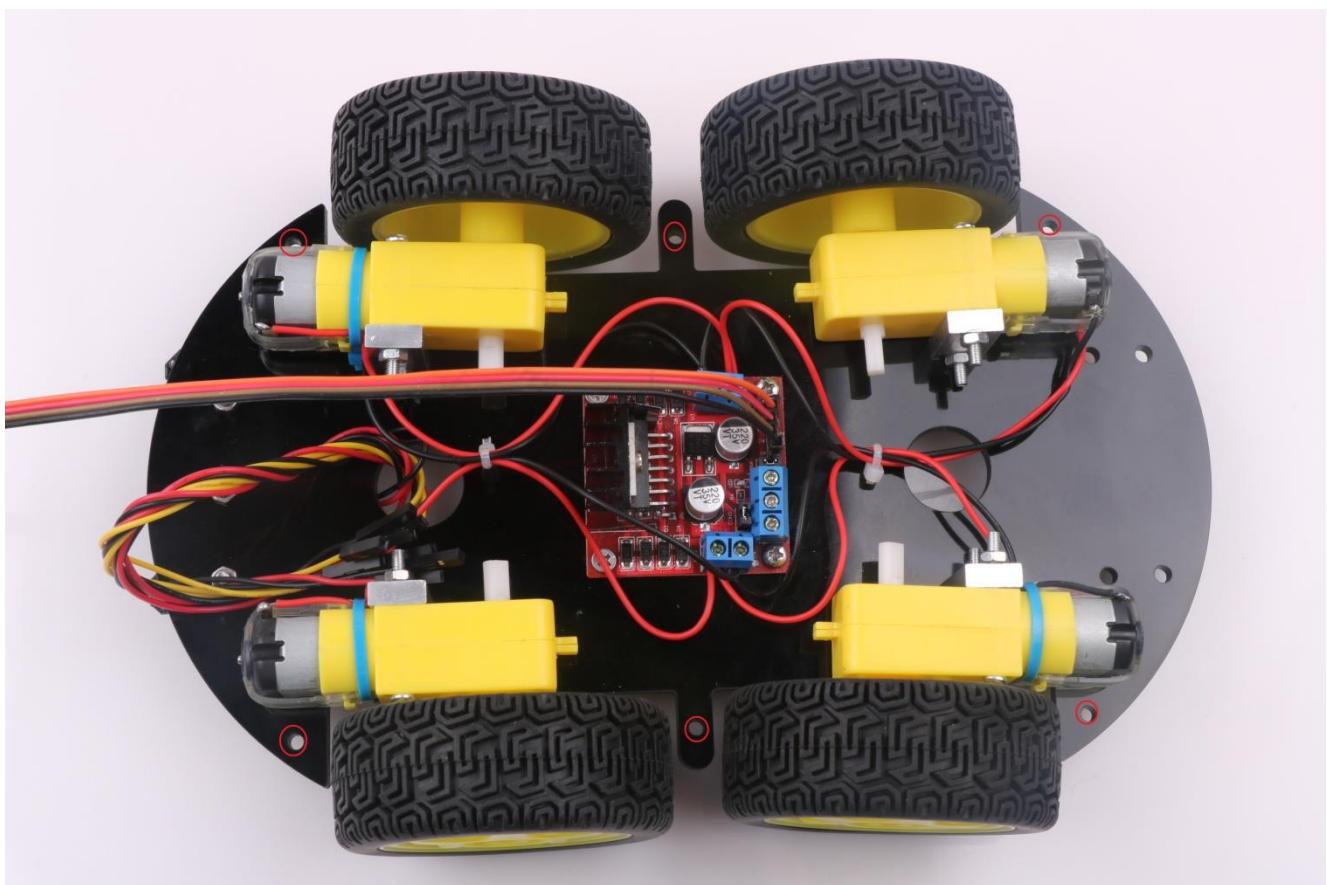


Figure .3.1.39 Diagram of Wires Arrangement

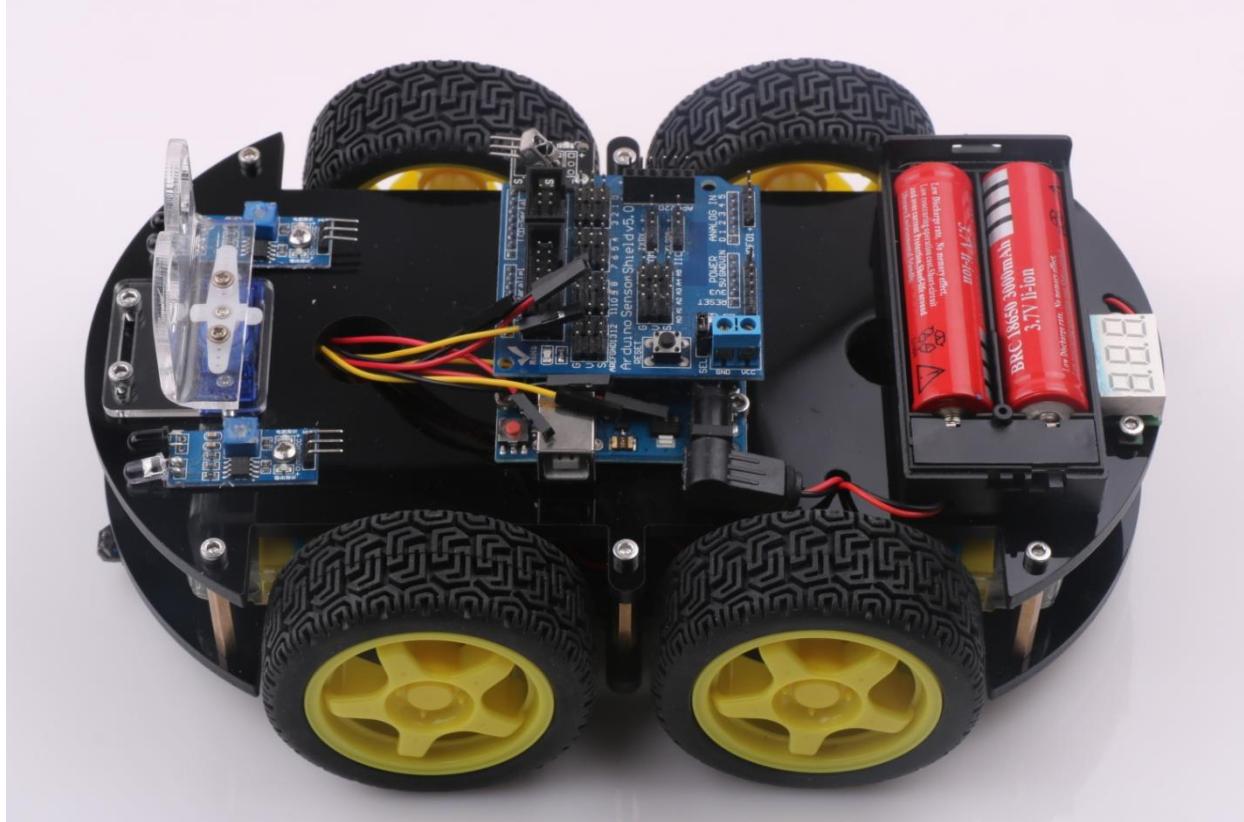


Figure 3.1.40 the Effect of Whole Assembly

### 3.1.15 Expansion board wiring diagram

Through the previous steps, we have completed the installation of the main structure of the car. Now we wire the car to connect the cable. The connection method is as shown in the following figure. For the specific experiment of a certain module, we will introduce it in detail through the following chapters.

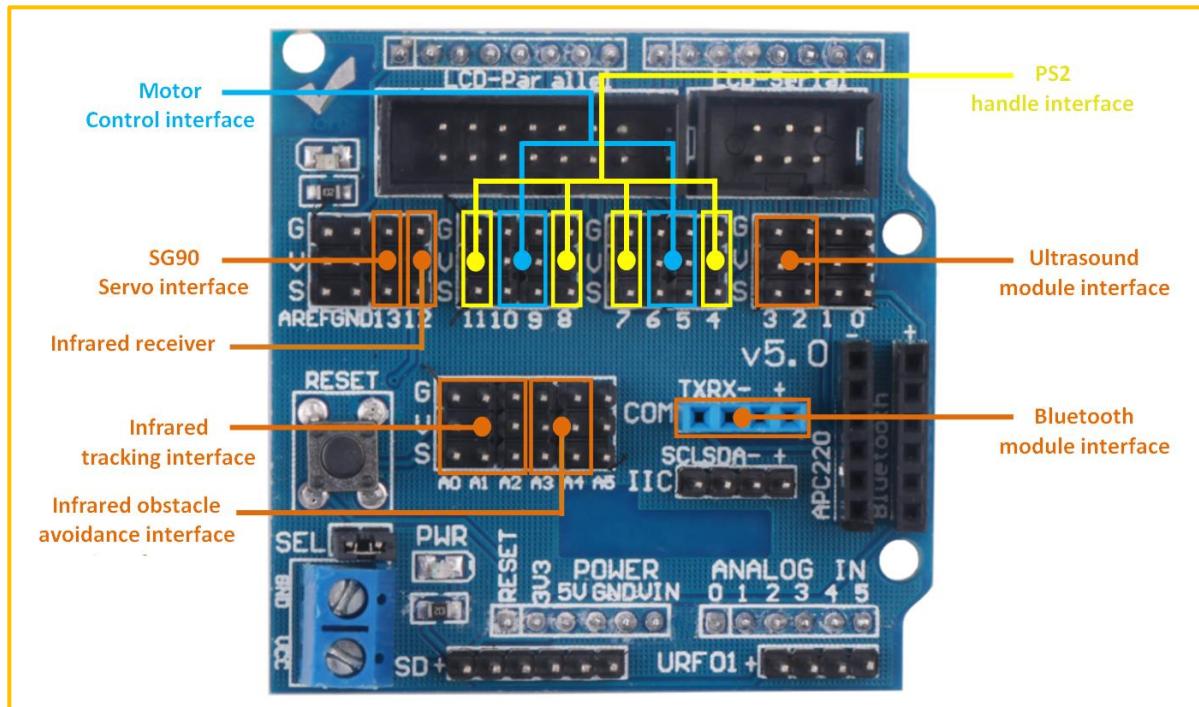
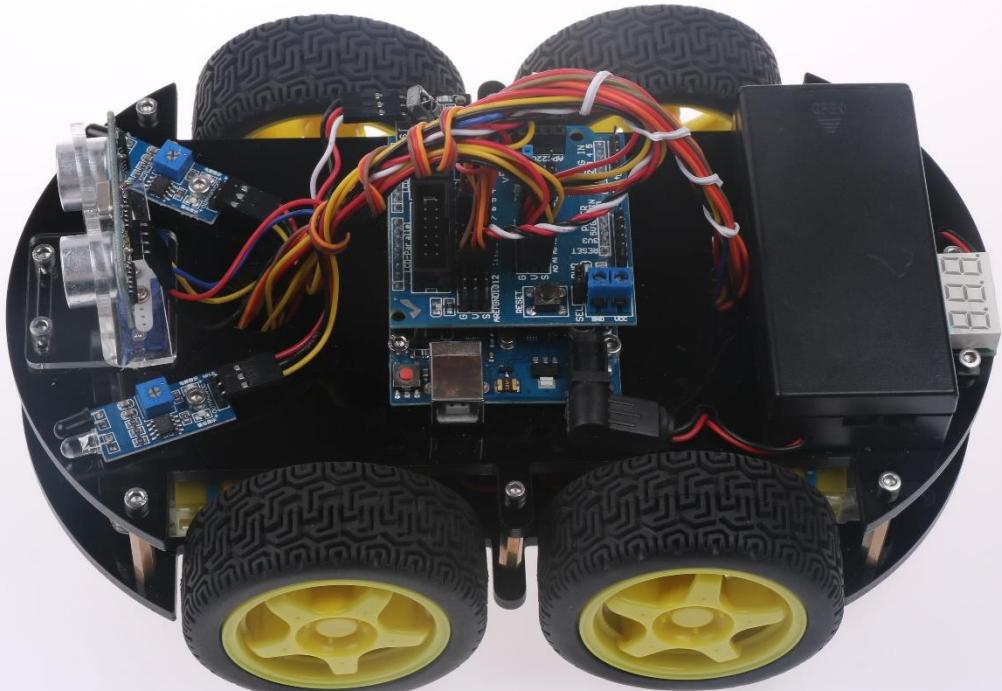


Figure 3.1.41 Expansion Board Connection Diagram

The full installation of the car is as shown below



### 3.1.42 Assembly Connection Diagram

So far, the basic assembly of car has been completed. We believe you have some basic knowledge of your car's structure, function and some modules through a short period of time, then you can achieve the corresponding functions only by downloading the program to the development board, each function has a corresponding program in CD , so please enjoy playing. However, if you can read the program and write your own program, there will be more fun, now let's go to the software section!

## 3.2 Hummer Bot Module experiment

### 3.2.1 Walking Principle of the Car

In the "Hummer-Bot" car, we choose the L298N as the motor driver chip for it is a high voltage and current full-bridge driver chip, the chip uses 15 pins package. It is a special motor driven integrated circuit (two H bridges) with high voltage and current full-bridge driver. And it contains 4 channel logic drive circuit, basically belongs to a kind of two-phase and four-phase special motor drive which contains two H bridges of high voltage large current. The output current is 2A, the maximum current is 4A, the maximum working voltage is 50V, which can drive the load under 46V and 2A, such as high power DC motor, stepper motor, solenoid valve and so on. The chip with two enable control terminals uses the standard logic level to control signals, allows or prohibits the device to work when the input signal is not interfered, it has a logic power input terminal which can enable the internal logic circuit to work under low voltage, and feedback the variation to the control circuit. Especially, the input can be connected directly with the MCU and easily controlled. When the DC motor is driven, the stepper motor can be directly controlled, and it can be turned forward and reversely, which only needs to change the logic level of the input. The pin arrangement is shown in Fig.3.2.1. The pin 1 and 15 can separately connect to the current sampling resistor and form the current sensing signal.

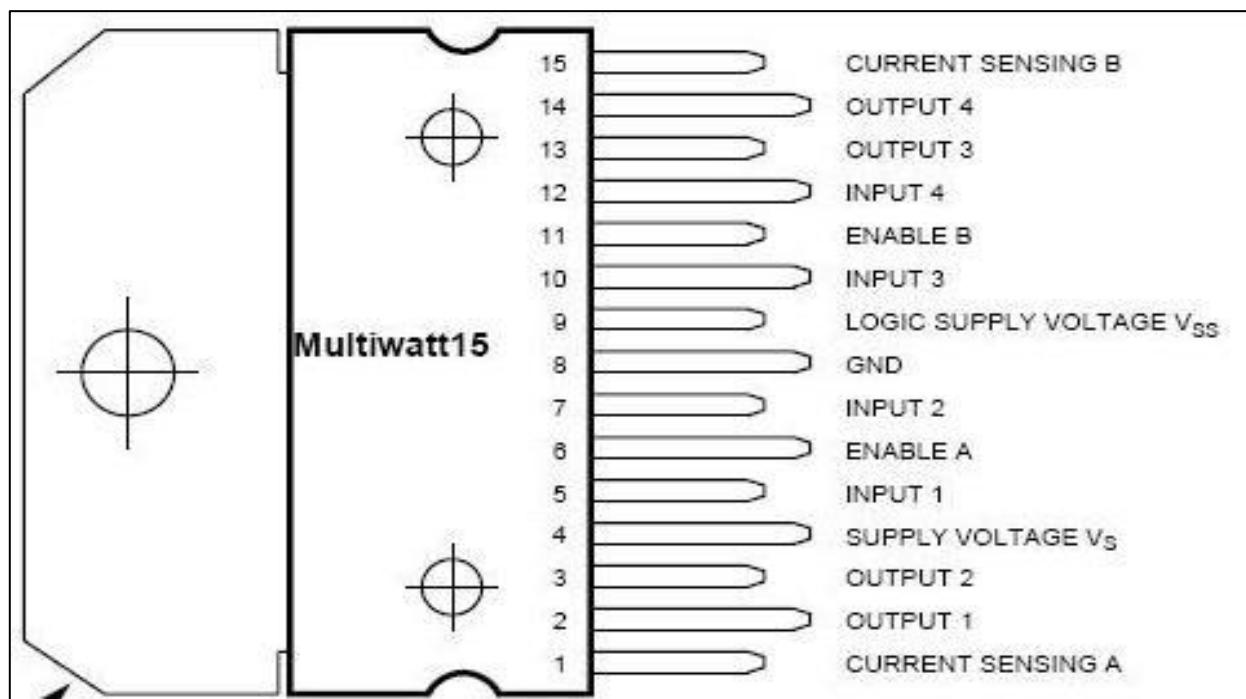


Figure .3.2.1 Arrangement of Chip Pins

L298N can drive 2 motors which are connected between OUT1, OUT2 and OUT3, OUT4. 5, 7, 10 and 12 pin are connected to input control level for controlling the positive and negative rotation of the motor, ENA, ENB are connected to control enable terminal for controlling the running and shutdown of the motor. Its characteristics:

- ◆ Signal indicator
- ◆ The speed is adjustable
- ◆ The strong anti-interference ability with photoelectric isolation
- ◆ Overvoltage and overcurrent protection
- ◆ Controlling of two motors separately
- ◆ Controlling the stepper motor
- ◆ The speed control with PWM pulse width
- ◆ Positive and negative rotation

ENA	IN1	IN2	Motor status
H	H	L	Forward
H	L	H	Reversal
H	IN2	IN1	Quick stop
L	X	X	Stop

Figure .3.2.2 Logic Function Chart

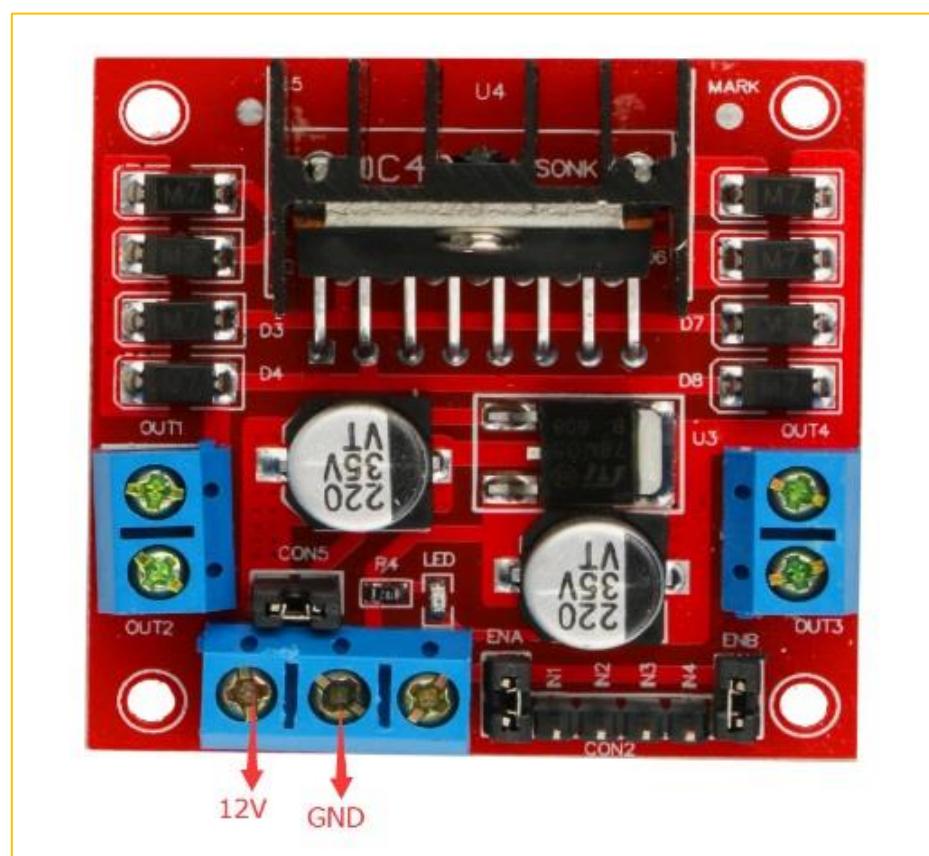


Fig.3.2.3 Module Physical Map

Detailed L298N chip data please refer to “hummer-bot\Document\L298N\_datasheet.pdf”

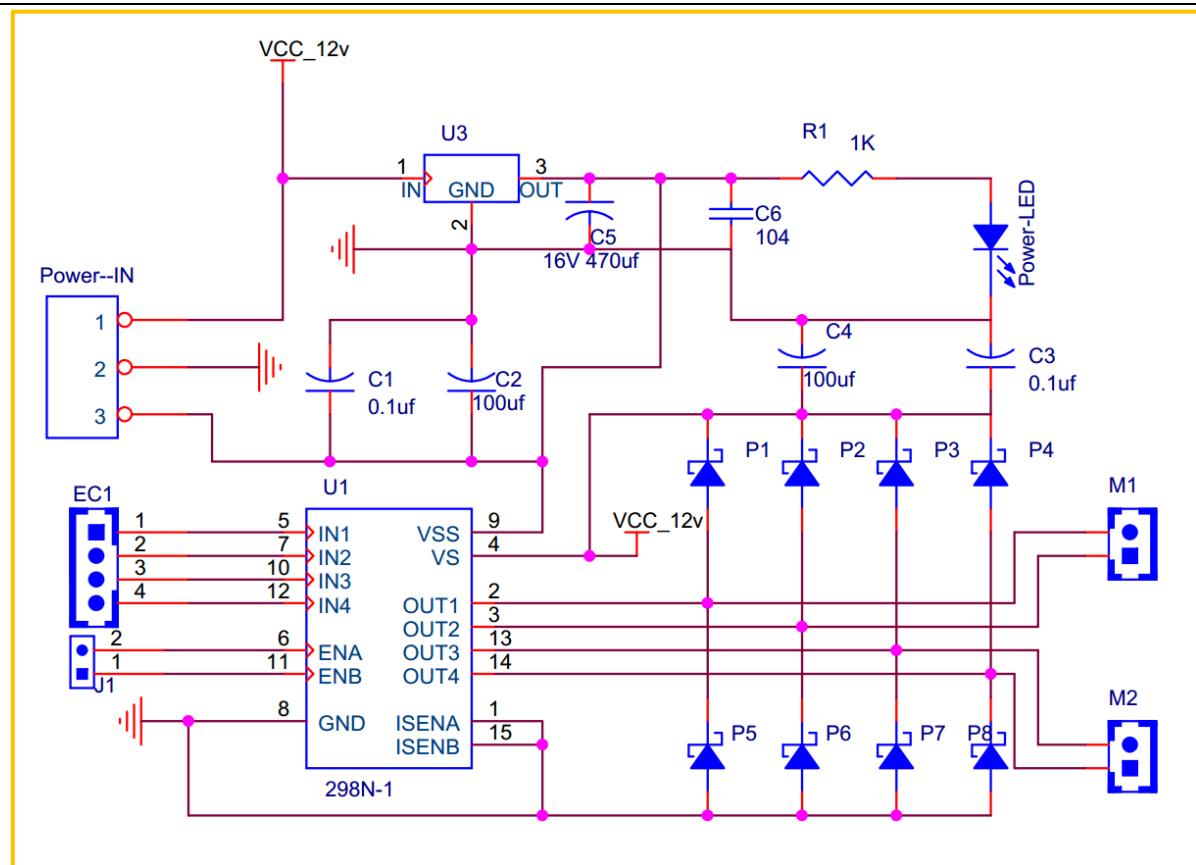


Figure .3.2.4 Schematic Diagram of Motor Drive

Four DC motors with high power L298N drive enable "Hummer-Bot" to run faster than conventional two-wheel car, the acceleration time is shorter and the structure is more stable. However, in the actual application, we need to adjust the speed of the car because of environmental or other factors, yet this does not affect the forward, backward, stop, flexible steering of the car, so we use PWM to control the speed of the motor (Note: PWM is a way to simulate the simulation output via square waves with different duty cycles.), Arduino PWM port outputs a series of square waves with fixed frequency, the power and current of the motor can be amplified after receiving the signal, thereby changing the motor's speed. The speed coordination of two motors on the right and left wheels can achieve the forward, backward, turning and other functions of the car. Figure 2.4.5 shows the sequence diagram of PWM duty cycles.

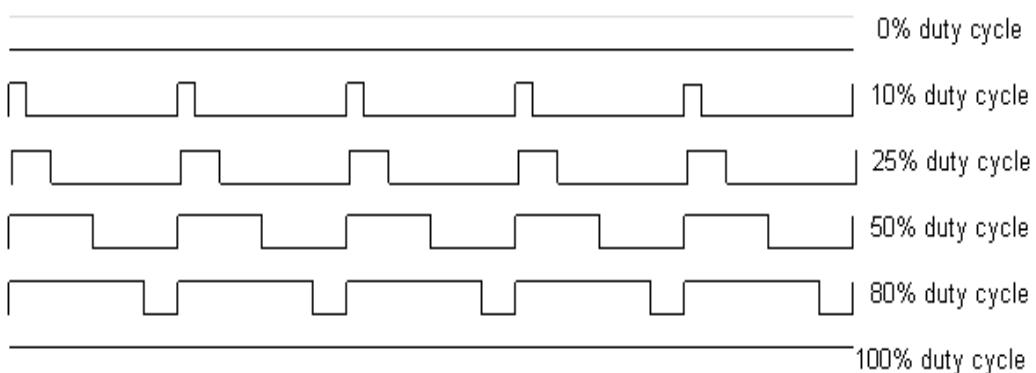


Figure .3.2.5 Sequence Diagram of PWM Duty Cycles

In Arduino, analog voltage can't be output, only 0 or 5V digital voltage value, we can use high resolution counter and the duty cycles of the square wave modulation method to encode a specific level of

analog signal. The PWM signal is still digital, because at any given time, the full amplitude of DC power supply is either 5V (ON) or 0V (OFF). The voltage or current source is added to the analog load with a ON or OFF repetitive pulse sequence. When the DC power supply is added to the load, the power supply is on, otherwise the power supply is off. As long as the bandwidth is enough, any analog value can use PWM to encode. The output voltage value is calculated by the on and off time. Output voltage = (turn-on time / pulse time) \* maximum voltage. Fig.2.4.6 shows the corresponding voltage to the pulse change.

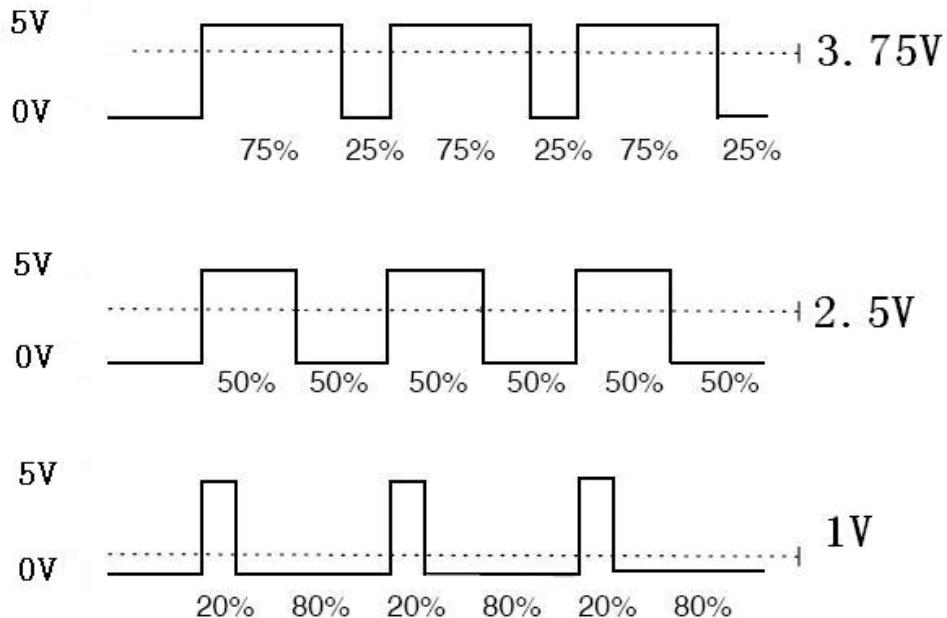
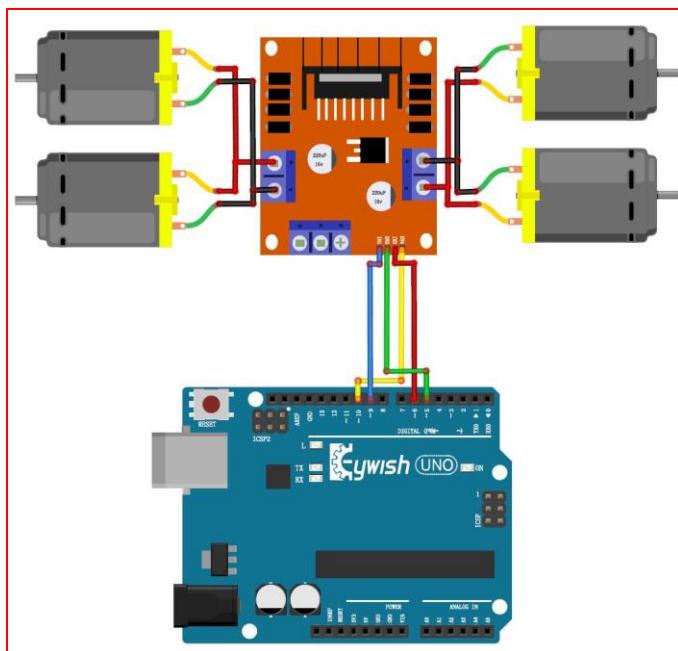


Figure .2.4.6 Relation between Pulse and Voltage

In the "Hummer-Bot" car experiment, we use Arduino UNO R3 as the main control board. By referring to the chip data, we will know that Arduino UNO has 6 PWM pins, namely digital interfaces 3, 5, 6, 9, 10, 11, and we select 5, 6, 9, 10 as the motor control IO, the connection is shown in Fig.2.4.7.

The following table shows the correspondence between L298N and Uno board:



L298N	Arduino Uno
IN1	D6
IN2	D10
IN3	D5
IN4	D9

Figure .2.4.7 Arduino and L298N driver board connection diagram and connection table

The L298N and Arduino expansion board wiring is as follows:

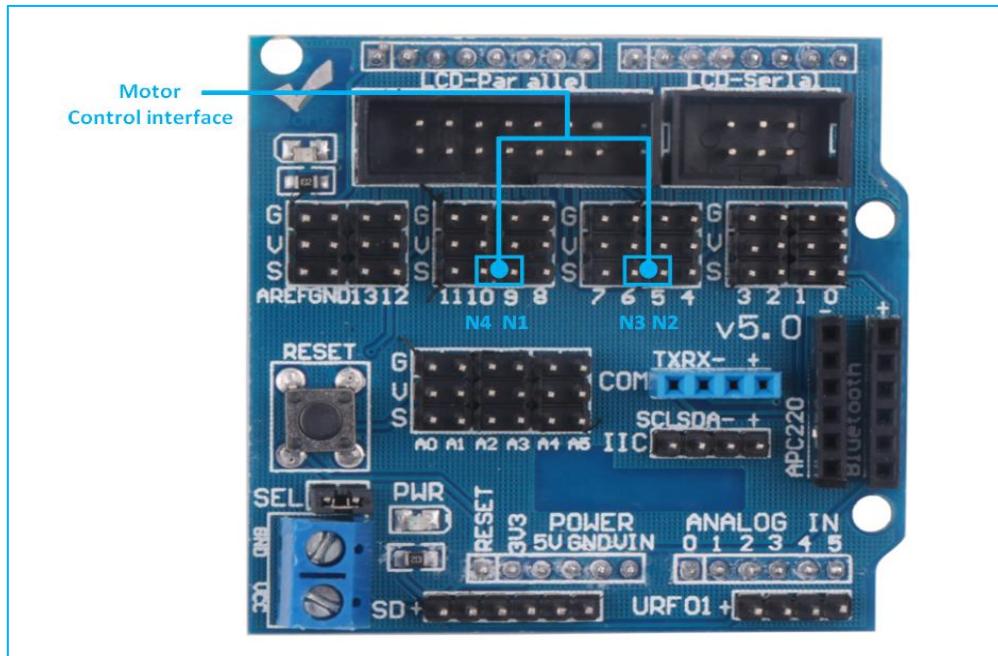


Figure 3.2.8 L298N and Arduino Expansion Board Connection Diagram

After the connection, we do not know whether the motor can work normally or not, so we need to do a simple test by copying the following code (You can also open the program in the CD directly.) into the IDE development environment and downloading to the development board. And turning on the power (power connection is introduced the tenth and eleventh steps in 3.1.2) to observe the wheels rotation, if "going forward 5s----stopping 1s---- going back 5s---- stopping 1s----turning left 3s----stop 1s----turning right 3s" are normal, the connection is correct, otherwise the polarities of the motor may be reversed, then you need to adjust slightly.

Program flow chart is as follows:

L298N	Arduino Uno
IN1	D6
IN2	D10
IN3	D5
IN4	D9

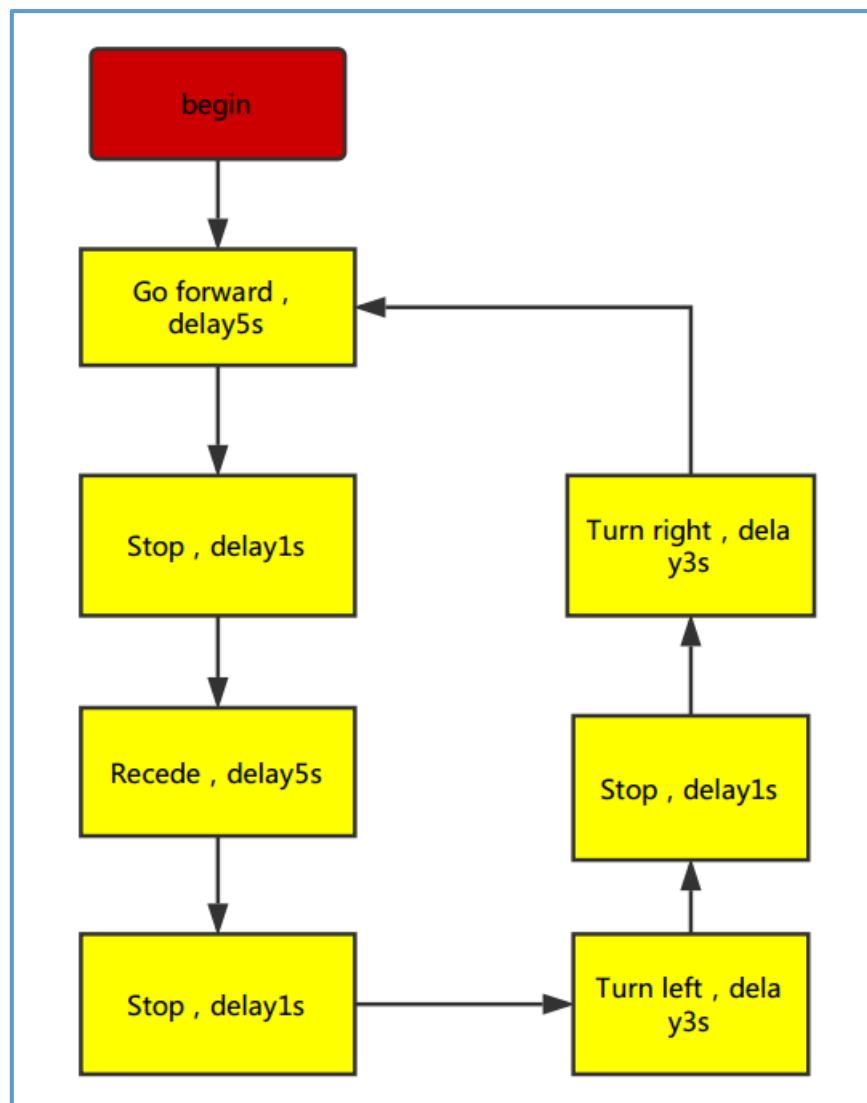


Figure 3.2.9 Motor Test Flow Chart

Note: This test and IO selection are only for reference, you can choose other IO ports or use other wiring methods according to your own ideas.

```
int E1 = 5; //PWMA
int M1 = 9; //PWMA
int E2 = 6; //PWMB
int M2 = 10; //PWMB
void setup() {
}
void loop() {
    analogWrite(M1, 0);
    analogWrite(E1, 150); //the speed value of motorA is 150
    analogWrite(M2, 0);
    analogWrite(E2, 150); //the speed value of motorB is 150
    delay(5000);
    //***** forward *****/
    analogWrite(M1, 0);
    analogWrite(E1, 0); //the speed value of motorA is 0
    analogWrite(M2, 0);
    analogWrite(E2, 0); //the speed value of motorB is 0
    delay(1000);
```

```

//*****//stop
analogWrite(M1, 150); //the speed value of motorA is 150
analogWrite(E1, 0);
analogWrite(M2, 150); //the speed value of motorA is 150
analogWrite(E2, 0);
delay(5000); //*****//back
analogWrite(M1, 0);
analogWrite(E1, 0); //the speed value of motorA is 0
analogWrite(M2, 0);
analogWrite(E2, 0); //the speed value of motorB is 0
delay(1000);
//*****//stop
analogWrite(M1, 0);
analogWrite(E1, 180); //the speed value of motorA is 180
analogWrite(M2, 180); //the speed value of motorB is 180
analogWrite(E2, 0);
delay(3000);

//*****//left
analogWrite(M1, 0);
analogWrite(E1, 0); //the speed value of motorA is 0
analogWrite(M2, 0);
analogWrite(E2, 0); //the speed value of motorB is 0
delay(1000);
//*****//stop
analogWrite(M1, 200); //the speed value of motorA is 200
analogWrite(E1, 0);
analogWrite(M2, 0);
analogWrite(E2, 200); //the speed value of motorB is 200
delay(3000); //***//right
}

```

By now, the car can move normally, next we will add several common sensor modules.

### 3.2.2 Infrared Obstacle Avoidance

#### 3.2.2.1 Introduction of Infrared Obstacle Avoidance Sensor

Infrared obstacle avoidance module is a pair of infrared transmitting and receiving tubes, the former launches a certain frequency infrared, the receiving tube will receive the reflected infrared when the infrared detects the obstacles. After the signal is processed by the comparator circuit, the green LED lights, and the signal output port outputs digital signal at the same time (a low level signal). The detection distance can be adjusted through the potentiometer knob, the effective distance range is 2-30cm, the working voltage is 3.3V-5V. The sensor uses infrared, so the anti-interference ability is very strong, the measurement accuracy is very high when the distance is moderate. In addition, the module can be assembled easily and used

conveniently, it can be widely used in robot obstacle avoidance, car obstacle avoidance and the black&white line tracing and many other occasions.

### 3.2.2.2 Working Principle

1, The module output port OUT can be directly connected with the IO port of the microcontroller, and directly drive a 5V relay; the connection mode is: VCC-VCC; GND-GND; OUT-IO (A3 and A4), as shown in Fig.3.2.9 and Chart 3.2.1.

2, The module uses the 3-5V DC power as power supply. When the power is on, the indicator will light.

3, The diameter of installation hole is 3mm, you can use the same size screws (screws in the kit).

Pin wiring definition (only for reference, you can define according to your own ideas):

arduino Uno	Infrared Obstacle Avoidance Module
VCC	VCC
GND	GND
A3	The left module
A4	The right module

Chart 3.2.1 Pin Wiring Definition

### 3.2.2.3 Module Parameters

The working principle of infrared obstacle avoidance sensor is very simple, that is the reflection property of objects. In a certain range, if there is no obstacle, the infrared ray emitted will gradually weaken because of the farther distance of transmission, and finally disappear. If there are obstacles, the infrared will be reflected to the receiving head. As soon as the sensor detects the signal, it can confirm that there are obstacles in front of the circuit board, the green indicator will light, the OUT port continuously outputs low level signal to MCU at the same time, the MCU conducts a series of analysis to ensure that the two wheels of car works properly and avoids the obstacle beautifully. The schematic diagram of the sensor is shown in Fig.3.2.8. Infrared detector can be divided into active and passive according to its working mode.

Active infrared detector is equipped with infrared light source, it can detect the location of the object through covering the light source, reflection, refraction and other optical means.

Passive infrared detector has no light source, and it can measure the position, temperature, or infrared imaging of the detected object by receiving the characteristic spectral radiation of the detected object.

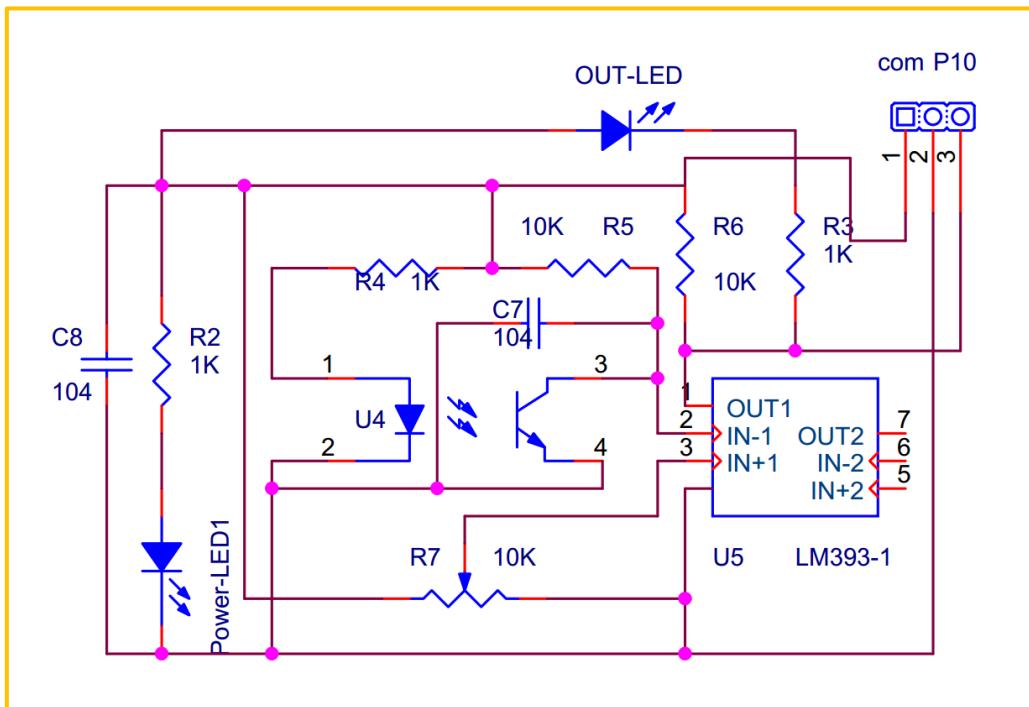


Figure .3.2.10 Infrared obstacle avoidance schematic diagram

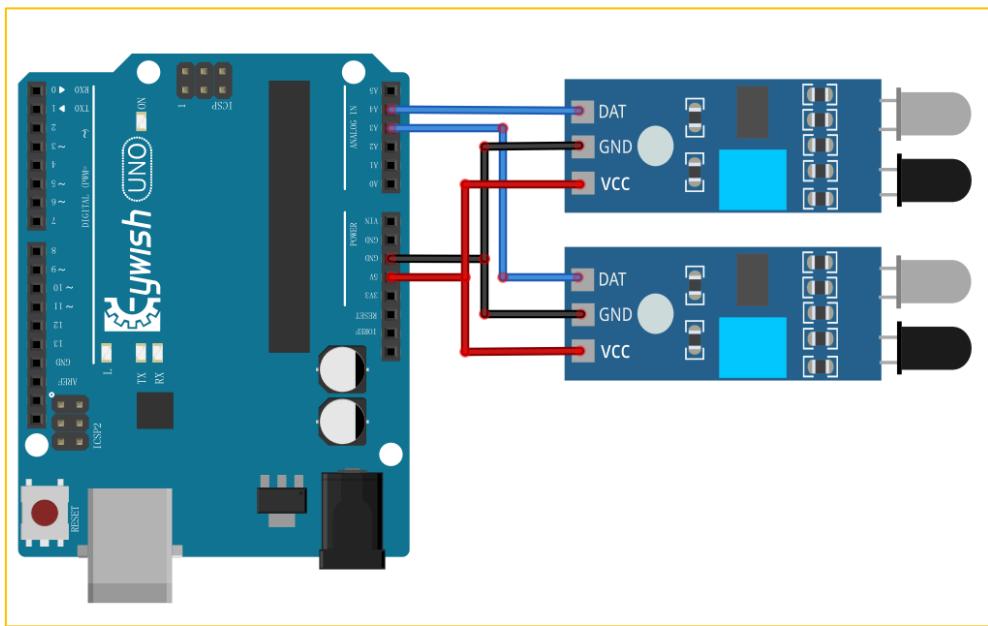


Figure .3.2.11 Connection of Arduino and Sensor

Note: This module can adjust the detection distance by the potentiometer, the detection distance is 2-30cm, if it is found that the distance detection is not very sensitive, you can use the potentiometer to achieve the desired results (rotating the potentiometer clockwise will increase the detection distance; counterclockwise will decrease), it is shown in Fig.3.2.12.

Manual adjustment is shown in the following diagram:

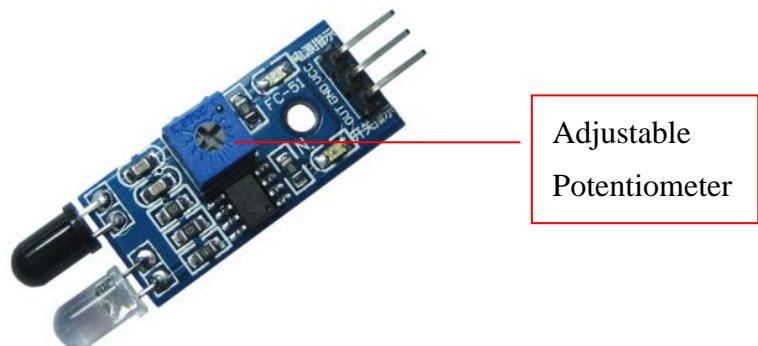


Figure .3.2.12 Diagram of Distance Detection Adjustment

#### 3.2.2.4 Wire connection

As the figure shown below, the upper column is the "GND" interface, the middle column is the "VCC" interface, and the lower column is the "OUT" interface, where "A3" corresponds to the "OUT" of the left infrared obstacle avoidance, and "A4" corresponds to the right infrared obstacle avoidance. "OUT".

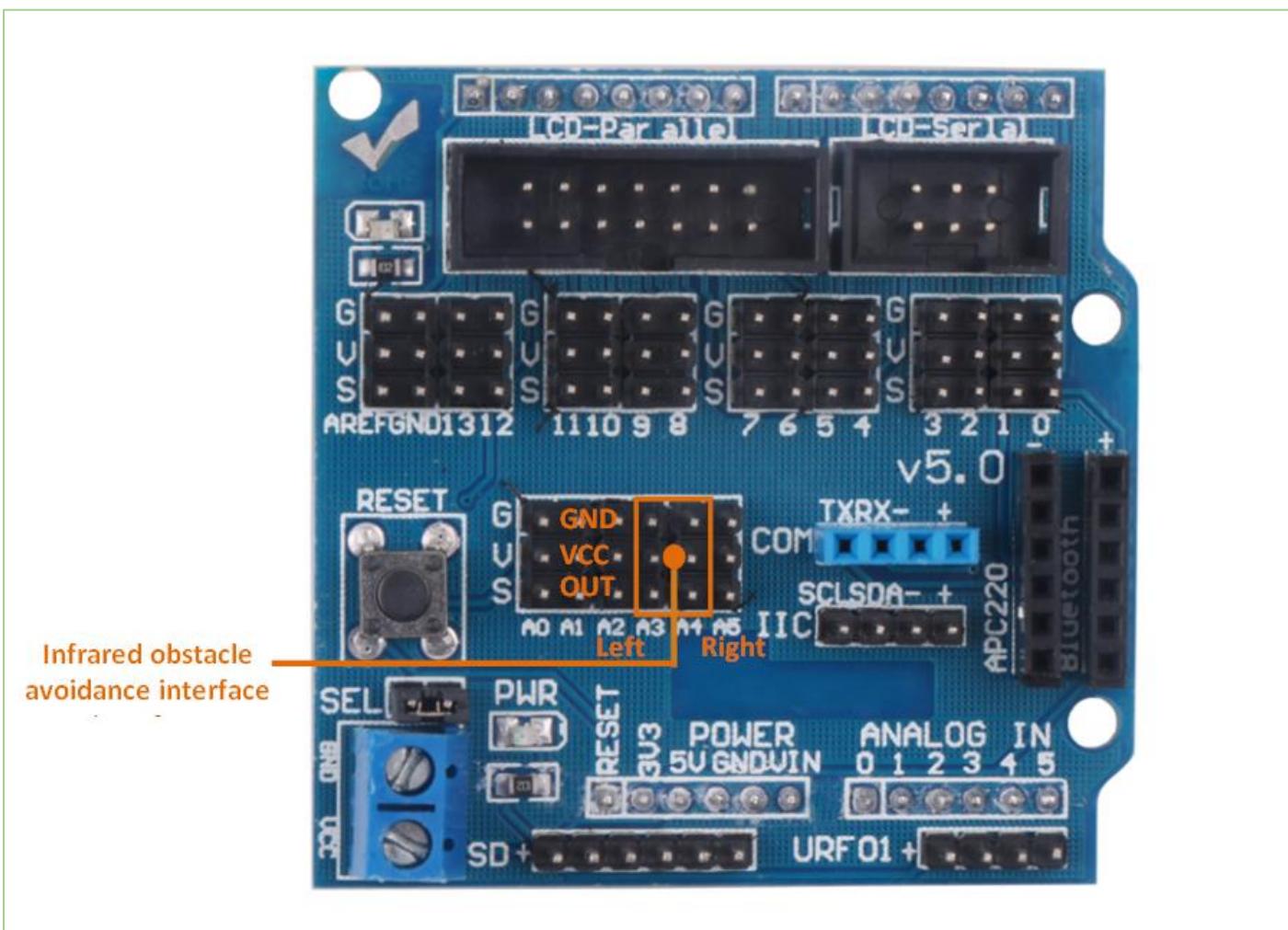


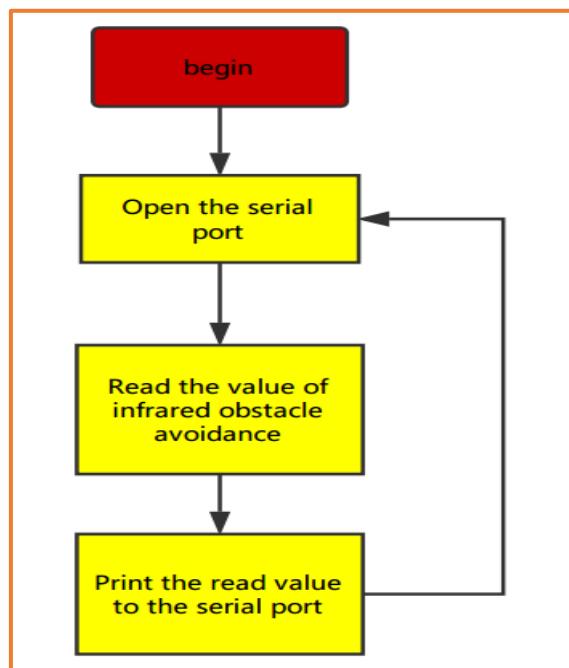
Figure 3.2.13 Wire connection diagram

### 3.2.2.5 Experimental Procedures

- 1, Fixing the two sensors on the car and connecting them to Arduino with wires.(Already done)
- 2, Testing the sensitivity of module, namely opening the switch on the battery box and the indicator will light, placing obstacles 10cm away from the infrared tubes, adjusting the potentiometer until the output indicator lights up.
- 3, Module test. Copying the following code to the IDE compiler environment (you can also open the program directly in the CD), downloading it to the development board, opening the serial port monitor (baud rate is 9600) and observing the changes of data when there is an obstacle (Figure 3.2.14) and no obstacle (Figure 3.2.15).

Note: Here we connect the infrared obstacle avoidance signal output port to the analog port on Arduino (A0-A5), so the serial port prints out analog value, you can connect it to digital port (2-13), and the serial port will only print out "0" and "1".

Program flow chart is as follows:



```
const int leftPin = A3;
const int rightPin = A4;
int dl;
int dr;

void setup() {
    Serial.begin(9600);
    pinMode(leftPin, INPUT);
    pinMode(rightPin, INPUT);
    delay(1000);
}

void loop() {
    dl = analogRead(leftPin);
    dr = analogRead(rightPin);
    Serial.print("left:");
    Serial.print(dl);
    Serial.print("  ");
    Serial.print("right:");
    Serial.println(dr);
}
```

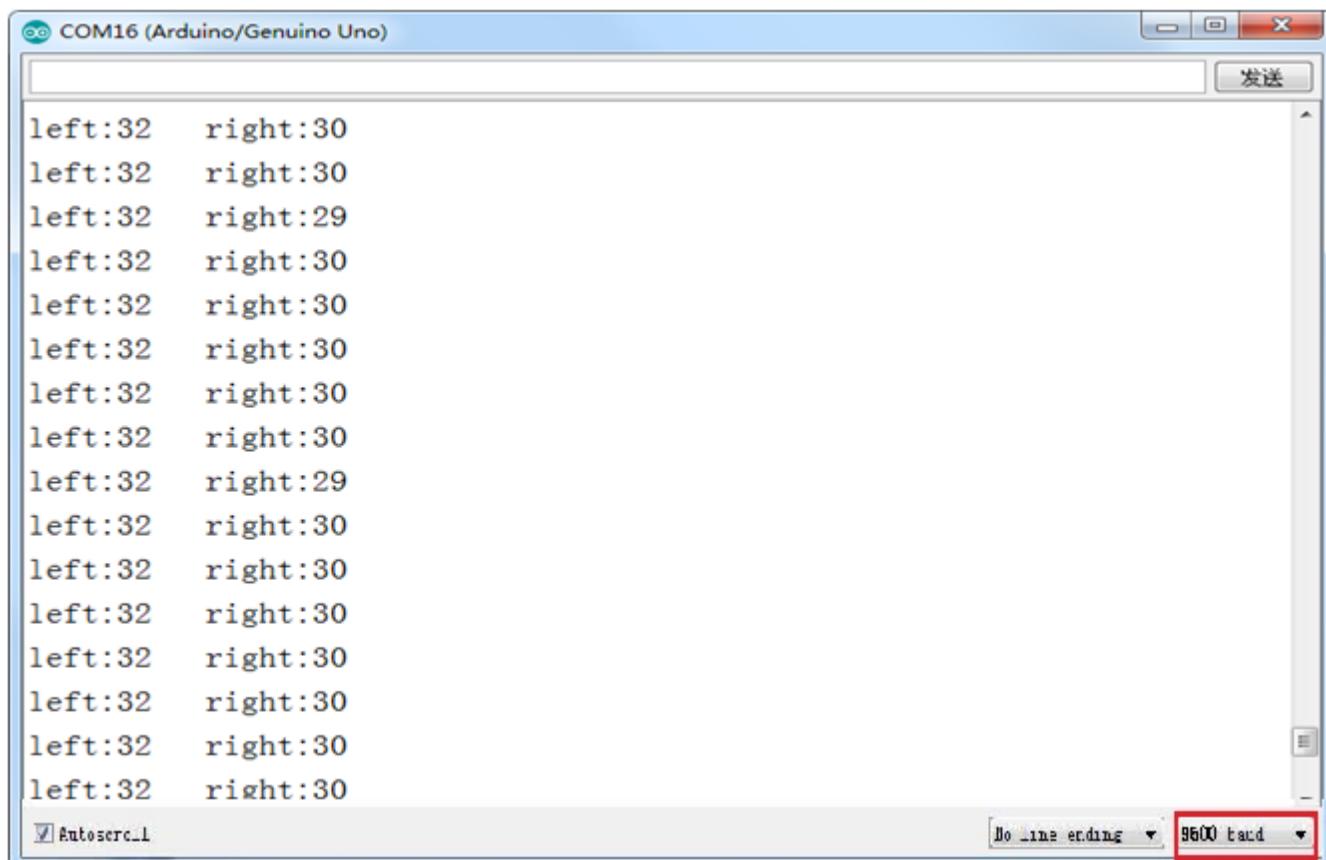
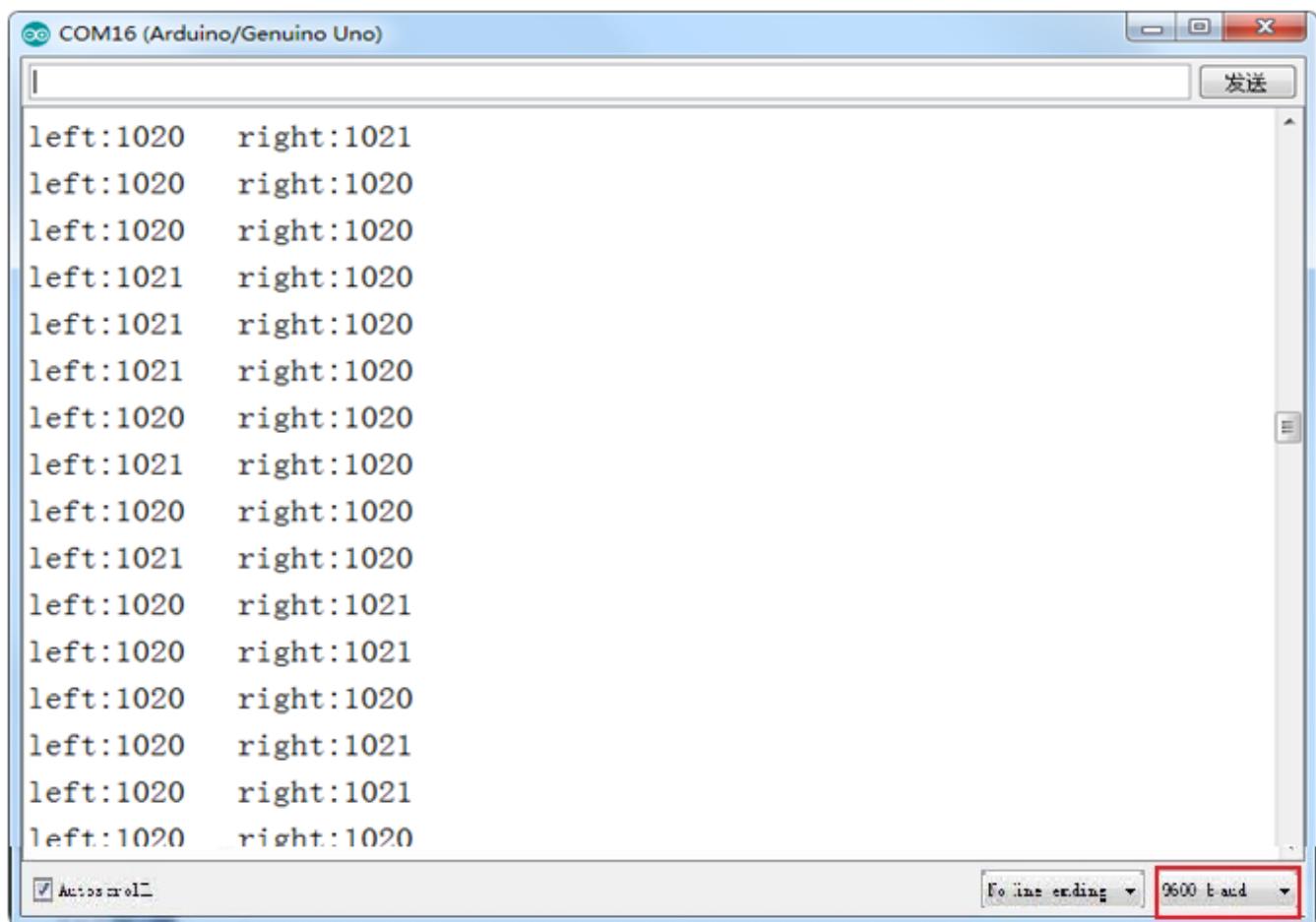


Figure .3.2.14 Diagram of Data with Obstacles

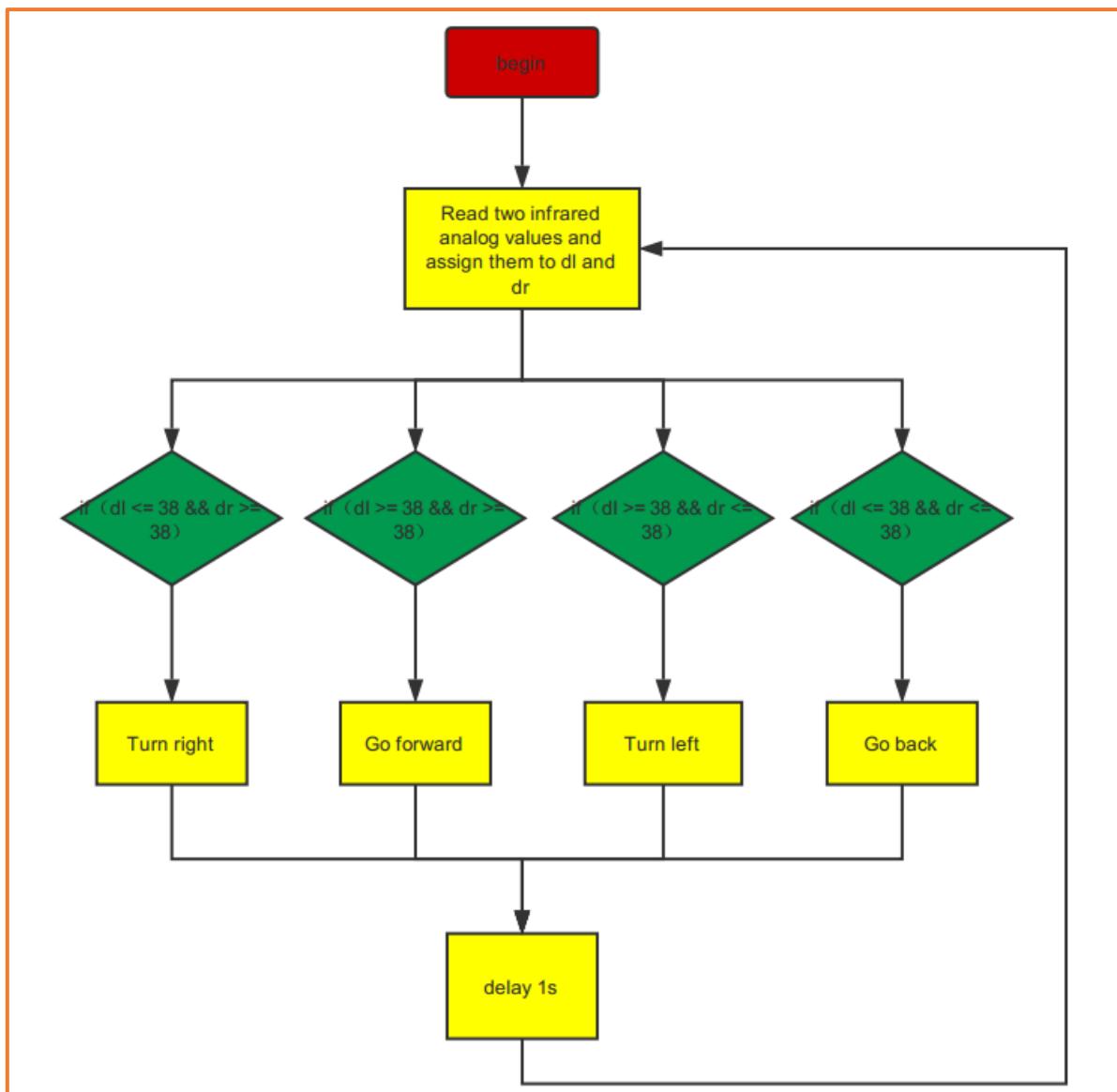


```
left:1020    right:1021
left:1020    right:1020
left:1020    right:1020
left:1021    right:1020
left:1021    right:1020
left:1021    right:1020
left:1020    right:1020
left:1021    right:1020
left:1020    right:1020
left:1021    right:1020
left:1020    right:1021
left:1020    right:1021
left:1020    right:1020
left:1020    right:1021
left:1020    right:1021
left:1020    right:1020
```

Figure .3.2.15 Diagram of Data without Obstacles

### 3.2.2.5 Software Design

#### 3.2.2.5.1 Program flow chart



#### 3.2.2.5.2 Program code

In the above steps, we have tested the car's driving and obstacle avoidance module respectively, they have achieved the desired results, here the "infrared obstacle avoidance" actually has been explained in this section, but we have not put the programs of two parts together, so we now integrate the program of the two parts and complete this great "infrared obstacle avoidance" project. Firstly, let's read the complete program:

```

int E1 = 5; //PWMA
int M1 = 9; //DIRA*****left
int E2 = 6; //PWMB
int M2 = 10; //DIRB*****right
/*Define 4 motor control terminals, connected to IN1-IN4 on the motor drive board.*/
const int leftPin = A3;
const int rightPin = A4; // Define the two signal receiving ends of the sensor
float dl;
float dr;// Define two margins to store the values read by both sensors
void setup() {
    Serial.begin(9600); // Set the serial port baud rate to 9600,
    pinMode(leftPin, INPUT);
    pinMode(rightPin, INPUT);// Set the working mode of two sensor pins, namely "input"
    delay(1000);
}

void loop() {
    dl = analogRead(leftPin);
    dr = analogRead(rightPin); // Read the values collected by both sensors and assign them
    to the defined variables.
    if (dl >= 38 && dr <= 38) {/*If the value collected by the left sensor is greater than
    or equal to 38 and the right value is less than or equal to 38, the following program in {} is
    executed (dl>= 38, there is no obstacle on the left, dr<= 38 shows that there is an obstacle
    on the right, so at this time the car is turning to the side without obstacles (ie, turning
    to the left). From Figure 3.2.11, we know that the simulated value will drop below about 35
    in the event of an obstacle , But in order to reduce the error, we set the threshold at 38
    to prevent the car from judging the error because of the error. We can also customize other
    values. If we use the digital port to receive the value of the sensor, we only return "0"
    and "1" , But the same way to judge. The reason why I did not use digital IO, because we
    use the digital IO port in other places.*/
    digitalWrite (M1, 0);
    digitalWrite(E1, 180); //the speed value of motorA is 180
    digitalWrite (M2, 180); //the speed value of motorB is 180
    digitalWrite(E2, 0); /*Set a PWM value, the maximum PWM is 255, but the speed of the
    car should not be too fast when walking, otherwise it can not hit the obstacle in time when
    the obstacles are suddenly encountered.*/
}

```

```

    Serial.print(dl);
    Serial.print("  ");
    Serial.print(dr);
    Serial.print("  ");
    Serial.println("Turning left"); /*Through the "Serial Monitor" print the current
status of the car and the value collected by the sensor*/
    delay(300);
    analogWrite(M1,0);
    analogWrite(E1,0);
    analogWrite(M2,0);
    analogWrite(E2,0);/*As the car left after about 300ms stop, after measuring, 300ms
time car just can rotate about 90 degrees, because the DC motor does not like the steering
angle can be precisely controlled, so can only give a rough estimate, of course, different
motor speed is not Similarly, the time used is not the same, so everyone in the experiment
can be based on their own ideas, but the angle of 90, but also other values.*/
    delay(1000);/************//Turning left
}

if (dl <= 38 && dr <= 38) {/*If the value collected by the left sensor is less than or
equal to 38 and the right value is less than or equal to 38, the following program in {} is
executed (dl <= 38, indicating that there is an obstacle on the left and dr<= 38 shows that
there is an obstacle on the right, so at this time the car is rotated 180 degrees backwards.
In the experiment, the car can just turn around 180 degrees after 500ms of rotation. Because
the DC motor can not precisely control the angle like the steering gear, An approximate value,
of course, different motor speed is not the same, the time used is not the same, so everyone
in the experiment can be based on the circumstances may be.)*/
    analogWrite(M1, 255); //the speed value of motorA is 255
    analogWrite(E1, 0);
    analogWrite(M2, 0);
    analogWrite(E2, 255); //the speed value of motorB is 255
    Serial.print(dl);
    Serial.print("  ");
    Serial.print(dr);
    Serial.print("  ");
    Serial.println("Turning around");/*Through the "Serial Monitor" print the current
status of the car and the value collected by the sensor.*/
    delay(500);
    analogWrite (M1, 0);
    analogWrite (E1, 0);
    analogWrite (M2, 0);
    analogWrite (E2, 0); /*Rotate 180 degrees and stop*/
    delay(1000);/************//Turning around
}

```

```

if (dl <= 38 && dr >= 38) /*If the left sensor is less than or equal to 38 and the right
value is greater than or equal to 38, the following program in {} is executed (dl <= 38, indicating
that there is an obstacle on the left, dr >= 38 shows that there is no obstacle on the left,
so at this moment the car is turning to the side without obstacle, that is, turning to the
right)*/
{
    analogWrite(M1, 180); //the speed value of motorA is val
    analogWrite(E1, 0);
    analogWrite(M2, 0);
    analogWrite(E2, 180); //the speed value of motorA is val
    Serial.print(dl);
    Serial.print(" ");
    Serial.print(dr);
    Serial.print(" ");
    Serial.println("Turning right");
    delay(300);
    analogWrite(M1, 0);
    analogWrite(E1, 0);
    analogWrite(M2, 0);
    analogWrite(E2, 0); /*Car must stop after each rotation, if you do not stop there will
be the phenomenon of rotating around. */
    delay(1000); //*****Turning right
}

if (dl >= 38 && dr >= 38) {/* Judge two values collected by the sensor. If the value collected
by the left sensor is greater than or equal to 38 and the right value is greater than or equal
to 38, execute the following program in {} (dl >= 38, indicating that there is no obstacle
on the left and dr >= 38 that there is no obstacle on the left, so the car at this time straight
*/
    intval = 150; /*When the straight line has a PWM value of 150, if the value is too
large, the speed of the car will be very fast, which may lead to the car can not hit the obstacle
in time when it encounters the obstacle. */
    analogWrite(M1, 0);
    analogWrite(E1, intval); //the speed value of motorA is val
    analogWrite(M2, 0);
    analogWrite(E2, intval); //the speed value of motorB is val
    Serial.print(dl);
    Serial.print(" ");
    Serial.print(dr);
    Serial.print(" ");
    Serial.println("go"); //***** / forward
}
}

```

---

In the above program, we made comments on some part of the program in order to make you to learn and understand the program easily, the program is relatively simple, you can write your own programs to give the car more skills. Of course, if you want to use it directly, we have the corresponding source program in the CD.

### 3.2.3 Infrared Tracing

#### 3.2.3.1 Introduction of Infrared Tracing Sensor

After infrared obstacle avoidance, let us learn the infrared tracing, their nature of work is the same, using basically the same module, just in different ways, to achieve different functions. **In this section when we study, we have to pay attention to the color of the line we trace (the black line or white line), if your floor is black, you should trace the white line (pasting white line on the floor); if it is white, then you should trace the black line (pasting black line on the floor); you just need to make a distinct difference between the track and the ground environment.**

Black line tracking refers to the car drives along the black line on the white floor, it can know where to drive according to the received reflected light due to the different light reflection coefficient on the black and white floor.

White line tracking refers to the car drives along the white line on the black floor, it can know where to drive according to the received reflected light due to the different light reflection coefficient on the white and black floor.

In the "Hummer-Bot" car, we use the TCRT5000 sensor as tracing module, TCRT5000 infrared reflection sensor is a photoelectric sensor which consists of an infrared emitting diode and an NPN infrared photoelectric transistor. The detectable reflective distance is 1mm-25mm, the sensor is specially equipped with M3 fixed installation holes, so it is easy to adjust the direction, it also has the 74HC14 Schmidt trigger inverter which ensure the clean signal, the good wave shape and the strong driving ability. It can be applied to robot obstacle avoidance, robot tracing (detecting black line in white background and detecting white line in black background), which is the necessary sensor for tracing line robot and other occasions. The PCB size is 3.5cm\*1cm, and the physical map is shown in Fig.3.2.16.

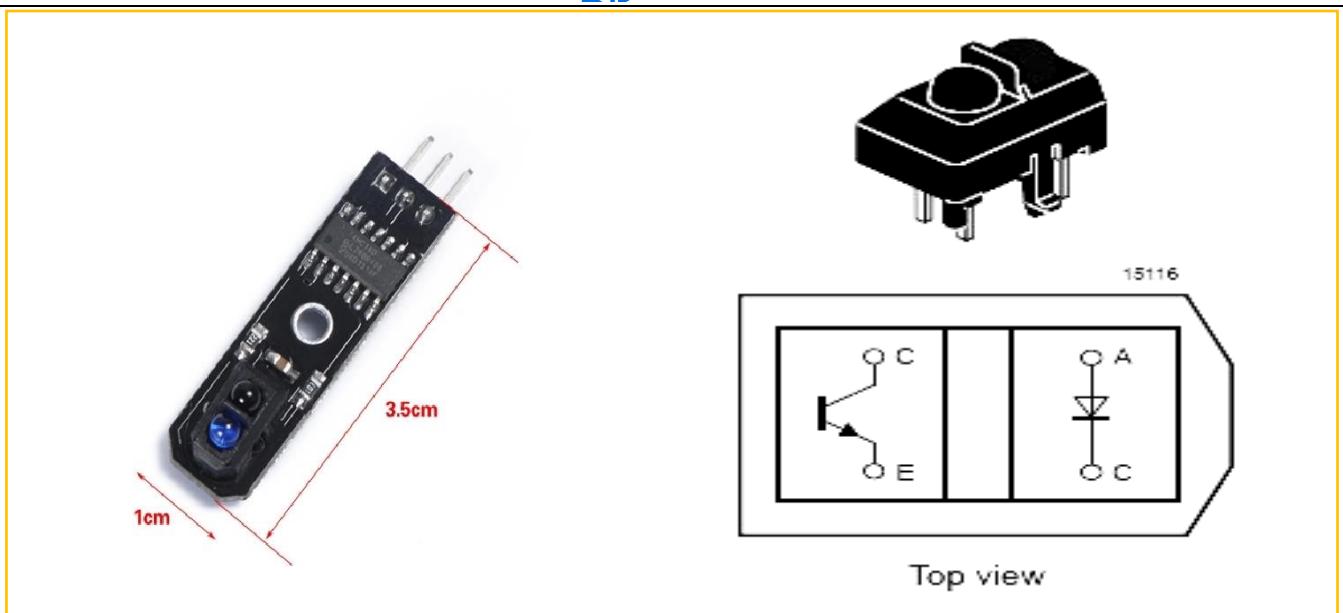


Figure .3.2.16 Physical Map of the Module

### 3.2.3.2 Working Principle

In the above, we talked about two patterns of tracing-the white line and the black line. In fact, either the black line or the white line, we usually adopt the infrared detection method.

Infrared detection method means that different objects with different colors have the different infrared reflection characteristics. The car launches the infrared to the ground continually during driving process, the infrared receiving tube will be in a shutdown state and the output of the module is low level when the emitted infrared is not reflected or the reflected infrared is not strong enough, and indicating diode will be off; when the diffuse reflection occurred on a white floor, the intense reflected infrared will be received by the receiving tube on the car, the photosensitive triode will be saturated, the output end of the module is high level and the indicating diode will light.

As is shown in the schematic diagram 3.2.17 (U1 is comparator, such as LM358, LM324, LM393, LM339 and a series of comparators, we use the 74HC14D comparator in TCRT5000), A and C are connected to the light emitting diode, C and E to the receiving diode, as shown in Fig.3.2.16. In the "Hummer-Bot" car, we use three modules, two in the left and right sides, one in the middle. Its installation is shown in Fig.3.2.18, the tracing sensors are in a straight line.

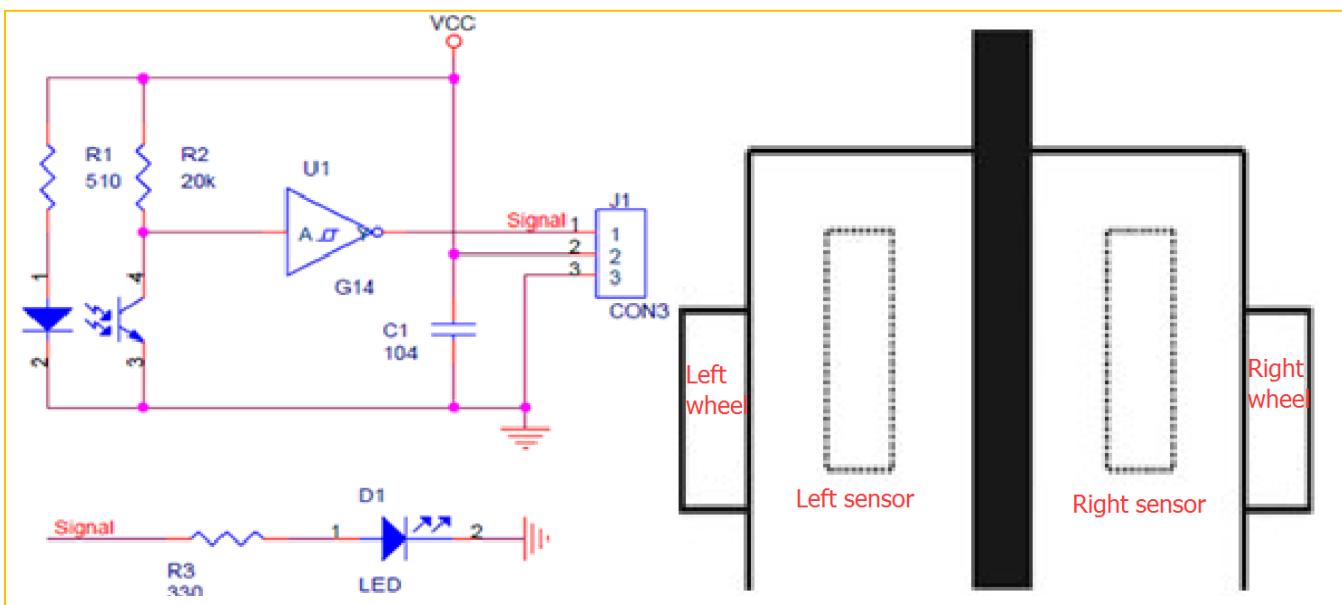


Figure .3.2.17 Schematic Diagram of Tracing Module Figure. 3.2.18 Diagram of Tracing Module Installation

The X1 and Y1 are the first direction control sensors, and the width of the two sensors on the same side of the black line must not be greater than the width of the black line. When the car is moving forward, the driving track is always between the two first level sensors X1 and Y1 (the black track as shown in Fig. 3.2.18), when the car deviates from the black line:

If the left X1 detects the black line which can't be detected by the right Y1 and intermediate sensors, the the car has shifted to the right, then the car will turn left slightly, and keeping intermediate sensor always detecting the black line; if the right Y1 detects the black line which can't be detected by the left X1 and intermediate sensors, the the car has shifted to the left, then the car will turn right slightly, and keeping intermediate sensor always detecting the black line; if the car turns back on the track driving along the black line, X1 and Y1 can all detect the white line, and send high level to the microcontroller.

### 3.2.3.3 Module Parameters

- ◆ Using TCRT5000 infrared reflection sensor
- ◆ The detection distance: 1mm~25mm, the focal distance is 2.5mm
- ◆ The comparator output signal waveform is clean, good-shape and it has more than 15mA strong drive ability.
- ◆ The working voltage: 3.3V-5V
- ◆ Using wide voltage comparator 74HC14D, digital output (0 and 1)
- ◆ Easy-to-install fixed bolt holes

**Detailed parameters please refer to “hummer-bot\Document\ TCRT5000.pdf”**

#### Note:

Correct wiring! The mainboard and electronic device may burn up if you have reverse connection between positive and negative poles. Connecting the VCC to 3.3V or 5V, the OUT output port to the

microcontroller IO port directly. The I/O port on Arduino should be set for input mode / receiving mode, otherwise it can't be used. As for other MCU, such as ARM or more advanced control boards, if the I/O ports need to be used as the input and output mode, they have to be set to the input mode / receiving mode. The 51 series microcontrollers can be used directly, there is no need to set the input and output mode.

### 3.2.3.4 Wire connection

As shown in the below figure, the upper column is the "GND" interface, the middle column is the "VCC" interface, and the lower column is the "OUT" interface, where "A0" corresponds to the "OUT" of the left trace, and "A1" corresponds to the "OUT" of the intermediate trace. "A2" corresponds to the "OUT" of the right trace.

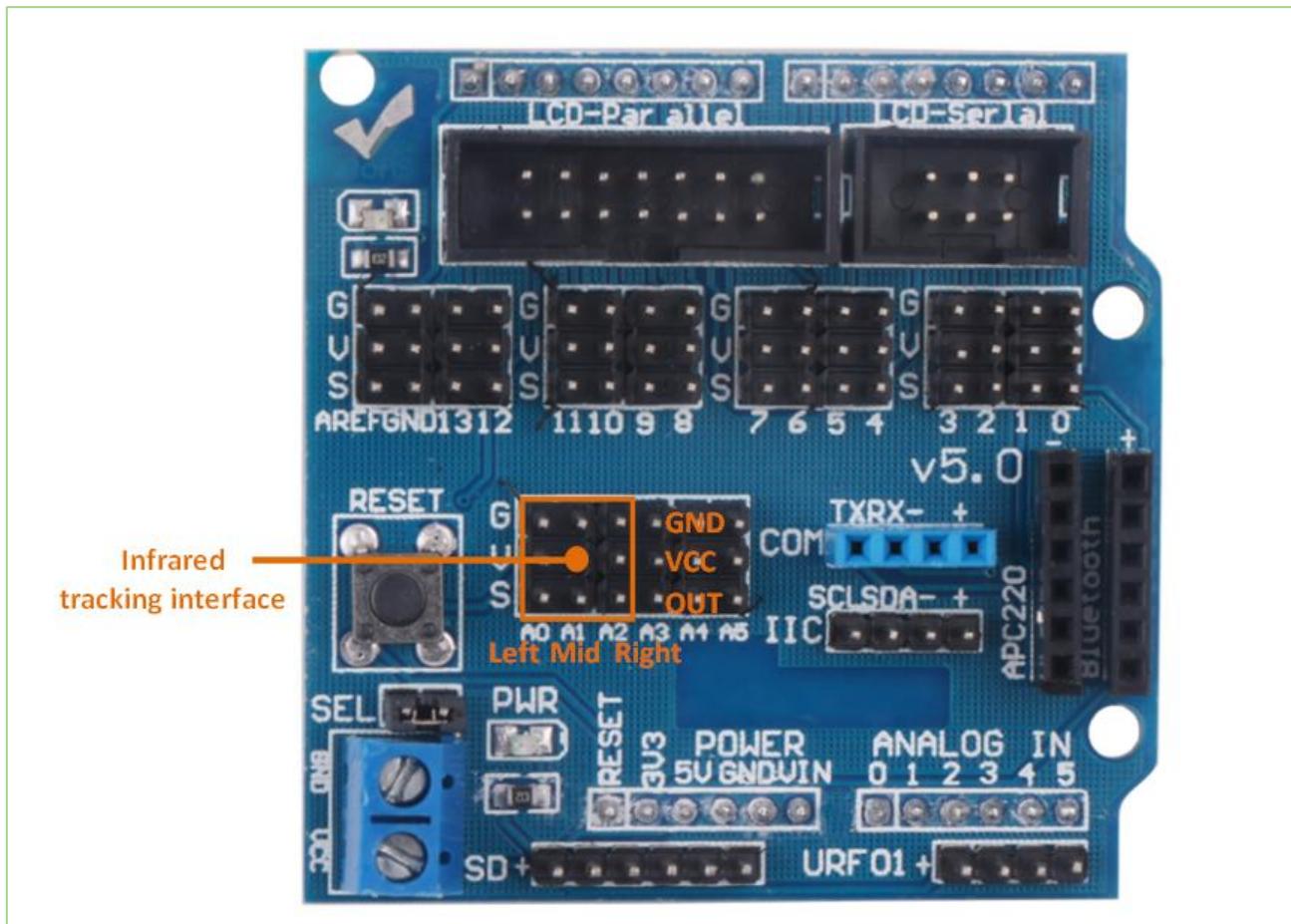


Figure .3.2.19 Wire connection diagram

### 3.2.3.5 Experimental Procedures

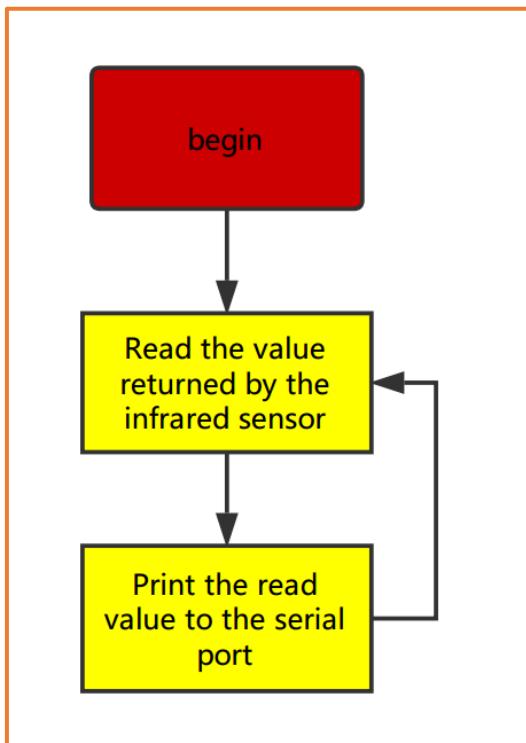
1, Fixing the sensor on the car (the assembly is completed) and connecting it to the Arduino as shown in Fig.3.2.19.

2, Making the track.If your floor is white, then you could stick a black tape to form a loop, otherwise stick a white tape, the shape of track is based on your own desires, the best width of the tape is 13-18mm. In this manual, we use the black track, as shown in Fig.3.2.20.

3, Module test. Copying the following codes to the IDE compiler environment (you can also open the program in the CD directly) and downloading to the development board, opening the serial port monitor

(baud rate is 9600) to observe the changes of data when there is the white line (Fig. 3.2.21) and is not the white line (Figure 3.2.22).

Program flow chart is as follows:



Note: Here we connect the signal output port of infrared obstacle avoidance to the analog port on Arduino (A0-A5), so the serial port monitor prints analog values, you can connect it to the digital port (2-13), then the serial port monitor will print out only "0" and "1".

```

void setup() {
    Serial.begin(9600);
}

void loop() {
    int left, centre, right;
    left = analogRead(A0);
    centre = analogRead(A1);
    right = analogRead(A2);
    Serial.print("right:");
    Serial.print(right);
    Serial.print(" ");
    Serial.print("centre:");
    Serial.print(centre);
    Serial.print(" ");
    Serial.print("left:");
    Serial.print(left);
    Serial.println(" ");
}

```

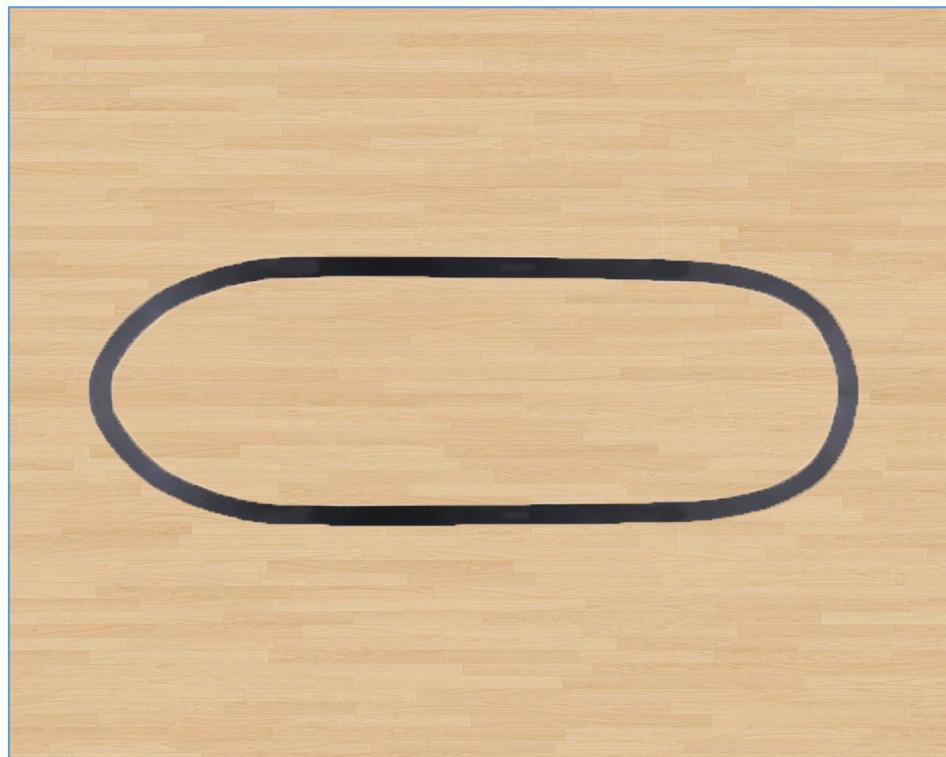
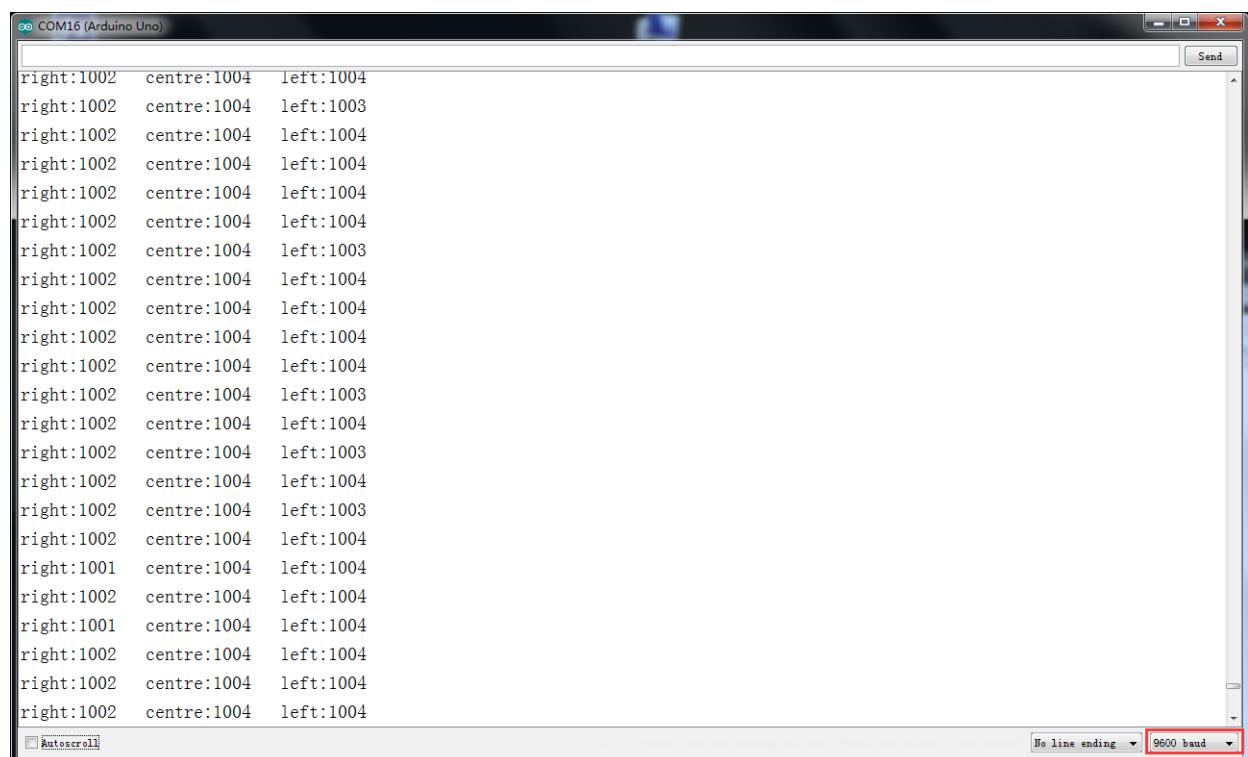
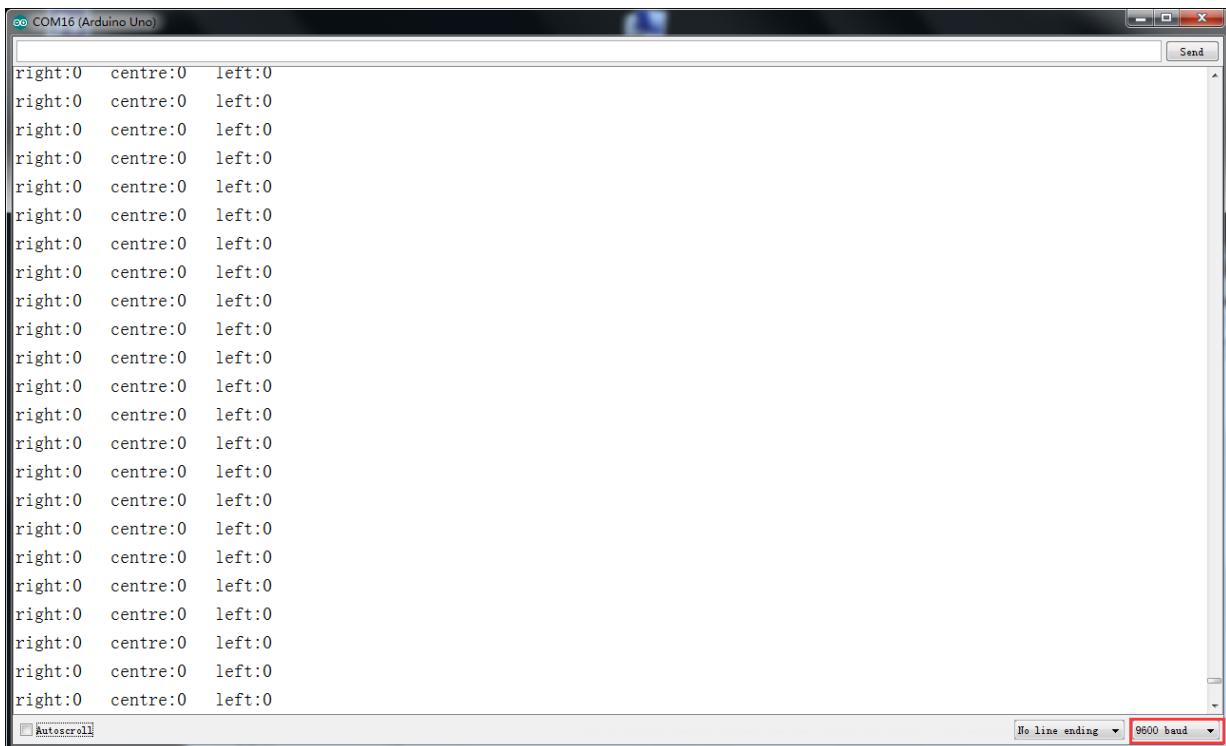


Figure .3.2.20 Example of the Black Track



```
right:1002    centre:1004    left:1004
right:1002    centre:1004    left:1003
right:1002    centre:1004    left:1004
right:1002    centre:1004    left:1003
right:1002    centre:1004    left:1004
right:1001    centre:1004    left:1004
right:1002    centre:1004    left:1004
right:1001    centre:1004    left:1004
right:1002    centre:1004    left:1004
right:1002    centre:1004    left:1004
right:1002    centre:1004    left:1004
```

Fig. 3.2.21 The Data When the Sensor Does Not Detect the Black Line



```
right:0 centre:0 left:0
```

No line ending ▾ 9600 baud ▾

Figure 3.2.22 The Data When the Sensor Detects the Black Line

From Fig.3.2.21 and Fig.3.2.22 we can see that the output is high level when the sensor does not detect the black line, low level when detects the black line. We use the analog port to collect the sensor's signal, so the printed value is analog that, the high level is reaching 1024, the low level is 0. After we master the working principle of the sensor, our tracing car in this section comes to an end, then let us open a car journey.

### 3.2.3.5 Software Design

#### 3.2.3.5.1 Program flow chart

When the car enters the tracing mode, it keeps scanning the I/O port of the MCU connected to the sensors, once detecting the changes in signal at the I/O port, the corresponding procedure will be implemented, the corresponding signal will be sent to the motor so as to correct the status of the car.

When the car enters the tracing mode, it keeps scanning the I/O port of the MCU connected to the sensors, once detecting the changes in signal at the I/O port, the corresponding procedure will be implemented. If the left sensor detects the black line (the left half of the car walked across the black line, the car body is trended right), the car should turn the left; If the right sensor detects the black line (the right half of the car walked across the black line, the car body is trended left), the car should turn the right. After the direction adjustment, the car walks forward, and continues to detect the black line repeatedly. The tracing flow chart is shown in Fig.3.2.23.

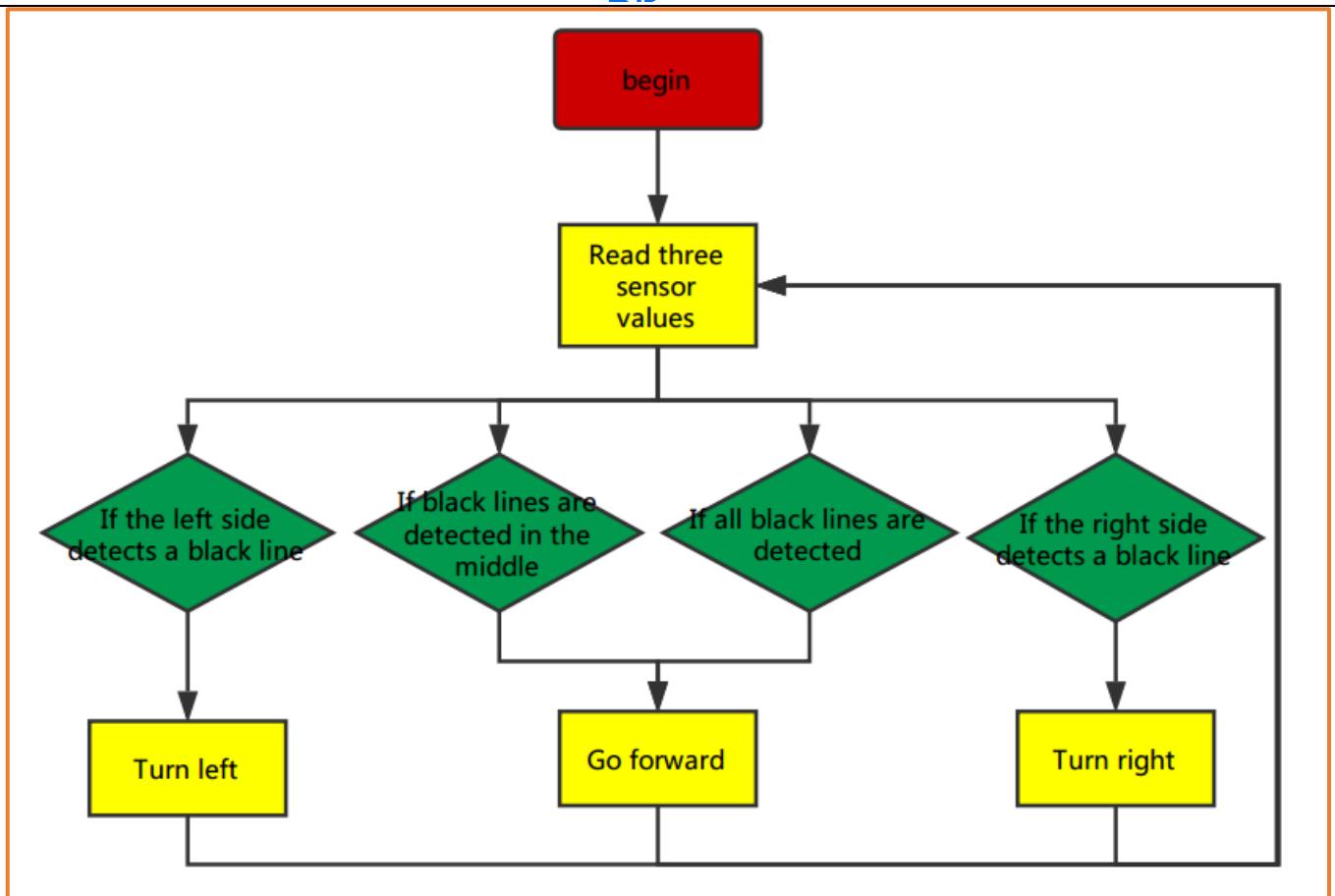


Figure .3.2.23 the Tracing Flow Chart

### 3.2.3.5.2 Program Code

```

int E1 = 5; //PWMA
int M1 = 9; //DIRA*****left
int E2 = 6; //PWMB
int M2 = 10; //DIRB*****right
/*Define 4 motor control terminals, connected to IN1-IN4 on the motor drive board.*/
void setup() {
    Serial.begin(9600); /*Set the baud rate to 9600 */
}
void loop()
{
    int left1, centre, right1; /*Define 3 sensors */
    left1 = analogRead(A0);
    centre = analogRead(A1);
    right1 = analogRead(A2); /*Read the value collected by 3 sensors */
    if ((right1 >= 975) && (centre <= 8) && (left1 >= 975)) {/* Judge the collected value, if right1 >
the sensor captures a value that is low and reads 0 after analog IO. However, to reduce the error,
we set the threshold In 8, to prevent the error caused by the car to determine the wrong, we can
    }
}
    
```

```

customize the other values, if the use of digital port to receive the value of the sensor returns
only "0" and "1", but to determine the same way. The reason why I did not use digital IO, because
we use the digital IO port in other places. */

    intval = 150; /*Set a PWM value, the maximum value of PWM is 255, but the speed should not
be too fast when tracing the car, otherwise the car will shake more in the tracing process.*/
    analogWrite (M1, 0);
    analogWrite(E1, val); //the speed value of motorA is val
    analogWrite (M2, 0);
    analogWrite(E2, val); //the speed value of motorB is val
}

else if((right1 <= 8) && (centre >= 975) && (left1 >= 975)) {/* The value collected to judge,
if the center > = 975 and left1 > = 975 are greater than 975, indicating that the middle and left
sensors did not detect the black line, right1 <= 8 shows the right sensor detects a black line, then
the car Has left to the left, or the black line has been turning to the right, so the car should
turn to the right. */
    intval = 150;
    analogWrite (E1, 0);
    analogWrite(M1, val); //the speed value of motorA is val
    analogWrite (M2, 0);
    analogWrite(E2, val); //the speed value of motorB is val
}

else if((right1 >= 975) && (centre >= 975) && (left1 <= 8)) {/* Judge the collected value, if
center > = 975 and right1 > = 975 are greater than 975, indicating that the middle and right sensors
did not detect the black line, left1 <= 8 shows that the left sensor detects the black line, then
the car Has been to the right deviation, or the black line has turned to the left, so the car should
turn left at this time. */
    intval = 130;
    analogWrite (M1, 0);
    analogWrite(E1, val); //the speed value of motorA is val
    analogWrite (E2, 0);
    analogWrite(M2, val); //the speed value of motorB is val
}

if ((right1 <= 8) && (centre <= 8) && (left1 <= 8)) {/* The value collected to judge, if the
center <= 8, left1 <= 8 and right1 <= 8 are greater than 8, indicating 3 sensors have detected a
black line, then the car has reached the "ten" intersection, because We have only 3 sensors, no way
to make more sophisticated judgments, so only let the car choose to go straight. */
    intval = 130;
    analogWrite (M1, 0);
    analogWrite(E1, val); //the speed value of motorA is val
    analogWrite (M2, 0);
    analogWrite(E2, val); //the speed value of motorB is val
}
}

```

### 3.2.4 Ultrasonic Obstacle Avoidance

In this product, we will integrate the ultrasonic module and steering engine together and make the two parts working at the same time, which greatly increases the effectiveness of the data and the flexibility of the car, the main working flow: When the power is on, steering engine will automatically rotates to 90 degrees, the MCU will read data from the reflected ultrasonic. If the data is greater than the security value, the car will continue to drive forward, otherwise the car will stop, then the steering engine will rotate 90 degrees to the right. After that, the MCU reads data from the reflected ultrasonic again, the steering engine rotates 180 degrees to the left, then reading data again, the steering engine rotate 90 degrees, the MCU will contrast the two detected data, if the left data is greater than the right data, the car will turn left, otherwise turn right, if the two data are both less than the safety value, the car will turn around.

#### 3.2.4.1 Suite Introduction

##### 1. The steering gear

The steering gear is also called servo motor which is originally used in ships, since it can control the angle continuously through the program, so it has been widely used in intelligent steering robot to achieve all kinds of joint movement, the characteristics steering gear are small volume, large torque, high stability, simple external mechanical design. Either in hardware or software design, the design of steering engine is an important part of car controlling, the steering gear is mainly composed of the following parts in general, steering wheels, gear group, position feedback potentiometer, DC motor and control circuit (shown in Fig.3.2.24). Fig.3.2.25 shows the most commonly used 9G steering gear now.

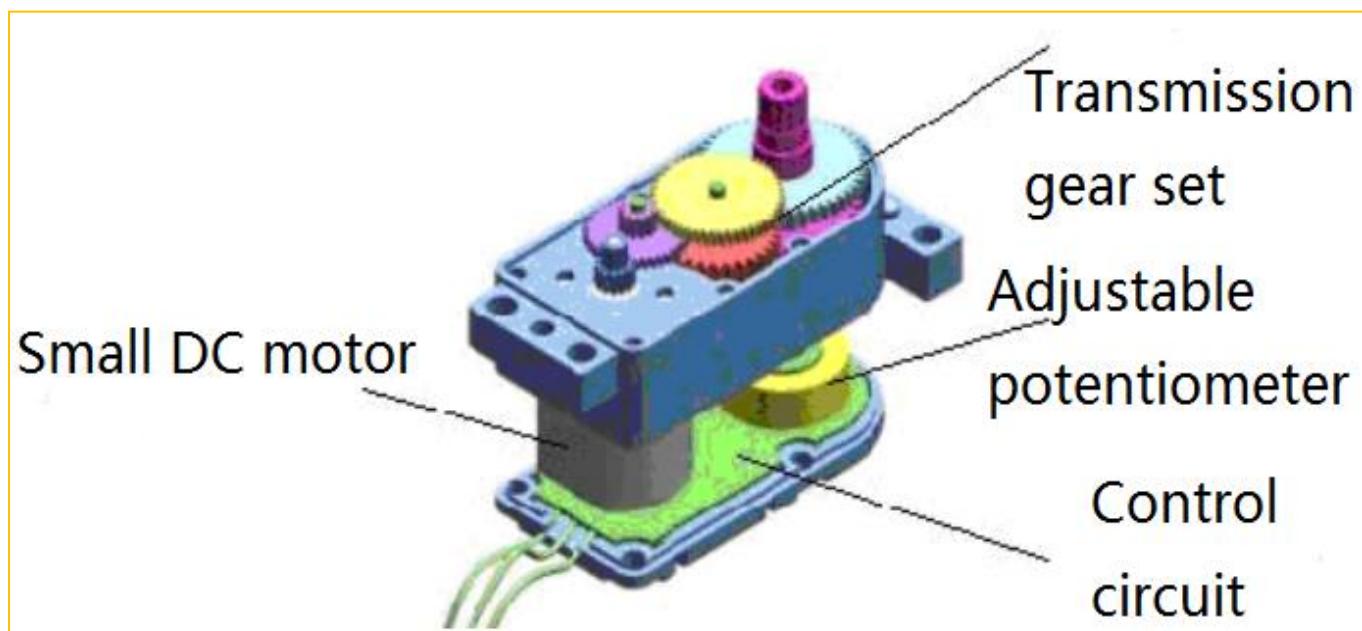


Figure .3.2.24 Diagram of Steering Gear

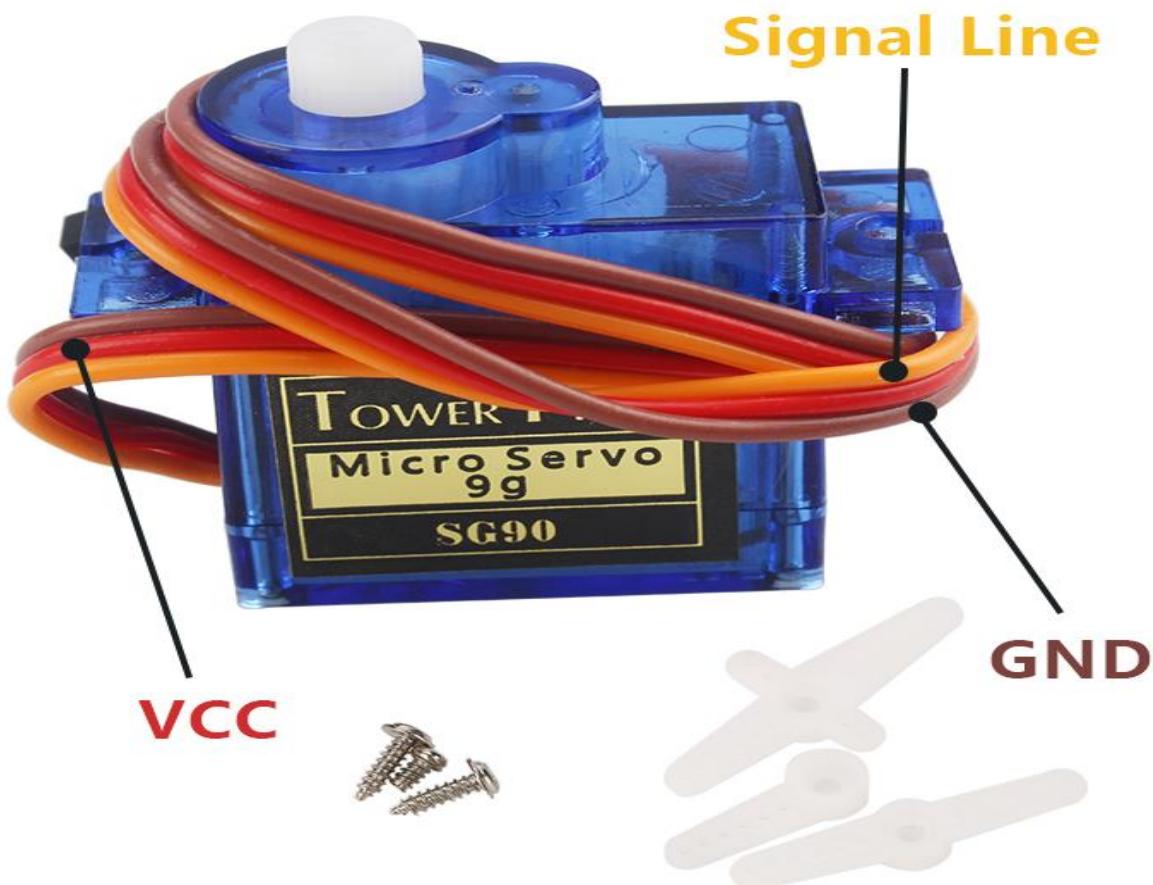


Figure .3.2.25 Physical Map of Steering Gear

## 2. The ultrasonic

An ultrasonic sensor is a device that transforms other forms of energies into ultrasonic energy with desired frequency or transforms the ultrasonic energy into other forms of energy with the same frequency. The ultrasonic sensors are commonly classified into two categories, the acoustic type and the hydrodynamic type. Acoustic type mainly has: 1, piezoelectric sensor; 2, magneto strictive sensor sensor; 3, electrostatic sensor. The hydrodynamic type includes the gas whistle and the liquid whistle. At present most of the ultrasonic sensors are working using piezoelectric sensors. Distance measurement with the ultrasonic is also a hot spot.

In the "Hummer-Bot" car, we use HC-SR04 ultrasonic module which has the 2cm-400cm non-contact distance sensing function, the measurement accuracy can achieve to 3mm; the temperature sensor can correct the measured results using the GPIO communication mode, the module has a stable and reliable watchdog. The module includes an ultrasonic transmitter, receiver and control circuit, which can measure distance and steer like in some projects. The smart car can detect obstacles in front of itself, so that the smart car can change direction in time, avoid obstacles. A common ultrasonic sensor is shown in Fig.3.2.26.



Figure 3.2.26 Physical Map of Ultrasonic Module

### 3.2.4.2 Suite Parameters

#### 1. Steering gear

The steering gear has three input wires as shown in Fig.3.2.25, the red is power wire, while the brown is the ground, which guarantee the basic energy supply for the steering gear. The power supply has two kinds of specifications (one is 4.8V, the other is 6.0V) which are corresponding to different torque standards, the 6.0V torque is higher than the 4.8V torque; and the another one is the signal control wire, which is generally white in Futaba, orange in JR. Noticing that some of the SANWA's power wires are on the edge rather than the middle which need to be identified, so you need to remember that the red is power wire, the brown is ground wire.

#### 2. Ultrasonic wave

- 1, Working voltage: 4.5V~5.5V. In particular, voltage above 5.5V is not allowed definitely
- 2, Power consumption current: the minimum is 1mA, the maximum is 20mA
- 3, Resonant frequency: 40KHz;
- 4, Detection range: 4 mm to 4 meters. Error: 4%. In particular, the nearest distance is 4mm, the longest distance is 4 meters, and the data outputs continuously without setting anything.
- 5, Temperature measurement range: 0°C to +100°C; precision: 1°C
- 6, Illumination measurement range: bright and dark;
- 7, Data output mode: iic and uart (57600bps), users can choose any of them; UART mode uses 7 bytes as a group, and the 3 data started with 0x55 are the distance values; the 2 data started with 0x66 are the temperature value; the 2 data started with 0x77 are the illumination values. 0x55\0x66\0x77 are the data headers in order to distinguish the 3 data;

8, Supporting the following 2 detection methods: 1, continuous detection; 2, controlled intermittent detection;

9, Distance data format: using mm as the smallest data unit, double byte 16 hexadecimal transmission;

10, Temperature data format: using Celsius degree as the smallest unit, single byte hexadecimal transmission;

11, Light data format: single byte 16 hexadecimal transmission; the value is big when it is dark, small when it is bright;

12, Working temperature: 0°C~+100°C

13, storage temperature: -40 to +120 degrees Celsius

14, Size: 48mm\*39mm\*22mm (H)

15, The size of fixing holes: 3\*Φ3mm; Gap:10mm

### 3.2.4.3 Working Principle

#### 1. Steering gear

The control signal enters the signal modulation chip by the receiver channel, gets the DC bias voltage. The steering gear has a reference circuit which generates a reference signal with a period of 20ms and a width of 1.5ms. Comparing the obtained DC bias voltage with the voltage of the potentiometer and obtaining the output voltage difference. Finally, the positive and negative output voltage difference in the motor driver chip decide the positive and negative rotation of motor. When the speed of motor is certain, the cascade reducer gear will drive potentiometer to rotate so that the voltage difference is reducing to 0, the motor will stop rotating.

When the control circuit receives the control signal, the motor will rotate and drive a series of gear sets, the signal will move to the output steering wheel when the motor decelerates. The the output shaft of steering gear is connected with the position feedback potentiometer, the potentiometer will output a voltage signal to the control circuit board to feedback when the steering gear rotates, then the control circuit board decides the rotation direction and speed of the motor according to the position, so as to achieve the goal. The working process is as follows: control signal→control circuit board→motor rotation→gear sets deceleration →steering wheel rotation→position feedback potentiometer→control circuit board feedback.

The control signal is 20MS pulse width modulation (PWM), in which the pulse width varies linearly from 0.5-2.5MS, the corresponding steering wheel position varies from 0-180 degrees, which means the output shaft will maintain certain corresponding degrees if providing the steering gear with certain pulse width. No matter how the external torque changes, it only changes position until a signal with different is provided as shown in Fig.3.2.27. The steering gear has an internal reference circuit which can produce reference signal with 20MS period and 1.5MS width, there is a comparator which can detect the magnitude and direction of the external signal and the reference signal, thereby produce the motor rotation signal.

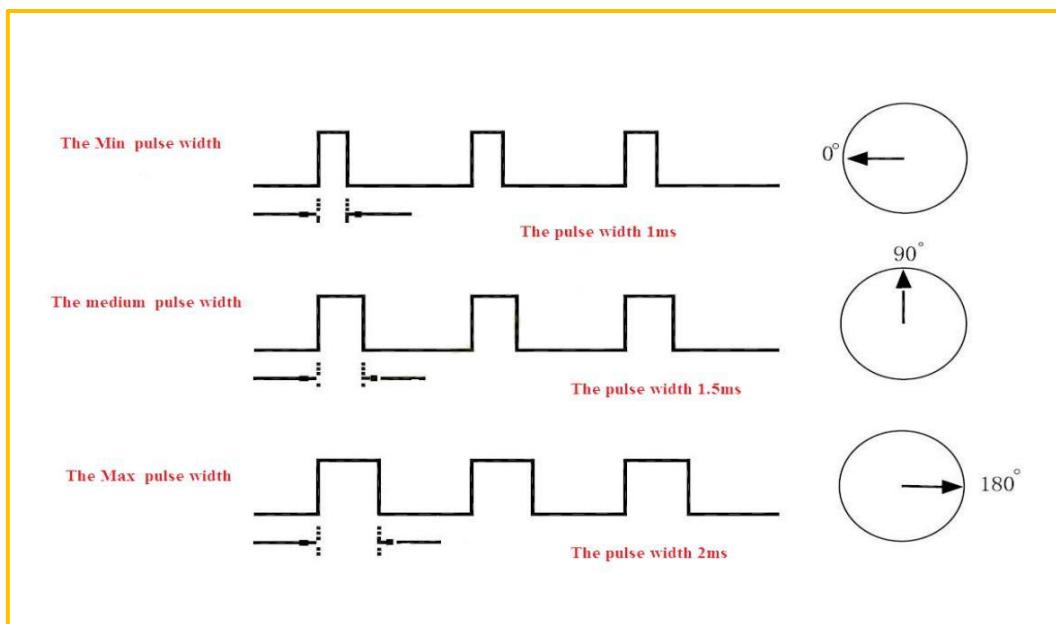


Figure .3.2.27 Relationship between the Motor Output Angle and Input Pulse

## 2. The ultrasonic

The most commonly used method of ultrasonic distance measurement is echo detection method, the ultrasonic transmitter launches ultrasonic toward a direction and starting the time counter at the same time, the ultrasonic will reflect back immediately when encountering a blocking obstacle and stopping the counter immediately as soon as the reflected ultrasonic is received by the receiver. The working sequence diagram is shown in Fig.3.2.28. The velocity of the ultrasonic in the air is 340m/s, we can calculate the distance between the transmitting position and the blocking obstacle according to the time t recorded by the time counters, that is:  $s=340*t/2$ .

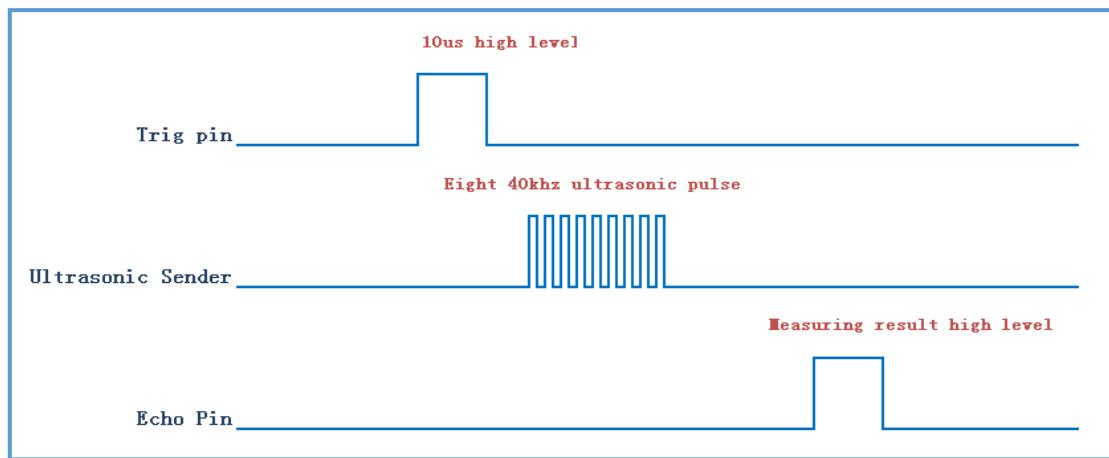


Figure .3.2.28 the Ultrasonic Working Sequence

Let us analyze the working sequence, first the trigger signal starts the HC-RS04 distance measurement module, which means the MCU sends an at least 10us high level to trigger the HC-RS04, the signal sent inside of the module is responded automatically by the module, so we do not have to manage it, the output signal is what we need to pay attention to. The output high level of the signal is the transmitting and

receiving time interval of the ultrasonic, which can be recorded with the time counter, and don't forget to divided it with 2.

The ultrasonic is a sound wave which will be influenced by temperature. If the temperature changes little, it can be approximately considered that the ultrasonic velocity is almost unchanged in the transmission process. If the required accuracy of measurement is very high, the measurement results should be corrected with the temperature compensation. Once the velocity is determined, the distance can be obtained. This is the basic principle of ultrasonic distance measurement module which is shown in Fig.3.2.29:

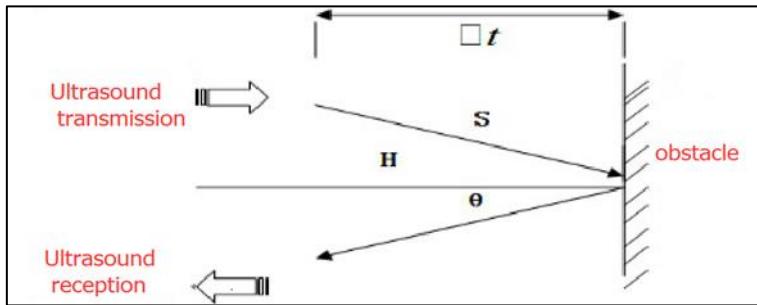


Figure .3.2.29 the Principle of Ultrasonic Distance Measurement Module

The ultrasonic is mainly divided into two parts, one is the transmitting circuit and the other is the receiving circuit, as shown in Fig.3.2.30. The transmitting circuit is mainly composed of by the inverter 74LS04 and ultrasonic transducer T40, the first 40kHz square wave from the Arduino port is transmitted through the reverser to the one electrode on the ultrasonic transducer, the second wave is transmitted to another electrode on ultrasonic transducer, this will enhance the ultrasonic emission intensity. The output end adopts two parallel inverters in order to improve the driving ability. the resistance R1 and R2 on the one hand can improve the drive ability of the 74LS04 outputting high level, on the other hand, it can increase the damping effect of the ultrasonic transducer and shorten the free oscillation time.

The receiving circuit is composed of the ultrasonic sensor, two-stage amplifier circuit and a PLL circuit. The reflected signal received by the ultrasonic sensor is very weak, which can be and amplified by the two-stage amplifier. PLL circuit will send the interrupt request to the microcontroller when receiving the signal with required frequency. The center frequency of internal VCO in the PLL LM567 is

$f_0 = 1/(1.1R_p C_2)$ , the locking bandwidth is associated with C3. Because the transmitted ultrasonic frequency is 40kHz, the center frequency of the PLL is 40kHz, which only respond to the frequency of the signal, so that the interference of other frequency signals can be avoided.

The ultrasonic sensor will send the received the signal to the two-stage amplifier, the amplified signal will be sent into the PLL for demodulation, if the frequency is 40kHz, then the 8 pins will send low level interrupt request signal to the microcontroller P3.3, the Arduino will stop the time counter when detecting low level.

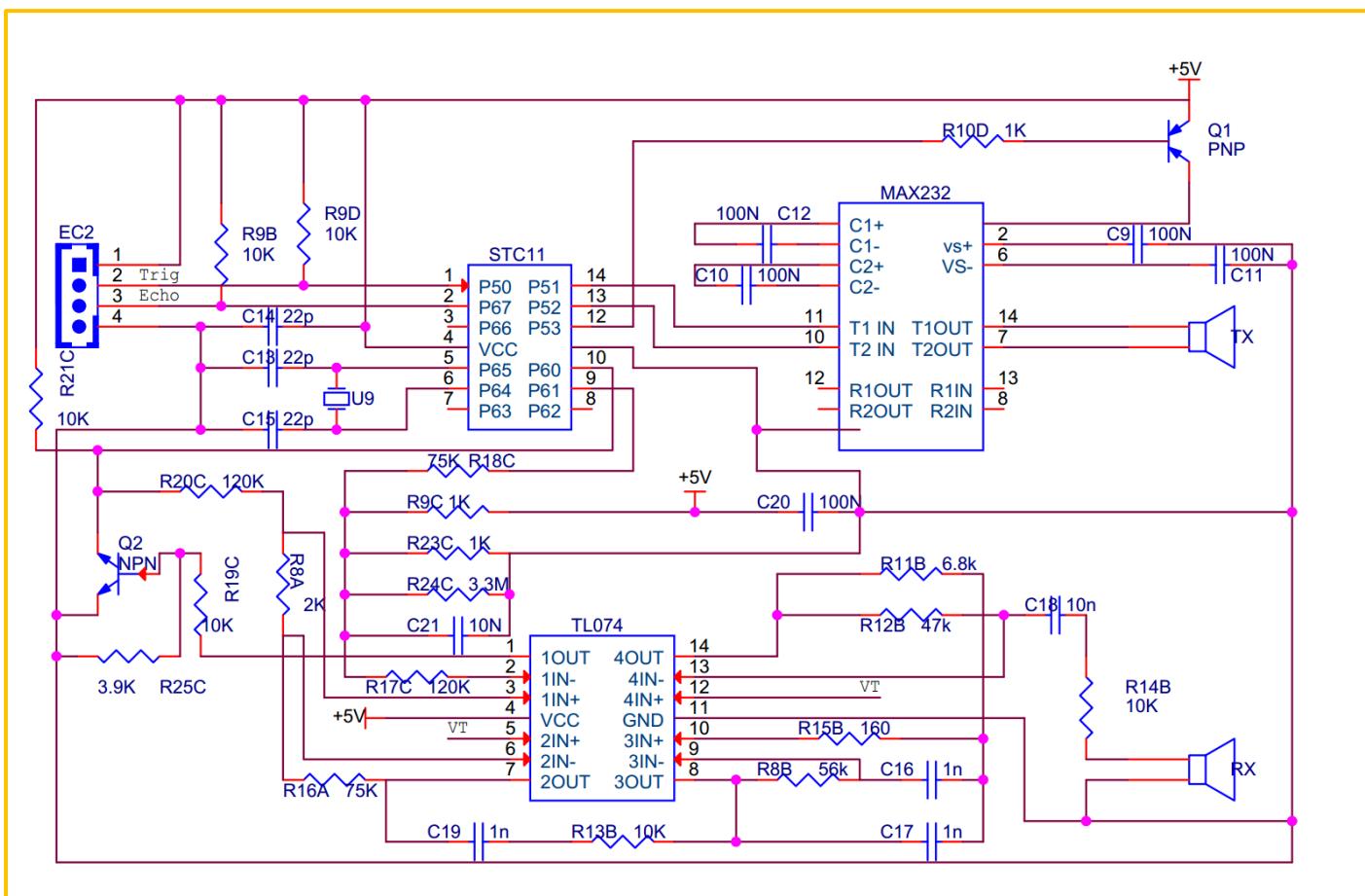


Figure .3.2.30 Schematic Diagram of Ultrasonic Transmitting and Receiving

#### 3.2.4.4 Experimental Procedures

1. Installing the steering gear, ultrasonic module to the car which has been completed in fourth step to the seventh step in 3.1.2) as shown in Fig.3.2.31.
2. Connecting the steering gear and ultrasonic module to the Arduino motherboard as shown in Fig.3.2.32. (you can choose other IO ports according to your own ideas).

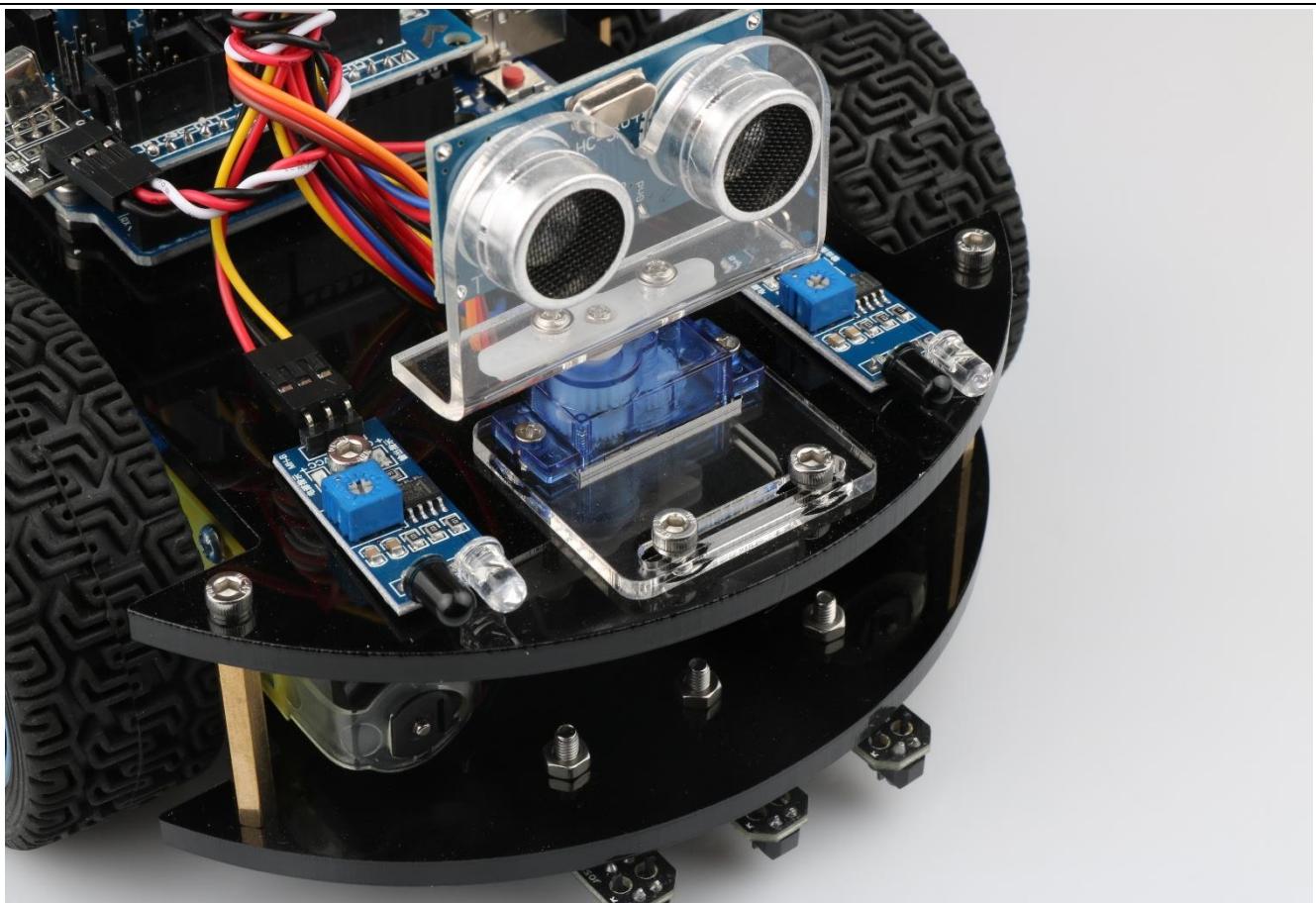


Figure .3.2.31 Installation Diagram of the Steering Gear and Ultrasonic Module

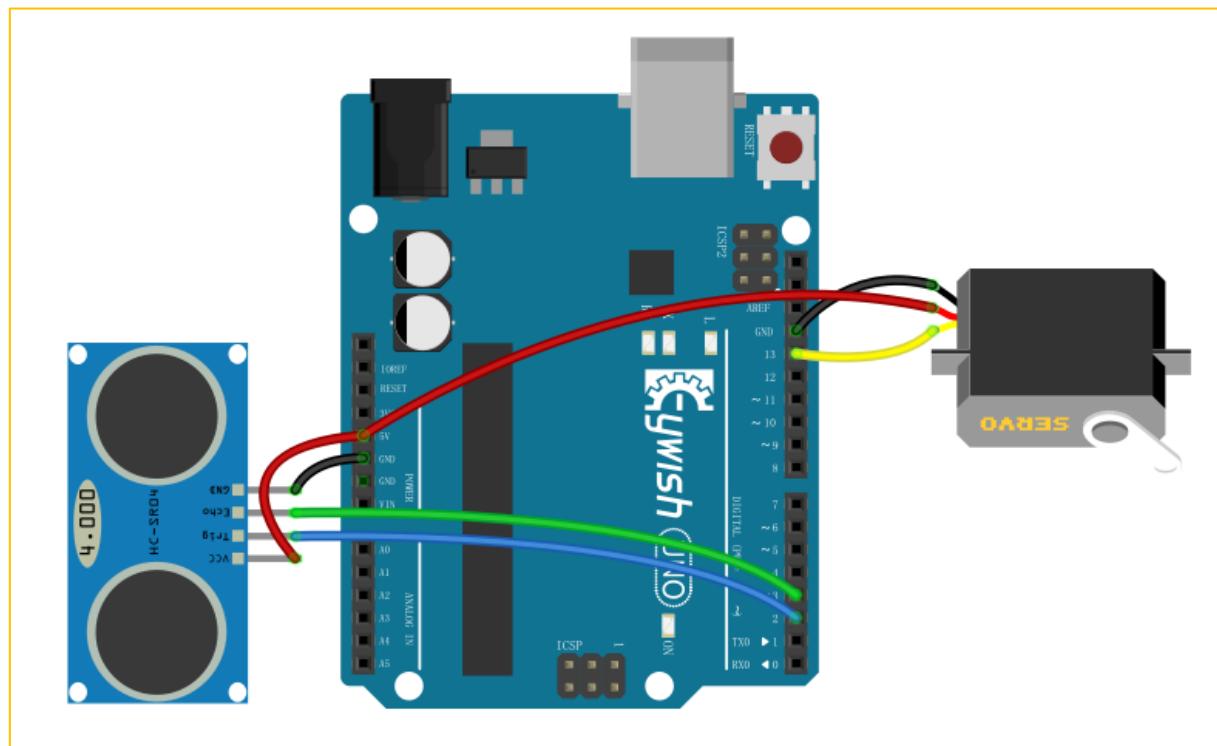


Figure .3.2.32 Wiring of the Steering Gear and Ultrasonic Module

### 3.2.4.5 Wire connection

As shown in the below figure, the servo's "S" is connected to pin 13, the ultrasonic "Trig" is connected to pin 2, the "Echo" is connected to pin 3, the "VCC" pin is connected to VCC, and the "GND" pin is connected to GND.

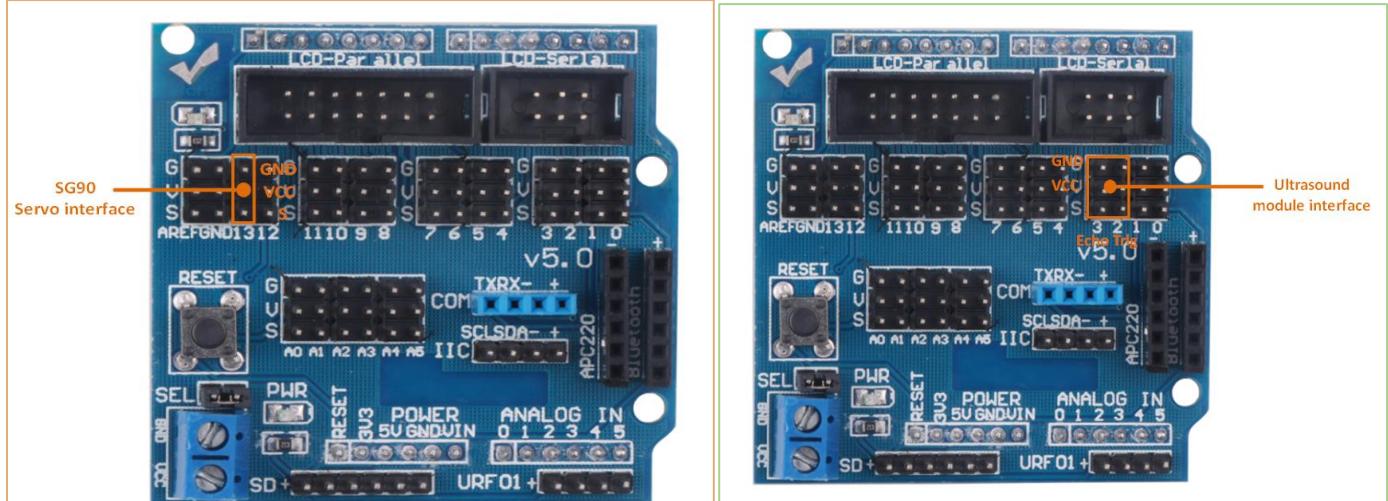
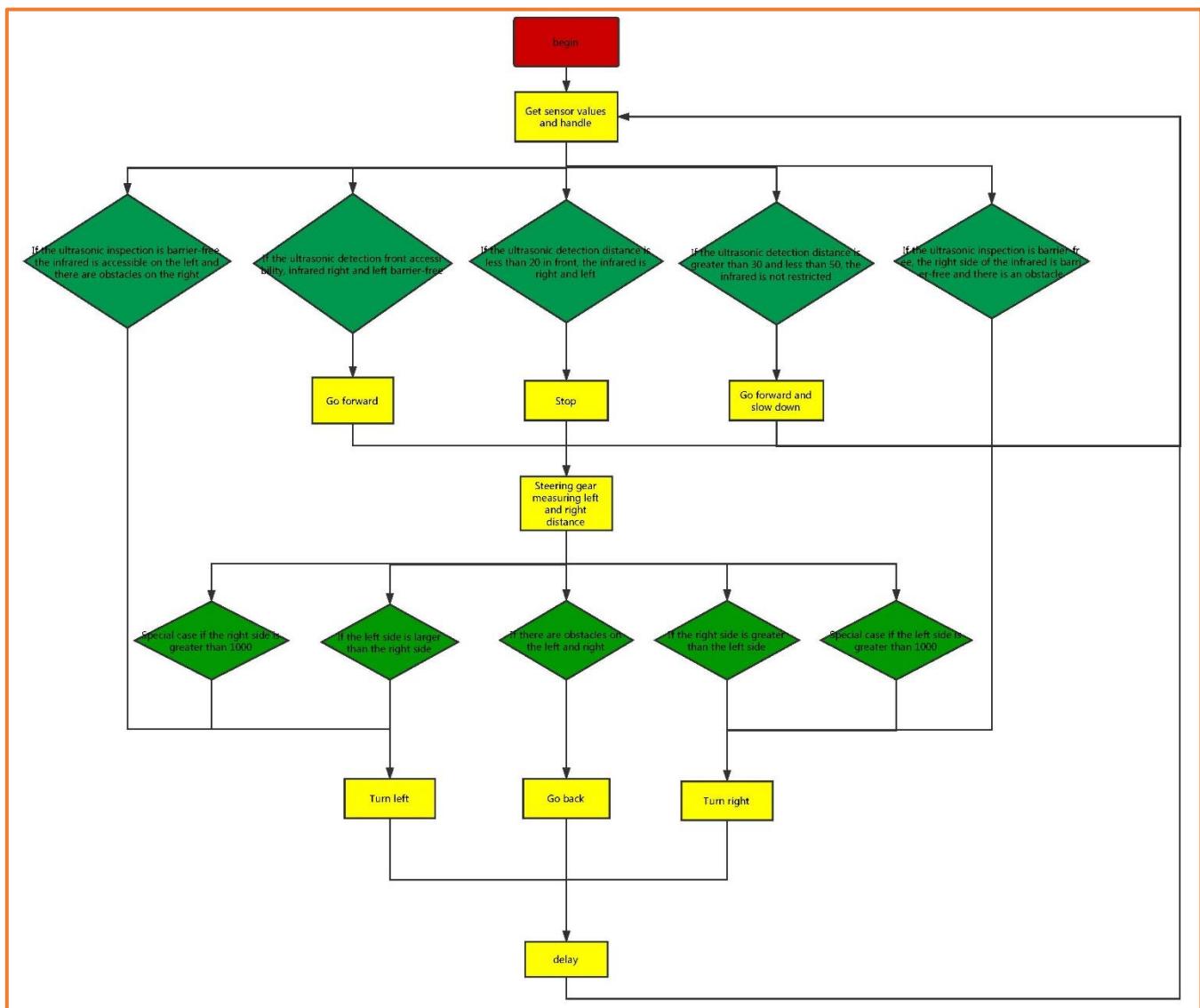


Figure 3.2.33 Wiring diagram of steering gear, ultrasonic wave and expansion board

### 3.2.4.6 Software design

### 3.2.4.6.1 Program flow chart



Code path “hummer-bot\Lesson\ModuleDemo\UltrasonicAvoidance\UltrasonicAvoidance.ino”

### 3.2.4.6.2 Program Code

```
#include <Servo.h> /* In this section, we use the steering gear, so we need to call the steering gear library file. As for what is in the library file, we will not study it. Interested friends can drive for research. We have put this library files on the CD-ROM, we need to copy this folder to the Arduino IDE installation path "libraries" folder, otherwise the program can not compile. */

Servo head;

int E1 = 5; //PWMA
int M1 = 9; //DIRA*****left
int E2 = 6; //PWMB
int M2 = 10; //DIRB*****right

/*Define 4 motor control terminals, connected to IN1-IN4 on the motor drive board.*/
const int TrigPin = 2;
const int EchoPin = 3; /* Define the sensor's 2 control pins to connect to pins 2 and 3 on the Arduino.*/
const int leftPin = A3;
const int rightPin = A4;
float da;
float dl;

float dr; /* Define three variables, used to store the servo at 0,90,180 degrees, the value collected by the ultrasonic module, da is the value collected by the ultrasonic 90 degrees servo, dl is the steering servo 180 degrees ultrasonic acquisition To the value, at this point the steering gear has turned to the left of the car. da for the servo 0 degrees ultrasonic collected value, then the steering gear has turned to the right side of the car. */

float left;
float right;

void setup() {
    Serial.begin(9600); /*Set the baud rate to 9600,use "Serial Monitor" to check the data during debugging*/
    head.attach(13); /* Define the control pin of the servo as pin 13*/
    pinMode(E2, OUTPUT);
    pinMode(E1, OUTPUT);
    pinMode(M1, OUTPUT);
    pinMode(M2, OUTPUT);
    pinMode(leftPin, INPUT);
    pinMode(rightPin, INPUT);
    pinMode(TrigPin, OUTPUT);
    pinMode(EchoPin, INPUT); /* Define two ultrasonic working mode.*/
    head.write(90); /* The servos swivel to 90 (center) during initialization, because some servos may have errors, so they are not necessarily centered at 90 degrees, so be fine - tuned where the servos are centered at 90 degrees.*/
    delay(1000);
}

void loop() {
    left = analogRead(leftPin);
```

```

right = analogRead(rightPin);

analogWrite(TrigPin, 0); // Low high and low send a short pulse to TrigPin)
delayMicroseconds(2);
analogWrite(TrigPin, 255);
delayMicroseconds(10);
analogWrite(TrigPin, 0);

da = pulseIn(EchoPin, HIGH) / 58.0; // Convert the echo time to cm

if (da >= 50 && da <= 2000 && (left >= 38) && (right >= 38)) {/* Judge the collected value, da>
= 50 && da <= 2000, meaning that when the distance between the current obstacle and the car is greater
than or equal to 50, and less than or equal to 2000cm, execute the following program in {} */

    int val = 150; /* When the straight line has a PWM value of 150, if the value is too high, the
speed of the car will be very fast, which may lead to the car can not hit the obstacle in time when
it encounters the obstacle. */

    digitalWrite(M1, 0);
    analogWrite(E1, val); //the speed value of motorA is val
    digitalWrite(M2, 0);
    analogWrite(E2, val); //the speed value of motorB is val
    Serial.print("Distance = ");
    Serial.print(da);
    Serial.print(" ");
    Serial.println("Moving advance 50");

    //delay(500);/* If the distance is more than 50cm, move forward and output "Moving advance 50",
indicating that the obstacle is more than 50cm from the car*/
}

if (da < 40 && da > 30 && (left >= 38) && (right >= 38)) {/* Judge the collected value, da < 50
&& da > 30, meaning that when the distance between the frontal obstacle and the car is greater than
30, and less than 40cm, execute the following program in {} */

    int val = 130;
    digitalWrite(M1, 0);
    analogWrite(E1, val); //the speed value of motorA is val
    digitalWrite(M2, 0);
    analogWrite(E2, val); //the speed value of motorB is val
    Serial.print("Distance = ");
    Serial.print(da);
    Serial.print(" ");
    Serial.println("Moving advance40");

    //delay(500);/* If the distance is more than 40cm, move forward and output "Moving advance 40",
indicating that the obstacle is more than 40cm from the car*/
}

if ((left <= 38) && (right >= 38) && (da >= 30 && da <= 1000)) {
    digitalWrite(M1, HIGH);
    analogWrite(E1, 0); //the speed value of motorA is val
    digitalWrite(M2, 0);
    analogWrite(E2, 250); //the speed value of motorA is val
}

```

```

Serial.println("Turning right");
delay(200);
analogWrite(M1, 0);
analogWrite(E1, 0);
analogWrite(M2, 0);
analogWrite(E2, 0);
//delay(1000); //******/Turning right
}

if ((left >= 38) && (right <= 38) && (da >= 30 && da <= 1000)) {
    analogWrite(M1, 0);
    analogWrite(E1, 250); //the speed value of motorA is 180
    digitalWrite(M2, HIGH);
    analogWrite(E2, 0); //the speed value of motorB is 180
    Serial.println("Turning left");
    delay(200);
    analogWrite(M1, 0);
    analogWrite(E1, 0);
    analogWrite(M2, 0);
    analogWrite(E2, 0);
    // delay(1000); //******/Turning left
}

else if (da <= 25) /* The collected value is judged, da <= 25, meaning that when the current obstacle
and the car is less than 20cm, execute the following program in {}, the distance between the car and
the obstacle has exceeded the safety value, So the car stopped forward */
{
    int val = 0;
    digitalWrite(M1, 0);
    analogWrite(E1, val); //the speed value of motorA is 0
    digitalWrite(M2, 0);
    analogWrite(E2, val); //the speed value of motorB is 0
    Serial.print("Distance = ");
    Serial.print(da);
    Serial.print("    ");
    Serial.println("Stopped");// If the distance is less than 20cm, the car will stop and output
    "Stopped"
    delay(500);
    head.write(180);/* Servo rotated 90 degrees from the original to 180 degrees, the left side of
the car */
    delay(1000);
    analogWrite(TrigPin, 0); // Low high and low send a short pulse to TrigPin
    delayMicroseconds(2);
    analogWrite(TrigPin, 255);
    delayMicroseconds(10);
    analogWrite(TrigPin, 0);
    dl = pulseIn(EchoPin, HIGH) / 58.0; // Convert the echo time to cm
}

```

```
Serial.print("Left distance = ");
Serial.print(dl);
Serial.print("  ");// Ultrasonic acquisition of the left side of the car and obstacles distance,
and then assigned to dl, then print on the "Serial Monitor" */
head.write(0);/* Servo steering from the original 180 degrees to 0 degrees, the right side of
the car */

delay(1000);

analogWrite(TrigPin, 0); // Low high and low send a short pulse to TrigPin
delayMicroseconds(2);
analogWrite(TrigPin, 255);
delayMicroseconds(10);
analogWrite(TrigPin, 0);

dr = pulseIn(EchoPin, HIGH) / 58.0; // Convert the echo time to cm
Serial.print("Right distance = ");
Serial.print(dr);
Serial.print("  ");

Serial.println();/*Ultrasonic acquisition of the distance between the right side of the car and
the obstacle, and then assigned to dr, and then print the distance on the "Serial Monitor" */
head.write(80);// head steering back, that is, when the initialization 80 degrees position

if (dl >= 20 && dl <= 1000 && dl > dr) {

    digitalWrite(M1, 0);
    analogWrite(E1, 180); //the speed value of motorA is 180
    digitalWrite(M2, 180); //the speed value of motorB is 180
    digitalWrite(E2, 0);
    Serial.println("Turning left1");
    delay(200); // determine the left and right distance if the left is larger than the left
}

else if (dl >= 1000) {

    digitalWrite(M1, 180); //the speed value of motorA is 180
    analogWrite(E1, 0);
    digitalWrite(M2, 0);
    analogWrite(E2, 180); //the speed value of motorB is 180
    Serial.println("Turning right1");
    delay(200);

    // Special case If the left return distance is greater than 1000, the probe is blocked and turn
right at this moment
}

else if (dr >= 20 && dr <= 1000 && dr > dl) {

    digitalWrite(M1, 180); //the speed value of motorA is 180
    analogWrite(E1, 0);
    digitalWrite(M2, 0);
    analogWrite(E2, 180); //the speed value of motorB is 180
    Serial.println("Turning right2");
    delay(200); // Judge about the distance if the right side then turn right
}
```

```

else if (dr >= 1000) {
    digitalWrite(M1, 0);
    analogWrite(E1, 180); //the speed value of motorA is 180
    digitalWrite(M2, 180); //the speed value of motorB is 180
    analogWrite(E2, 0);
    Serial.println("Turning left2");
    delay(200);
    // Special case If the return distance on the right is more than 1000, then the probe is blocked
    and turn left at this moment
}

else if (dr <= 20 && dl <= 20) {
    digitalWrite(M1, 255); //the speed value of motorA is 255
    analogWrite(E1, 0);
    digitalWrite(M2, 0);
    analogWrite(E2, 255); //the speed value of motorB is 255
    Serial.println("Turning around");
    delay(700);
    // turn around if both sides are less than 20cm in distance
}
}
}
}

```

In front the sections, we focus on the "automatic driving", and they are obstacle avoidance experiments. We didn't seem to have relationship with the car, it is lack of fun. Now in the next few sections, we will develop the car from other aspects to make sure that we are able to control the car personally, then we will start from the "infrared remote control", followed by "2.4G handle remote control" and the last is "mobile phone Bluetooth control".

### 3.2.5 Infrared Remote Control

#### 3.2.5.1 Suite Introduction

Infrared remote control is widely used in every field which is known to everyone, since it can control other electrical appliances, naturally it can control the Hummer-Bot car. Let us take a look at the infrared remote control first:

Infrared wireless remote control kit consists of Mini ultra-thin infrared remote controller and 38KHz infrared receiver module, the remote controller has 17 function keys, the transmission distance is up to 8 meters which is very suitable for controlling equipment indoor. The infrared receiving module can receive 38KHz modulation remote control signal. Through the Arduino programming, the decoding operation of Infrared wireless remote control signal can be realized so as to produce all kinds of remote control robot and interactive works. The suite is shown in Fig.3.2.34.



Figure .3.2.34 Physical Map of Remote Control Suite

Infrared remote control system is mainly divided into modulation, transmitting and receiving parts. The transmitting part is mainly composed of keyboard, remote control specific integrated circuit, exciter and infrared light emitting diode. The integrated circuit is the core part of the launch system which consists internal oscillation circuit, timing circuit, scanning signal generator, key input encoder, instruction decoder, user code converter, digital modulation circuit and buffer amplifier and so on. It can produce a key scanning pulse signal, translate the key code, then obtain remote control commands of the keys by telecommand encoder (remote control encoding pulse). Through pulse amplitude modulation of the 38KHZ carrier signal, the infrared diode can transmit infrared remote control signal.

In the infrared receiver, photoelectric converter (usually a photodiode or photoelectric triode, here we use PIN photodiode) converts the received infrared light instruction signal into a corresponding electrical signal. The received signal is very weak and interference is particularly large, in order to achieve the accurate detection and signal conversion, in addition to the infrared photoelectric conversion device with high performance, choosing the reasonable circuit design with good performance is also required. The most common photoelectric conversion device is a photodiode. When the photosensitive surface of the PN junction is irradiated by light, the semiconductor material of PN junction absorbs light energy and converts the light energy into electric energy. When the reverse voltage is added to the photodiode, the reverse current in the diode will change with the change of the incident light intensity. The larger the radiation intensity is, the larger the reverse current will be, the reverse current of the photoelectric varies with the incident light pulse.

In the Hummer-Bot car, the integrated infrared receiving head has three pins, including the power supply pin, grounding and signal output pin. The circuit is shown in Fig.3.2.35. Ceramic capacitors is a decoupling capacitor which can filter the output signal interference. The 1 end is the output of the demodulation signal which is directly connected to the number 2 port on the Arduino. When the infrared coded signal is transmitted, it will be processed by the infrared joint, then outputs the square wave signal, and directly supplied to the Arduino, and the corresponding operation is carried out to control the motor.

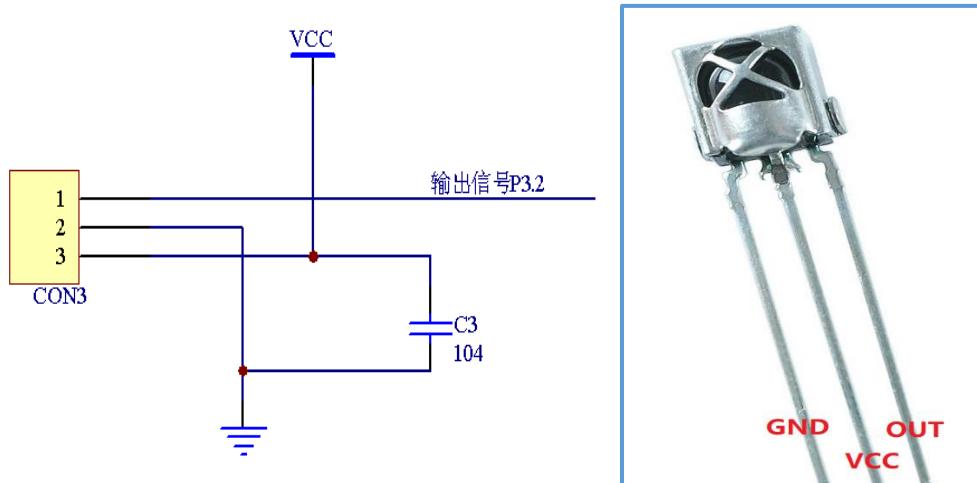


Figure .3.2.35 Circuit Diagram and Physical Map of Infrared Receiving Head

### 3.2.5.2 Working Principle

The remote control system in general composed of the remote controller (transmitter), and receiver, when you press any button on the remote control, it will generate the corresponding encoding pulse and output various control pulse signals based on the infrared, infrared monitor diode sends the signal to the the amplifier and the pulse amplitude limiter, the limiter controls the pulse amplitude at a certain level, regardless of the distance of infrared transmitter and receiver. AC signal enters the band-pass filter which can pass the 30KHZ to the load wave 60KHZ and enters the comparator through the demodulation circuit. The comparator outputs high or low level and restores the output signal waveform. The system procedure diagram is shown in Fig.3.2.36.

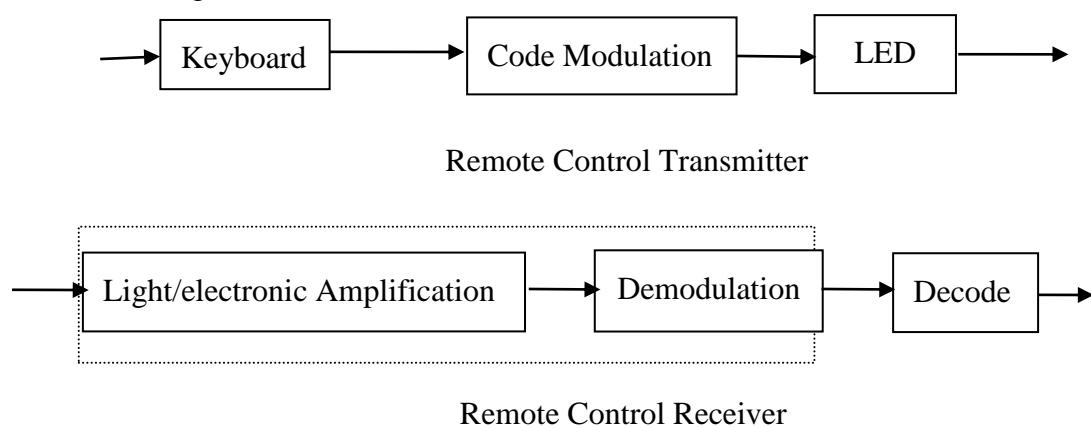


Fig.3.2.36 Remote Control System Diagram

### 3.2.5.3 Experimental Procedures

1, Installing the infrared receiving head on the development board (if it has been installed in the eighth step in "3.1.2", please ignore. The complete installation is shown in Fig.3.1.37.

2, Referring to Fig.3.2.37 and connecting the infrared receiving module to the Arduino board (you can choose other IO ports according to your own ideas)

**Note:** Do not reverse power line, otherwise the receiving head will burn up.

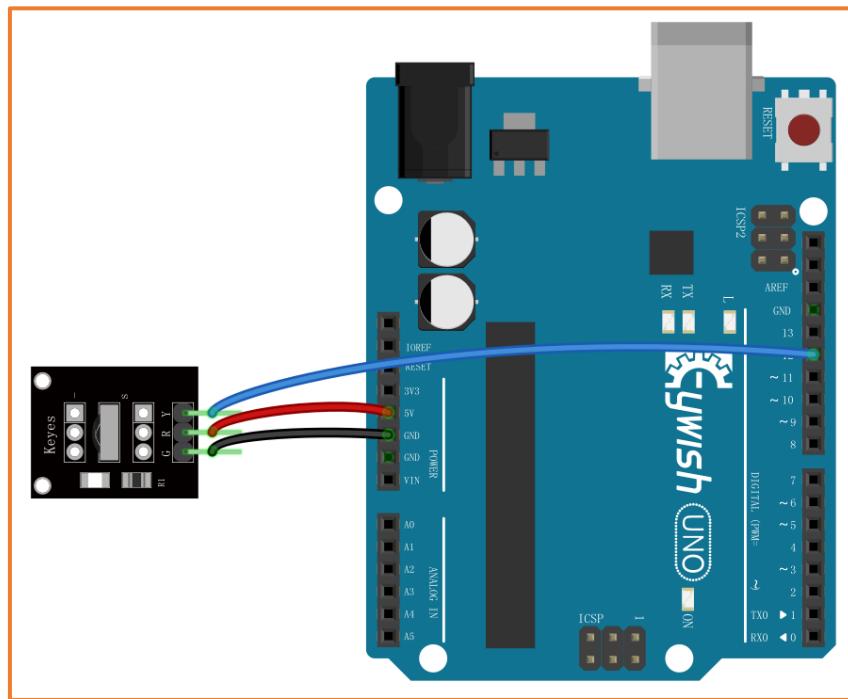
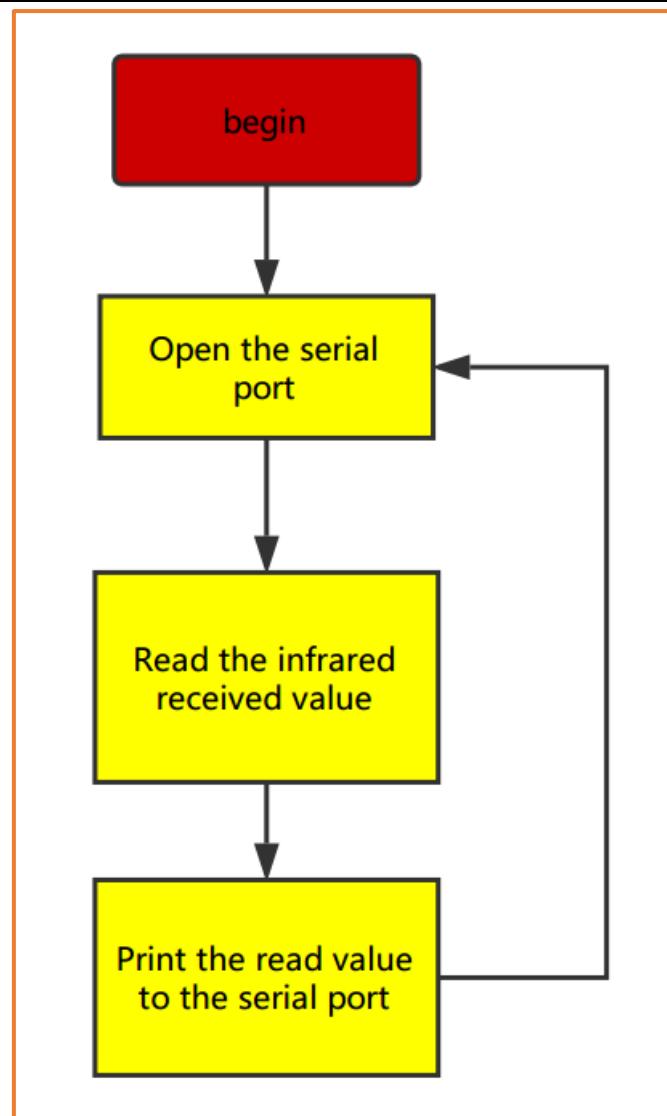


Figure .3.1.37 Infrared Module Connection Diagram

3, Copying the following program to IDE (you can also directly open the matching program in the CD), and downloading to the development board, pulled out the transparent plastic sheet marked as "1" in the Fig.3.2.33. Then opening the serial port monitor, observing and recording the values on it while pressing keys on the remote control towards the receiving head as shown in Fig.3.2.38.

Program flow chart is as follows:



Code Path : “hummer-bot\Lesson\ModuleDemo\IrkeyPressed\ IrkeyPressed.ino”

```
#include "IRremote.h"
IRremote ir(12);
unsigned char keycode;
char str[128];
void setup() {
    Serial.begin(9600);
    ir.begin();
}
void loop()
{
    if (keycode = ir.getCode()) {
        String key_name = ir.getKeyMap(keycode);
        sprintf(str, "Get ir code: 0x%02x key name: %s \n", keycode, (char *)key_name.c_str());
        Serial.println(str);
    } else {
        // Serial.println("no key");
    }
    delay(110);
}
```

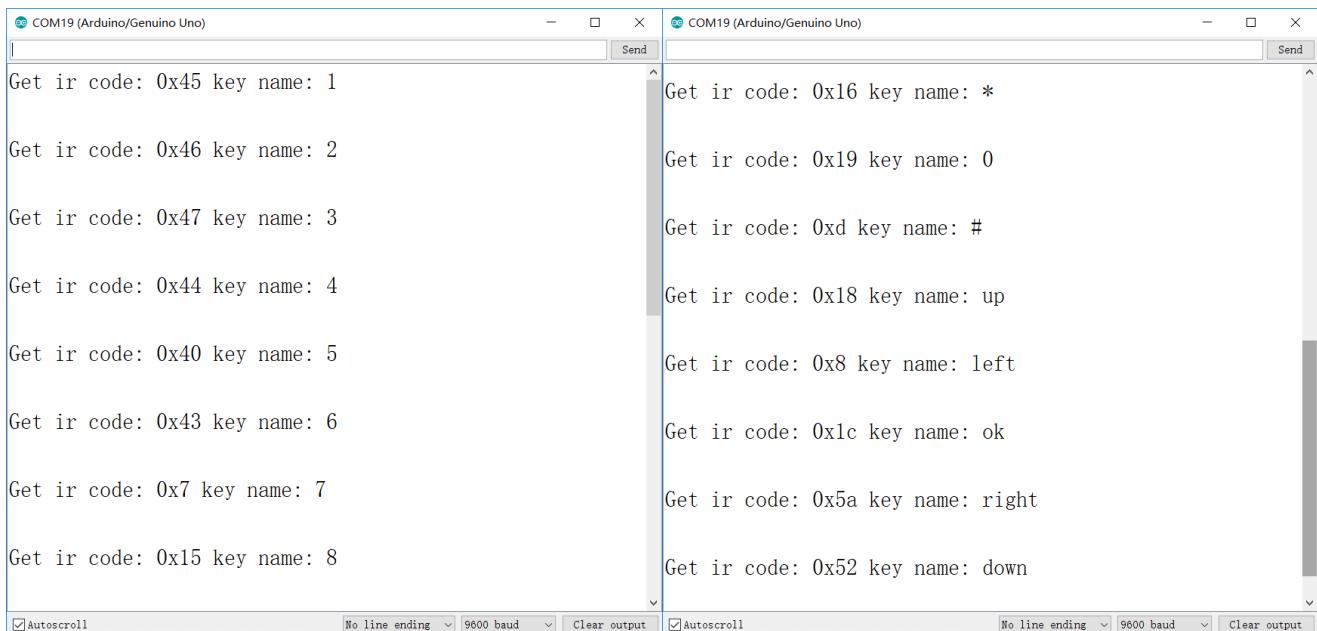


Figure .3.2.38 Remote Encoding Query

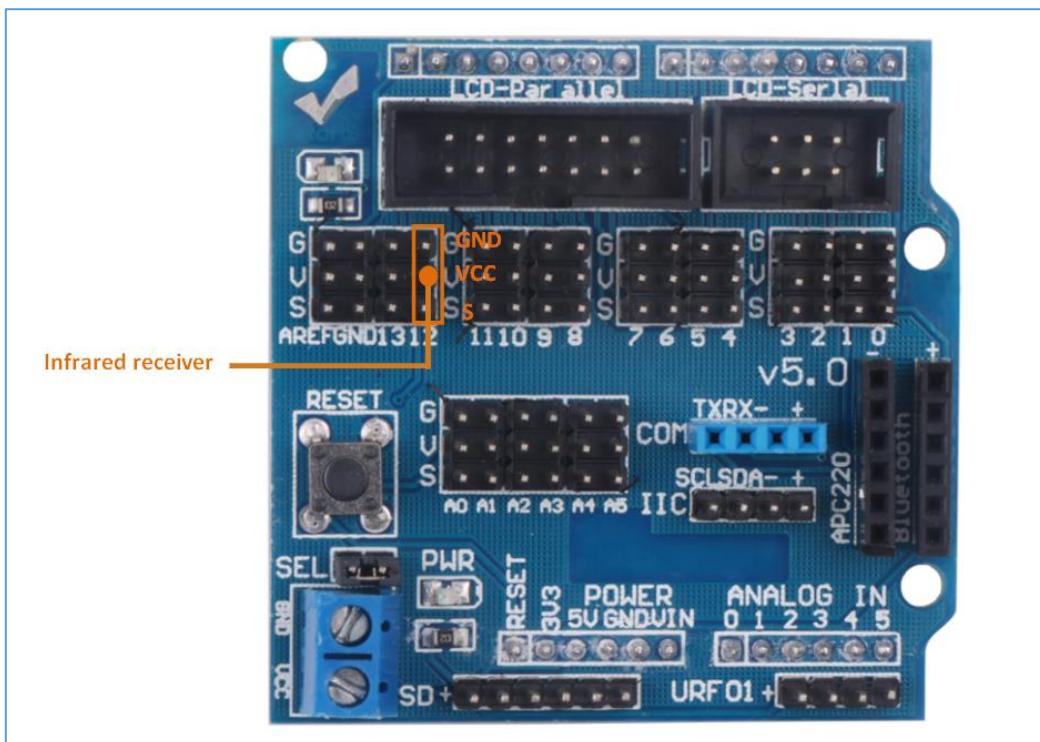
In Figure 3.2.38, we can see two values of Ir Code "0x45" and keyname "1", where "0x45" is the code of a key of the remote controller, and "1" is the name of the key function of the remote controller.

The key mapping table is as follows:

```
ST_KEY_MAP irkeymap[KEY_MAX] = {
    {"1", 0x45},
    {"2", 0x46},
    {"3", 0x47},
    {"4", 0x44},
    {"5", 0x40},
    {"6", 0x43},
    {"7", 0x07},
    {"8", 0x15},
    {"9", 0x09},
    {"0", 0x19},
    {"*", 0x16},
    {"#", 0x0D},
    {""up", 0x18},
    {""down", 0x52},
    {""ok", 0x1C},
    {""left", 0x08},
    {""right", 0x5A}
};
```

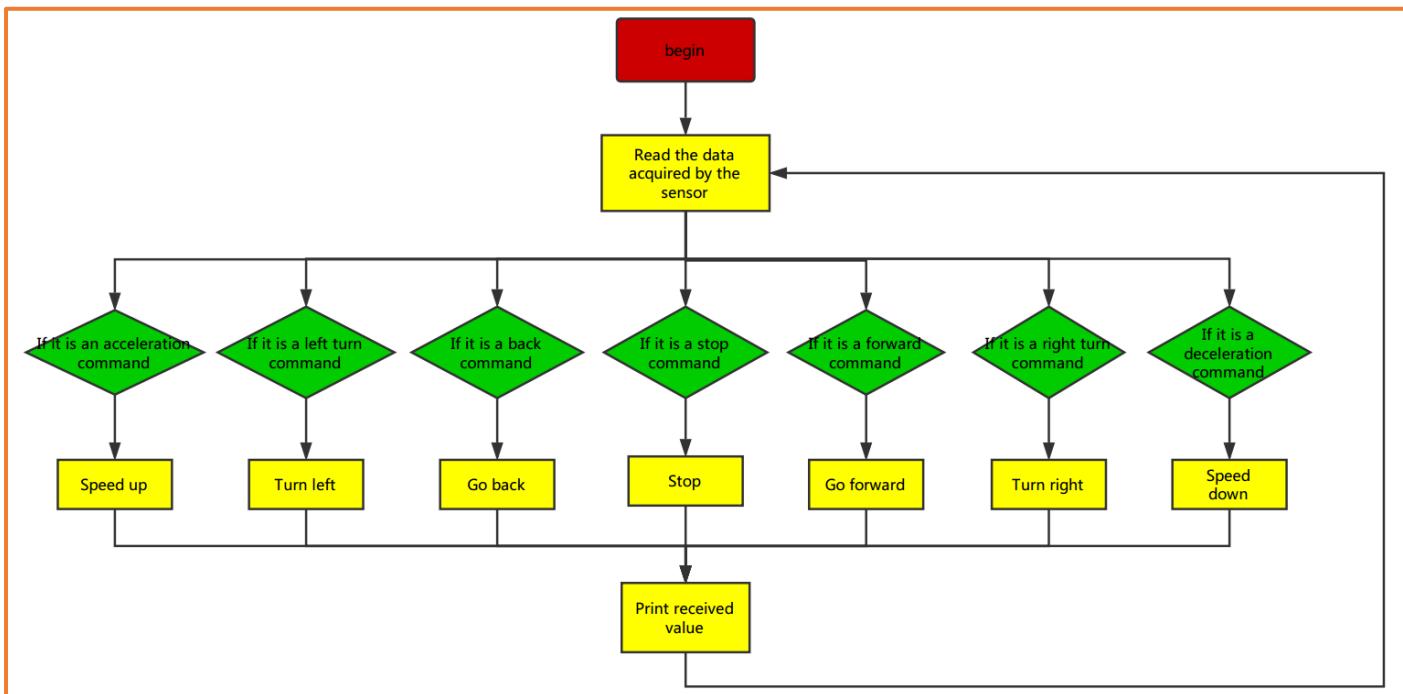
### 3.2.5.4 Wire connection

As shown in the below figure, the infrared receiver's "s" pin is connected to "12" pin, the "-" pin is connected to "GND", and the middle pin is connected to "VCC".



## 3.2.5.5 Software Design

### 3.2.5.5.1 Program flow chart



Code Path : “hummer-bot\Lesson\Advanced Experiment\Hummerbot\_IR\Hummerbot\_IR.ino”

### 3.2.5.5.2 Program code

```
#include <IRremote.h> /*In this section, we use infrared remote control, so we need to  
call the corresponding library file, as for what is in the library file, we will not  
study, and interested friends can drive research. We have put this library files on the  
CD-ROM, we need to copy this folder to the Arduino IDE installation path "libraries"  
folder, otherwise the program can not compile. */  
  
int E1 = 5;//PWMA  
  
int M1 = 9;//DIRA*****left  
int E2 = 6;//PWMB  
  
int M2 = 10;//DIRB*****right  
  
int RECV_PIN = 12;  
  
long expedite1 = 0xFF6897; /* Define a long integer expedite1 variable, and assign this  
variable 0xFF689, FF689 is the infrared remote control button encoding */  
long expedite2 = 0xFFB04F;  
  
long advance = 0xFF18E7;  
  
long back = 0xFF4AB5;  
  
long stop = 0xFF38C7;  
  
long left = 0xFF10EF;  
  
long right = 0xFF5AA5;
```

```
IRrecv irrecv(RECV_PIN);
decode_results results;

void setup() {
    Serial.begin(9600);
    irrecv.enableIRIn(); // Initialize the infrared receiver
}

void loop() {
    if (irrecv.decode(&results)) {/* Read the value received by the infrared */
        if (results.value == advence) {/* Judgment on the received value, if this value
            is advence, execute the following {} command, here is the forward instruction. */
            int val = 150;
            analogWrite(M1, 0);
            analogWrite(E1, val); //the speed value of motorA is val
            analogWrite(M2, 0);
            analogWrite(E2, val); //the speed value of motorB is val
            delay(500); irrecv.resume(); // Receive the next value
        }
        if (results.value == expedite1) {/* Judgment on the received value, if this value
            is expedite1, execute the command in {} below, here is the acceleration 1 command.
            */
            int val = 200;
            analogWrite(M1, 0);
            analogWrite(E1, val); //the speed value of motorA is val
            analogWrite(M2, 0);
            analogWrite(E2, val); //the speed value of motorB is val
            delay(500); irrecv.resume();
        }
        if (results.value == expedite2) {/* Judgment on the received value, if the value
            is expedite2, execute the command {} below, here for the acceleration 2 command. */
            int val = 255;
            analogWrite(M1, 0);
            analogWrite(E1, val); //the speed value of motorA is val
            analogWrite(M2, 0);
            analogWrite(E2, val); //the speed value of motorB is val
            delay(500); irrecv.resume();
        }
        if (results.value == stop) {/* To judge the value received, if this value is stop,
            execute the command in the following {}. here is the stop instruction. */
    }
}
```

```

        int val = 0;
        analogWrite (M1, 0);
        analogWrite(E1, val);//the speed value of motorA is val
        analogWrite (M2, 0);
        analogWrite(E2, val);//the speed value of motorB is val
        delay(500);
        irrecv.resume();
    }

    if (results.value == left) /* Judgment on the received value, if the value is left,
execute the command in the following {}, here is the instruction to the left. */
    {
        int val = 150;
        analogWrite (M1, 0);
        analogWrite(E1, val);//the speed value of motorA is val
        analogWrite (E2, 0);
        analogWrite(M2, val);//the speed value of motorB is val
        delay(500);/* Rotate 500ms to the left and stop, otherwise the car will always
be spinning around. */
        analogWrite (M1, 0);
        analogWrite(E1, 0);//the speed value of motorA is 0
        analogWrite (M2, 0);
        analogWrite(E2, 0);//the speed value of motorB is 0
        analogWrite(A1, 180);
        irrecv.resume();
    }

    if (results.value == right) /* Judgment on the received value, if the value is
right, execute the command in the following {}, here is the command to the right.
*/
    {
        int val = 150;
        analogWrite (E1, 0);
        analogWrite(M1, val);//the speed value of motorA is val
        analogWrite (M2, 0);
        analogWrite(E2, val);//the speed value of motorB is val
        delay(500);
        analogWrite (M1, 0);
        analogWrite(E1, 0);//the speed value of motorA is 0
        analogWrite (M2, 0);
    }
}

```

```

analogWrite(E2, 0); //the speed value of motorB is 0
analogWrite(A2, 180);
irrecv.resume();
}

if (results.value == back) {/* Judgment on the received value, if the value
is back, execute the command {} below, here for the back instruction. */
    int val = 150;
    analogWrite (E1, 0);
    analogWrite(M1, val); //the speed value of motorA is val
    analogWrite (E2, 0);
    analogWrite(M2, val); //the speed value of motorA is val
    delay(500);
    irrecv.resume(); // 接收下一个值
}

Serial.println(results.value, HEX); // Output the receive code in hexadecimal
Serial.println(); // Add a blank line for easy viewing of the output
irrecv.resume();
}
}

```

The above is the infrared remote reference program, you can open it in the CD and download to the development board, the instructions of remote control in shown in Fig.3.2.39.

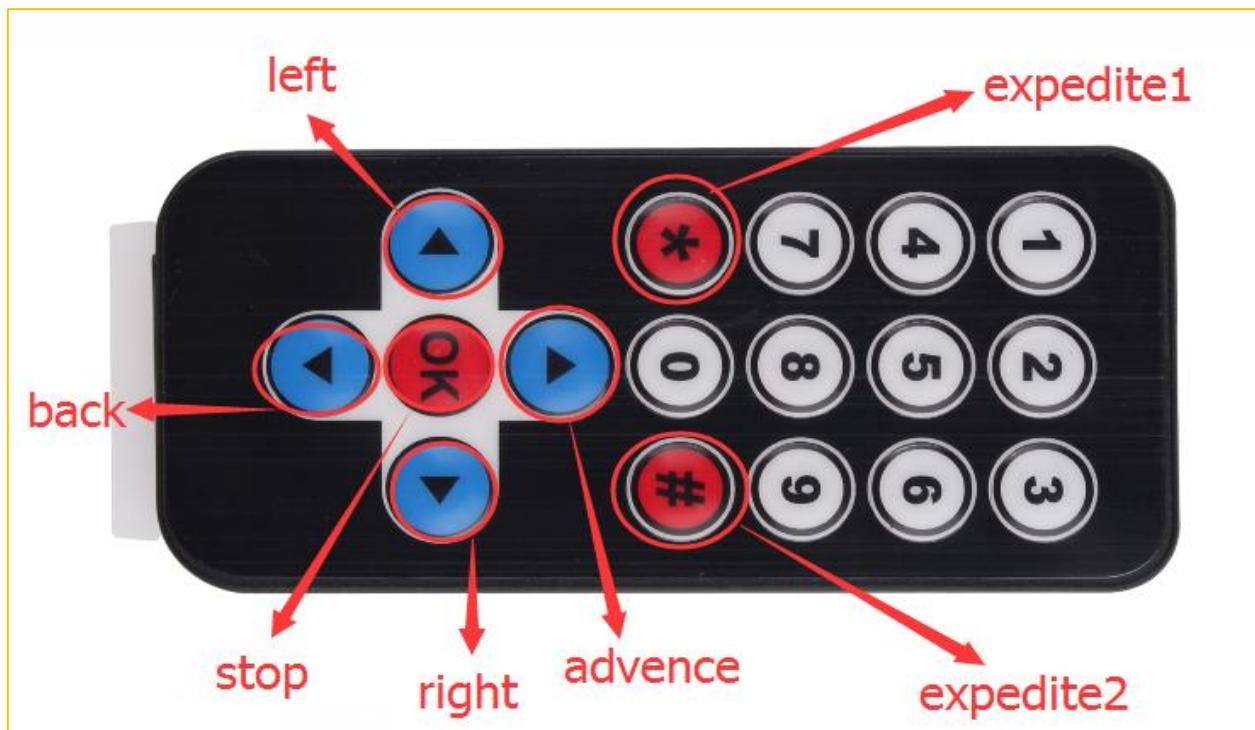


Fig.3.2.39. Infrared Remote Control Instructions

## 3.2.6 Mobile Phone Bluetooth Control

### 3.2.6.1 Suite Introduction

Hummer-Bot supports Bluetooth mobile phone Bluetooth remote control function is JDY-16 BLE (Bluetooth Low Energy).JDY-16 transparent transmission module is based on the Bluetooth 4.2 protocol standard, operating frequency range is 2.4GHZ range, modulation mode is GFSK, maximum transmission power is 0db, maximum transmission distance is 80 meters, adopts original imported chip design, and supports users to modify device by AT command. Names, service UUIDs, transmit power, pairing passwords, and other instructions are convenient and quick to use. For module information, see aurora-racing\Document\JDY-16-V1.2(English manual).pdf

The physical diagram of module is shown in Fig.3.2.40.



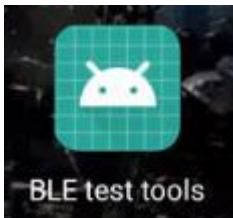
Fig.3.2.40 JDY-16 Module

#### 1) JDY-16 function introduction

- 1: BLE high speed transparent transmission supports 8K Bytes rate communication.
- 2: Send and receive data without byte limit, support 115200 baud rate continuously send and receive data.
- 3: Support 3 modes of work (see the description of AT+STARTEN instruction function).
- 4: Support (serial port, IO, APP) sleep wake up.
- 5: Support WeChat Airsync, WeChat applet and APP communication.
- 6: Support 4 channel IO port control.
- 7: Support high precision RTC clock.
- 8: Support PWM function (can be controlled by UART, IIC, APP, etc.).
- 9: Support UART and IIC communication mode, default to UART communication.
- 10: iBeacon mode (support WeChat shake protocol and Apple iBeacon protocol).
- 11: Host transparent transmission mode (transmission of data between application modules, host and slave communication).

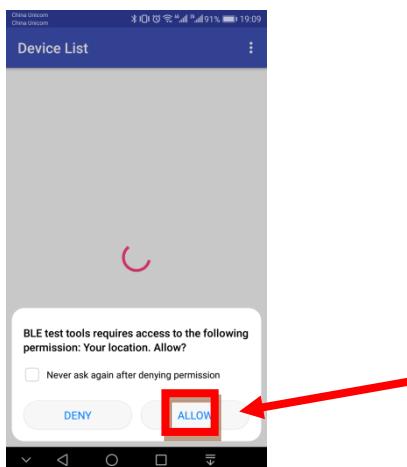
### 3.2.7.1 Use app to communicate with the serial port

- 1) Install “hummer-bot\JDY-16\BLETestTools.apk”, then turn on Bluetooth.
- 2) Open app, you will be asked to allow location permission at first, please allow.

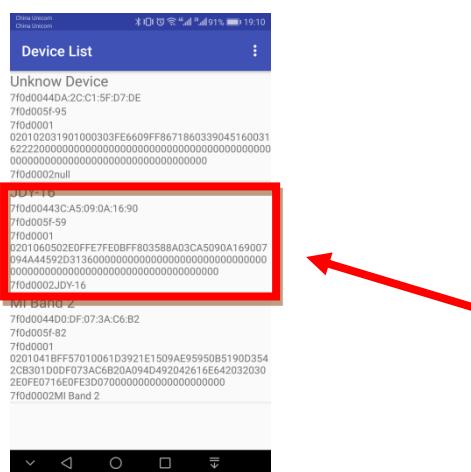


App: BLE test tools

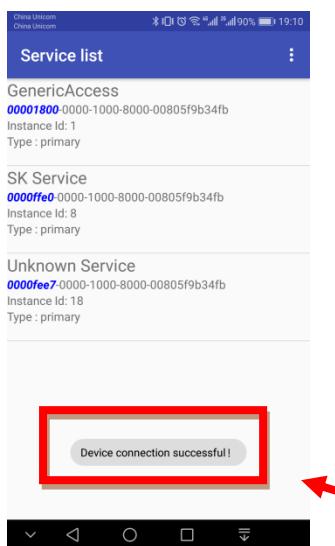
- 3) If Bluetooth information is not displayed, please pull down to refresh, if it still don't work, please close and reopen it.



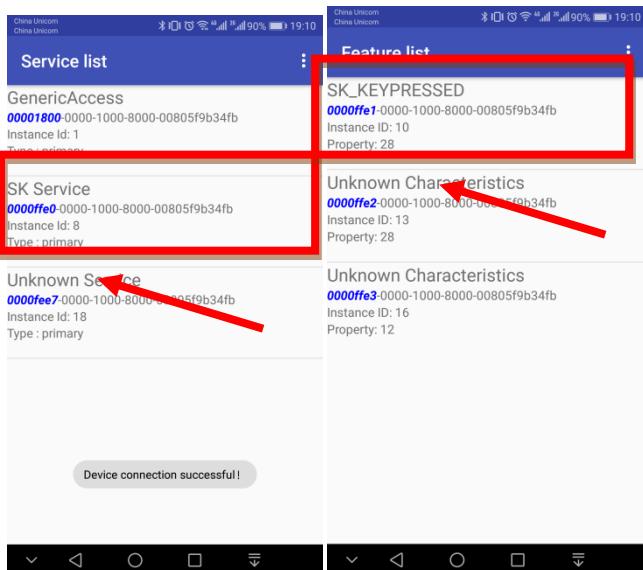
- 4) Select the JDY-16 Bluetooth model.



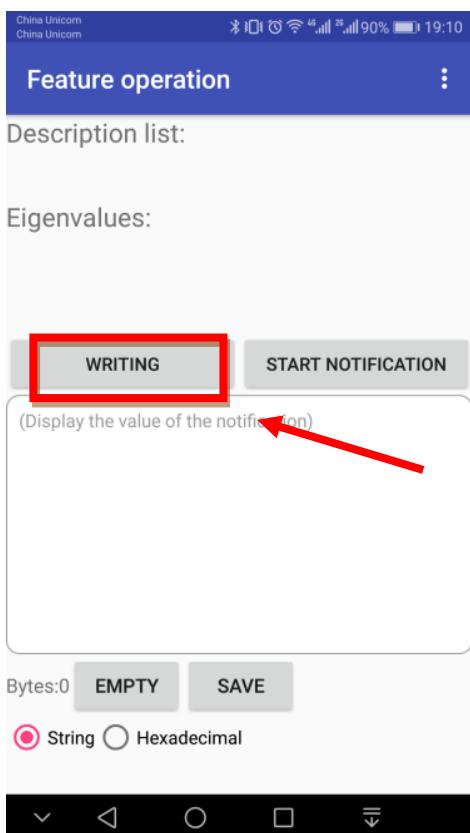
- 5) There will pop up a window which indicate connection success and jump to the operation interface:



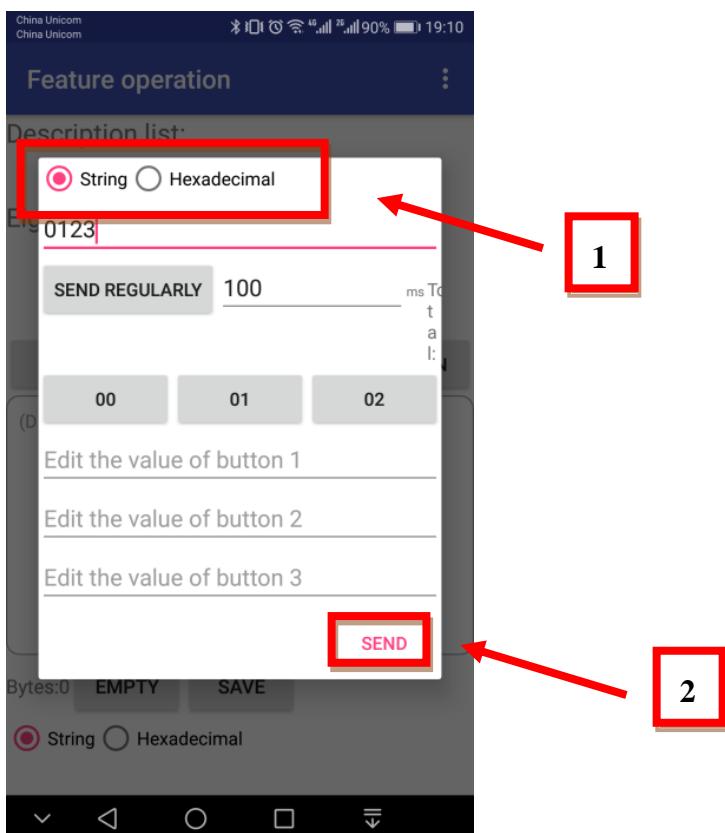
6) Click the second option “SK Service”,then click the first option “SK KEYPRESSED”:



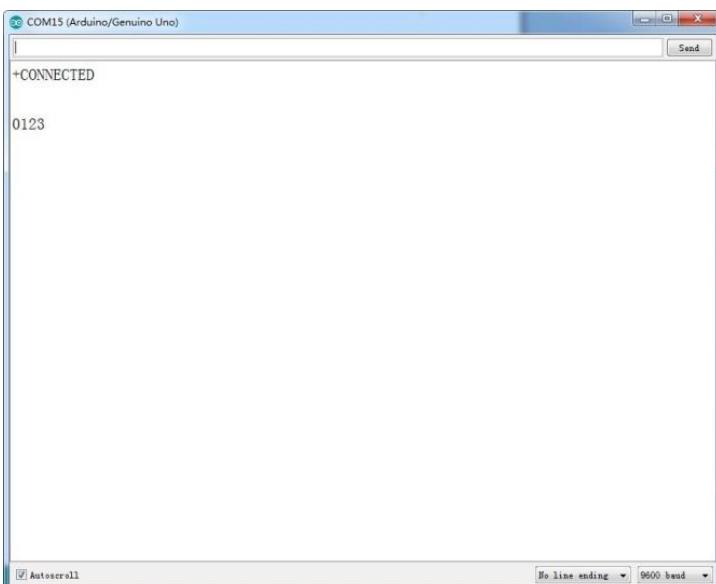
7) In the end you will jump to the user interface,click “WRITING” to send.



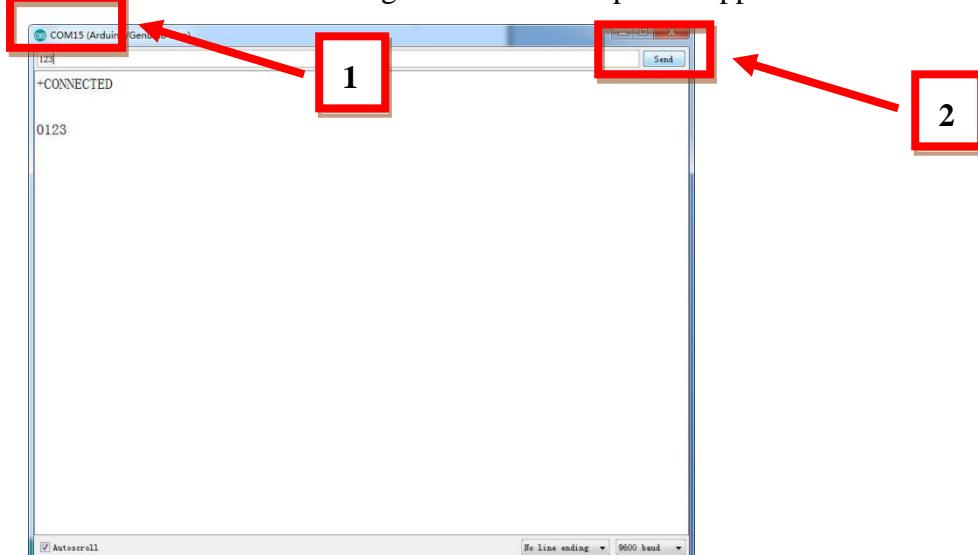
- 8) Write data on the pink line, click “send” to send.



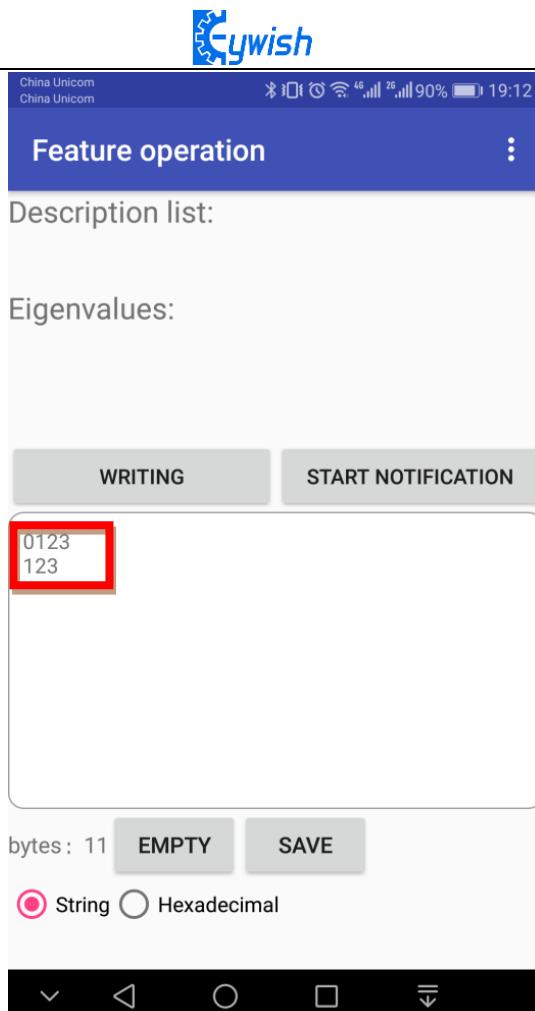
Serial port display as follow:



9) You can also send date through Arduino serial port to app.



10) The result as below:



Picture. 3.2.28

During above test, both the PC and Android can send and receive data normally, indicating that the Bluetooth module communicates normally and achieves the expect effect. Next, it can be used as a bridge between "Aurora" and the APP to control "Aurora" to realize the desired features.

### 3.2.6.3 Bluetooth protocol

Using Bluetooth to control the car means we use the Android app to control the Bluetooth sending instructions to the Arduino serial port, so as to control the motor's forwarding, reversing, speed and so on. Since the wireless communication is involved, one of the essential issues is the communication problem between the two terminals. But there is no common "language" between them, so designing communication protocols are required to ensure a perfect interaction between Android and Arduino. The main process is: the Android identification terminal packs the detected commands into the corresponding data packets, and then sends them to the Bluetooth module (JDY-16). When JDY-16 receives the packets, it will transmit them to Arduino through the serial port, then Arduino to analyze the data packets and execute the corresponding actions. The data format sent by the upper computer end (Android) is as follows, which mainly contains 8 fields, we use a structure to represent it.

Protocol Header	Data Length	Device Type	Device Address	Function Code	Control Data	Check Sum	Protocol End Code
-----------------	-------------	-------------	----------------	---------------	--------------	-----------	-------------------

In the 8 fields above, we use a structural body to represent.

```

typedef struct
{
    unsigned char start_code;           // 8bit 0xAA
    unsigned char len;
    unsigned char type;
    unsigned char addr;
    unsigned short int function;      // 16 bit
    unsigned char *data;              // n bit
    unsigned short int sum;           // check sum
    unsigned char end_code;           // 8bit 0x55
}ST_protocol;

```

“Protocol Header” means the beginning of the packet, such as the uniform designation of 0xAA.

“Data length” means except the valid data length of the start and end codes of the data.

“Device type” means the type of device equipment

“Device address” means the address that is set for control

“Function code” means the type of equipment functions that need to be controlled, the function types we currently support is as follows:

```

typedef enum
{
    E_BATTERY = 1,
    E_LED = 2,
    E_BUZZER = 3,
    E_INFO = 4,
    E_ROBOT_CONTROL = 5,
    E_ROBOT_CONTROL_SPEED = 6,
    E_TEMPERATURE = 7,
    E_IR_TRACKING = 8,
    E_ULTRASONIC = 9,
    E_VERSION = 10,
    E_UPGRADE = 11,
}E_CONTOROL_FUNC ;

```

The data means the specific control value of a car, such as speed, angle.

“Checksum” is the result of different or calculated data bits of the control instruction.

“Protocol end code ” is the end part of the data bag when receiving this data ,it means that the data pack has been sent, and is ready for receiving the next data pack, here we specified it as 0x55.

For example, a complete packet can be such as "AA 070101065000 5F55", in which:

"07" is Transmission Data Length 7 bytes.

"06" is the "function code",The 06 here refers to the transmission speed.

"50 (or 0050)" is the controlling data, 0x50 in hexadecimal is 80 when converted to binary, which means the speed value is 80. If the data is 05, it means the controlling direction, that is 80 degrees (forward).

"005F" is the check sum, that is,  $0x07+0x01+0x01+0x06+0x50 = 0x5F$ .

"55" is the tail of the protocol, indicating the end of data transmission.

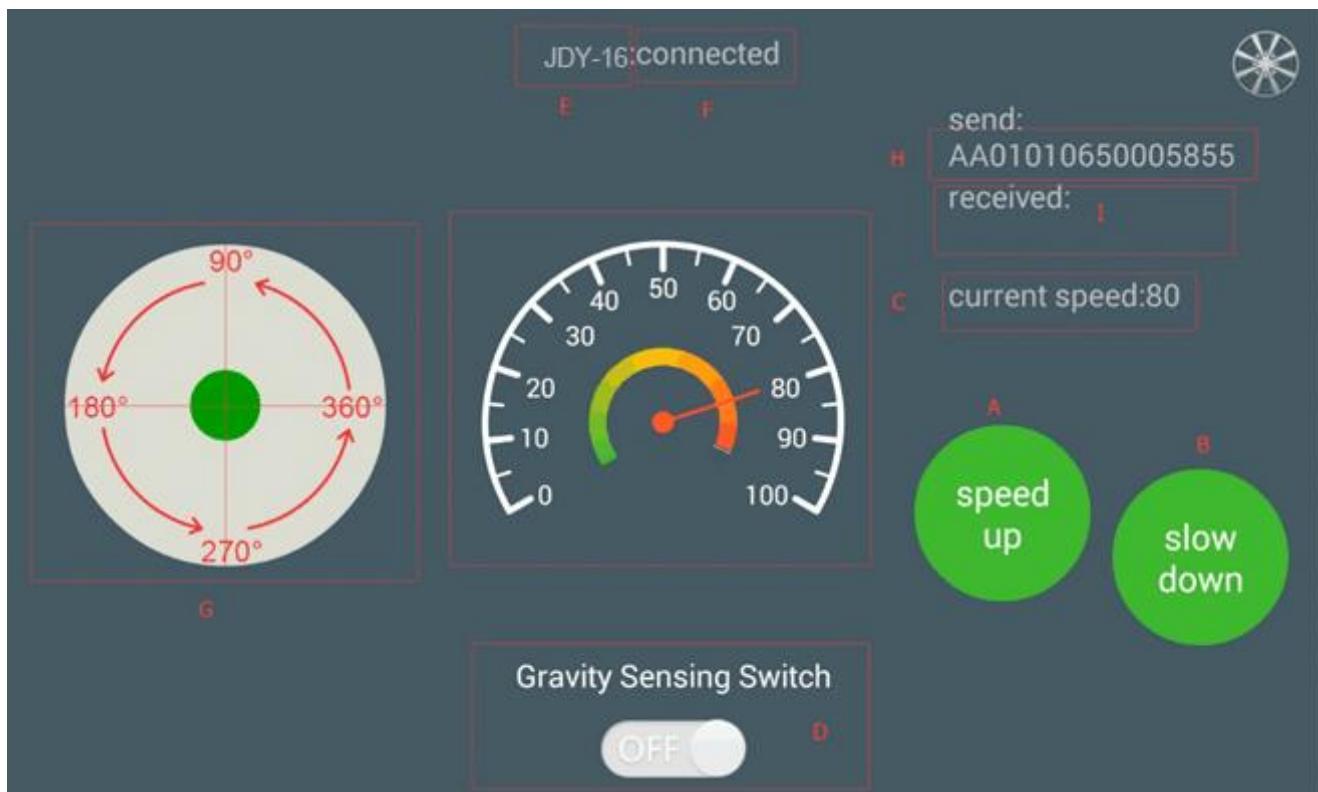


Fig.3.2.50 the Interface of Android APP

In the above Figure.3.2.50:

The "A, B" sections are the acceleration and deceleration buttons.

The "C" section includes the dashboard and the digital display area, and the two parts displaying synchronously. They represent the current speed.

The "D" section is a gravity remote sensing switch which can be switched to the gravity remote sensing mode.

The "E" section represents the Bluetooth name that is currently connected.

The "F" section indicates Bluetooth connection state. If the Bluetooth is not connected, the "disconnected" is displayed here.

The "G" section is a manual rocker, and sliding it allows the car to rotate.

The "I" section is a data return area, such as the current state, speed of the car, etc. The "H" section is the data packet, for example, the data is "AA 01 01 06 23 00 2B 55". At this time, the speed is 35 (23 is 16 hexadecimal data, which means 35 when converted to 10 hexadecimal).

If the transmitted data is "AA 01 01 05 00 5B 00 62 55", it means that the car is moving forward (05 is the direction control instruction, and the 005B means 91 when converted to binary number. By the Figure.3.2.48 we can know that 91 degree means the car is moving forward).

### 3.2.6.4 Experimental Procedures

Connect the Bluetooth module of the wire to "1" marked in Fig.3.2.51 Connection mode: JDY-16 VCC port on Bluetooth module is connected to Arduino 3.6V~6V DC power anode, GND port is connected to the cathode of the DC power, the RXD port is connected to the TXD port on Arduino extended board, TXD port is connected to RXD port on the board, as shown in Fig.3.2.52.

Note: Since Arduino UNO has only one serial port, the Bluetooth must be disconnected from the serial port when downloading the program, otherwise the download will fail.

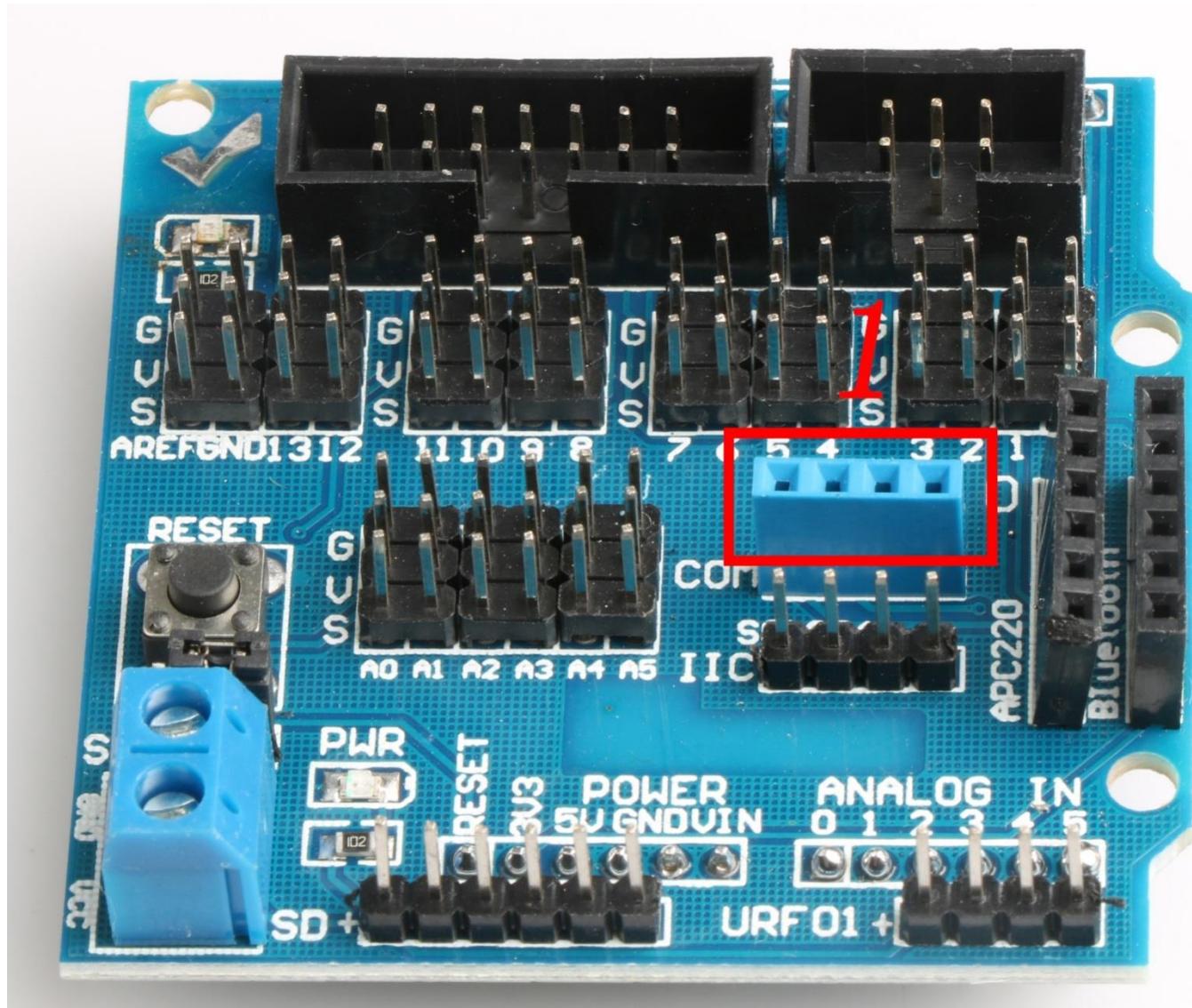


Figure .3.2.51 Wiring Positions of Bluetooth

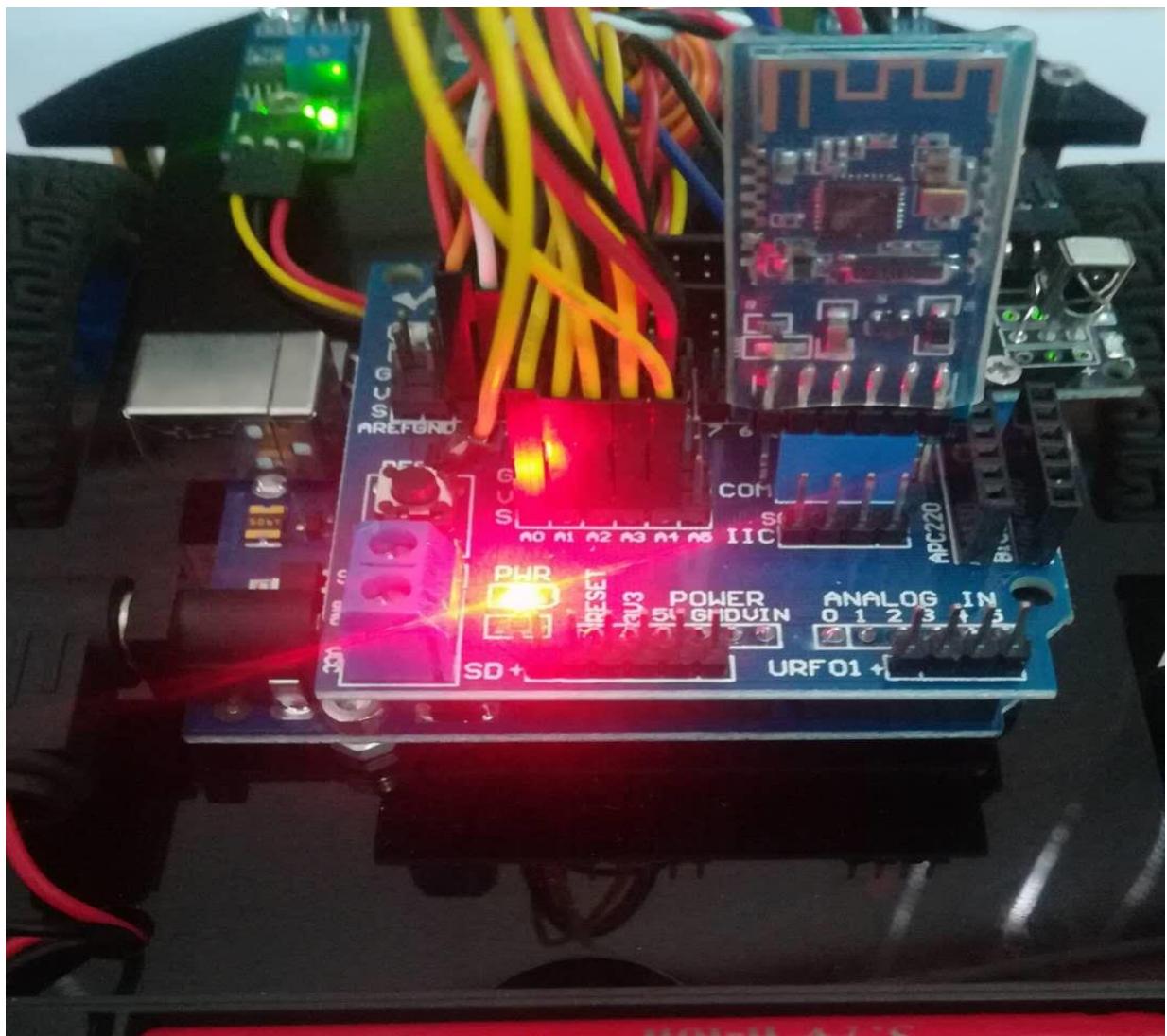


Figure .3.2.52 Installation of Bluetooth Module

2, Open the mobile phone Bluetooth and the APP (There is a software installation package on the CD, latter we will launch the IOS version.) You will see that the flashing of the Bluetooth module indicator slows down after successful connection. If you have downloaded the program to the development board before, you can use the phone to control the car directly, as shown in Fig.3.2.52.

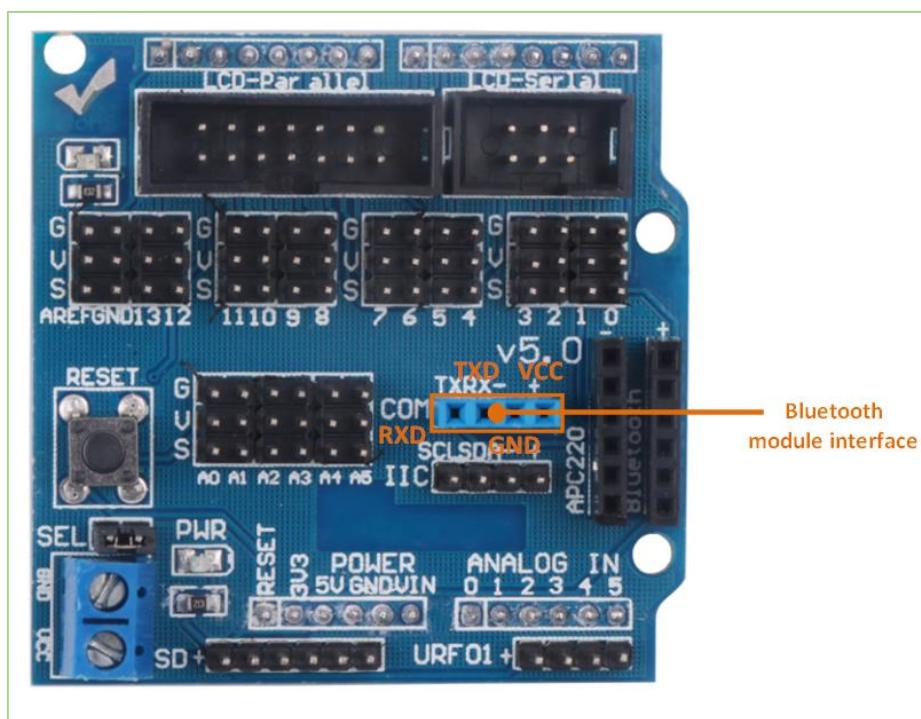


Figure .3.2.53. Diagram of APP Control

In Fig.3.2.53, we can see the logo "1" and "2". When the Bluetooth connection is successful, sliding green dot marked as "1" in any direction, the car will move towards the corresponding direction. Switching on the gravity sensor marked in "2", the APP is switched to the gravity induction mode, and you can control the movement direction of the car by shaking the mobile phone.

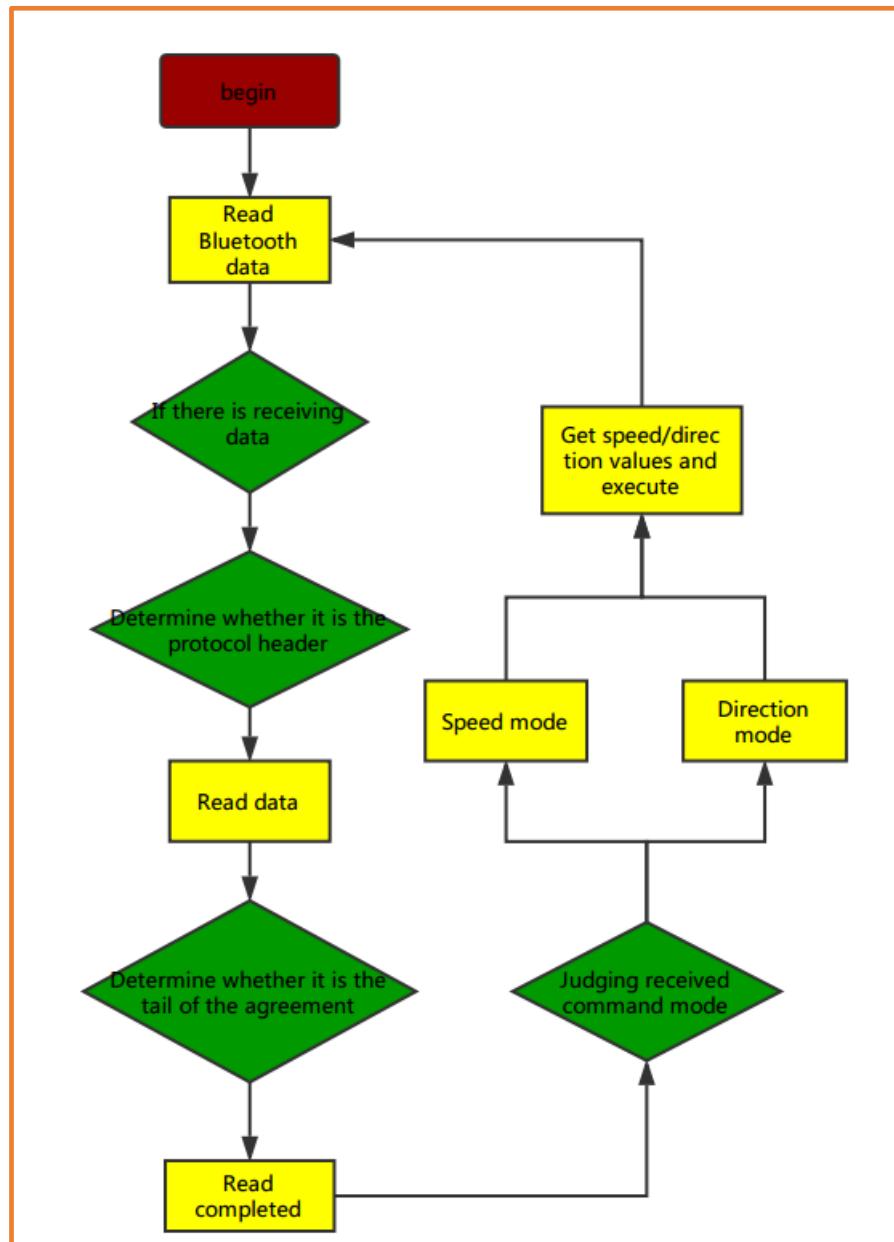
### 3.2.6.5 Wire connection

Bluetooth wire connection location as shown below:



### 3.2.6.6 Software Design

#### 3.2.6.6.1 Program flow chart



#### 3.2.6.6.2 Program Code

Code path hummer-bot\Lesson\Advanced Experiment\Hummerbot\_Bluetooth\Hummerbot\_Bluetooth\

### 3.2.7 PS2 Handle (Optional)

#### 3.2.7.1 Suite Introduction

PS2 handle is SONY game remote control handle, SONY series game host is very popular in the world. Someone has come up with the idea of the PS2 handle, cracked the communication protocol, so that the handle can be connected to other devices for remote control, such as remote control of our familiar four wheeled vehicles and robots. Its outstanding features are cost-effective, rich buttons and easy to extend to other applications, Fig.3.2.54 shows a commonly used PS2 wireless handle.



Figure .3.2.54 PS2 Wireless Handle

The PS2 handle is composed of the handle and the receiver, the handle uses two AAA batteries as power supply. The controller and receiver use the same power supply whose voltage range is 3~5V, overvoltage, reverse connection will cause the receiver to burn out. There is a power switch on the handle, ON /OFF, when you switch it to ON, the light on handle will not stop flashing until the receiver is searched. In a certain period of time, if the receiver can't be find, the handle will enter the standby mode and the light will burn out, you can press "START" button to wake up the handle.

The receiver is powered by the Arduino as shown in Fig.3.2.55, in the absence of pairing, the green light flashes. When the handle switch is opened, the handle and receiver will pair automatically, and the

light will be always on, and the handle is matched successfully. Button "MODE" (The above logo may be "ANALOG" in different handles, but it will not affect the usefulness), you can choose "red light mode" or "green light mode".

Some users see that the handle and receiver cannot match properly! Most of the problems are the incorrect wiring of the receiver and the program problems.

Solution: The receiver should only be connected with power supply (power line must be connected correctly), not any data lines and clock lines. The handle light will be always on when pairing is successful. Then checking whether the wiring and program transplantation are correct again.

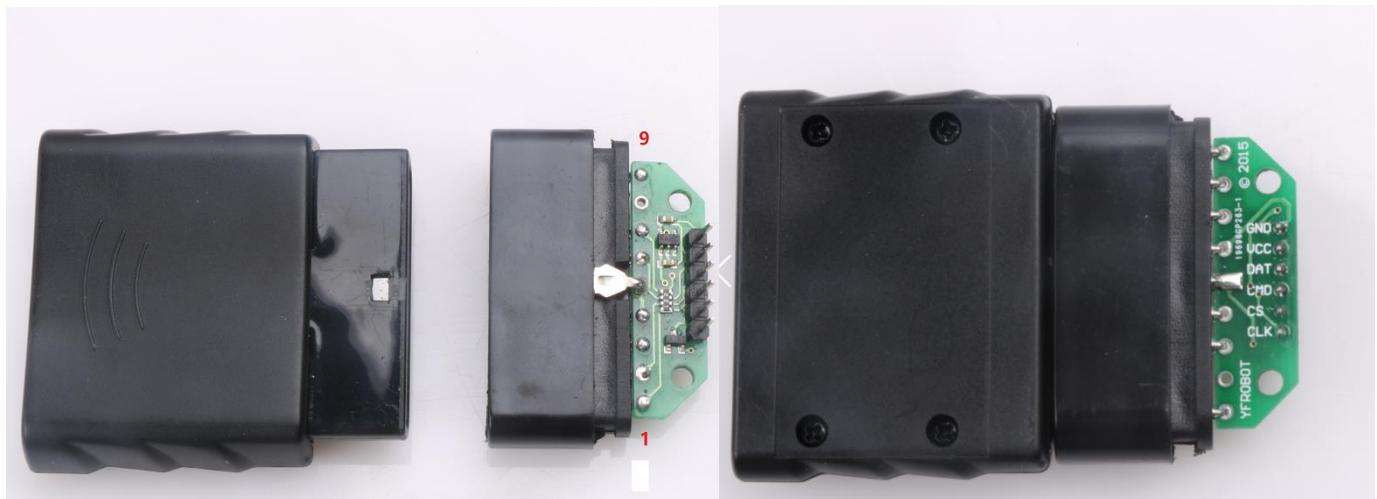


Figure .3.2.55 Remote Control Receiver Module

There are 9 interfaces at the end of the receiving head, each of which is shown in the following table:

1	2	3	4	5	6	7	8	9
DI/DAT	DO/CMD	NC	GND	VDD	CS/SEL	CLK	NC	ACK

Note: The appearance of the receiver will be different due to different batches, some with a power light, some without, but the use and definition of the pins are the same.

**DI/DAT:** The signal flows from the handle to the host. This signal is a serial 8-bit data which is transmitted synchronously to the falling edge of the clock. The read of the signal is completed in the process of clock changing from high to low;

**DO/CMD:** The signal flows from the host to the handle. The signal is similar to the DI, a serial 8-bit data, which is transmitted synchronously to the falling edge of the clock;

**NC:** Empty port; .

**GND:** Ground;

**VDD:** The 3~5V power supply;

**CS/SEL:** Providing trigger signals for handles, the level is low during communication;

**CLK:** The clock signal is sent by the host to maintain data synchronization;

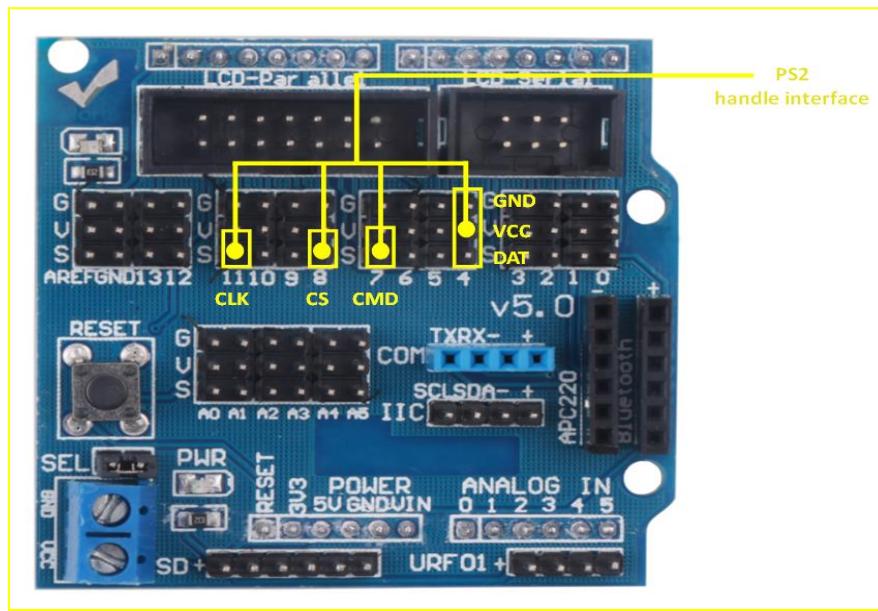
**NC:** Empty port;

ACK: The response signal from the handle to the host. This signal changes to low in the last cycle of each 8-bit data sending, and the CS remains low. If the CS signal do not remain low, the PS host will try another device in about 60 microseconds. The ACK port is not used in programming.

### 3.2.6.2 Experimental Procedure

1、 In order to wire simply, we use the PS2 receiver head adapter board and Arduino connection as follows:

As shown in the below figure, the six lines of the receiving head are connected to the following places respectively. “CLK” is connected to 11 pins, “CS” is connected to 8 pins, “CMD” is connected to pin 7, “DAT” is connected to 4 pins, and “VCC” is connected to 5V. , "GND" is grounded.



Ps2	Arduino Uno
DAT	4
CMD	7
CS	8
CLK	11

Fix the receiver head to the cart with a cable tie (red frame area in Figure 3.2.55), as shown in Figure 2.3.56.

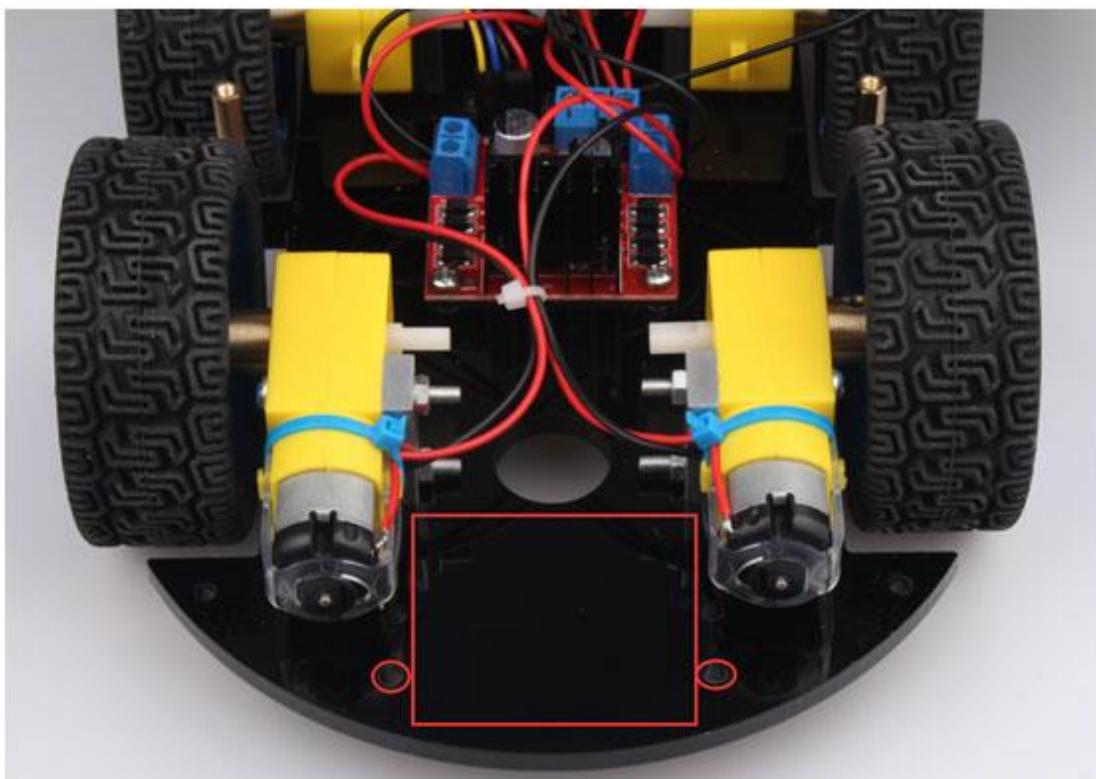


Figure 3.2.55 Receive Head Fixed Bit

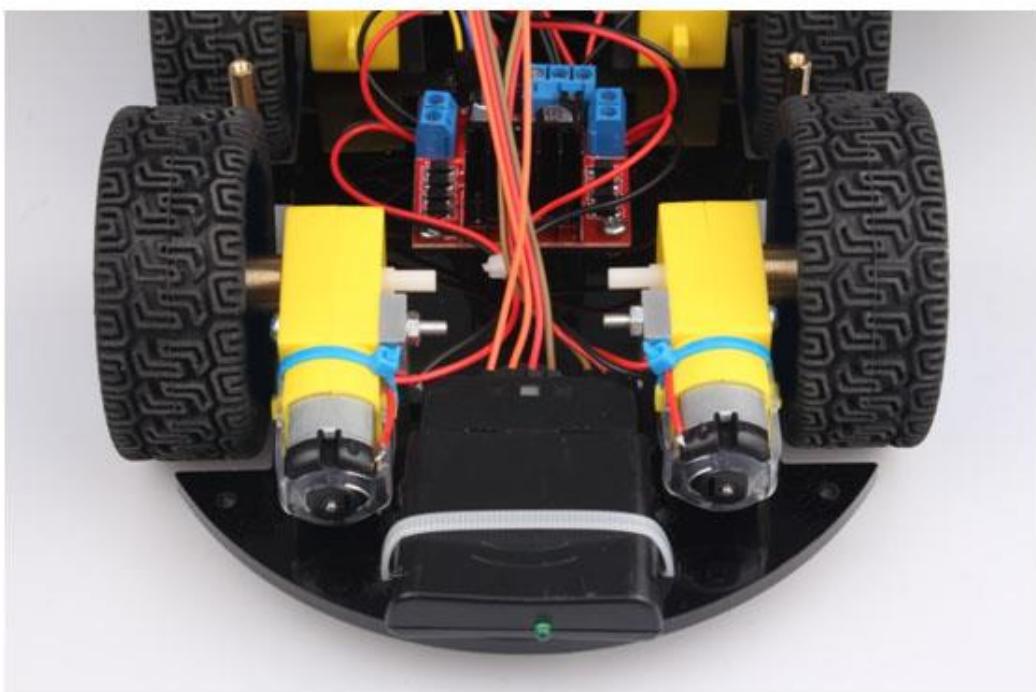


Figure 3.2.56 Receiving head fixing diagram

3、Lead the wire according to the hole marked “1” in Figure 3.2.57, and connect the wire to the Arduino expansion board with reference to Figure 2.3.58. After the completion, as shown as Figure 2.3.57.

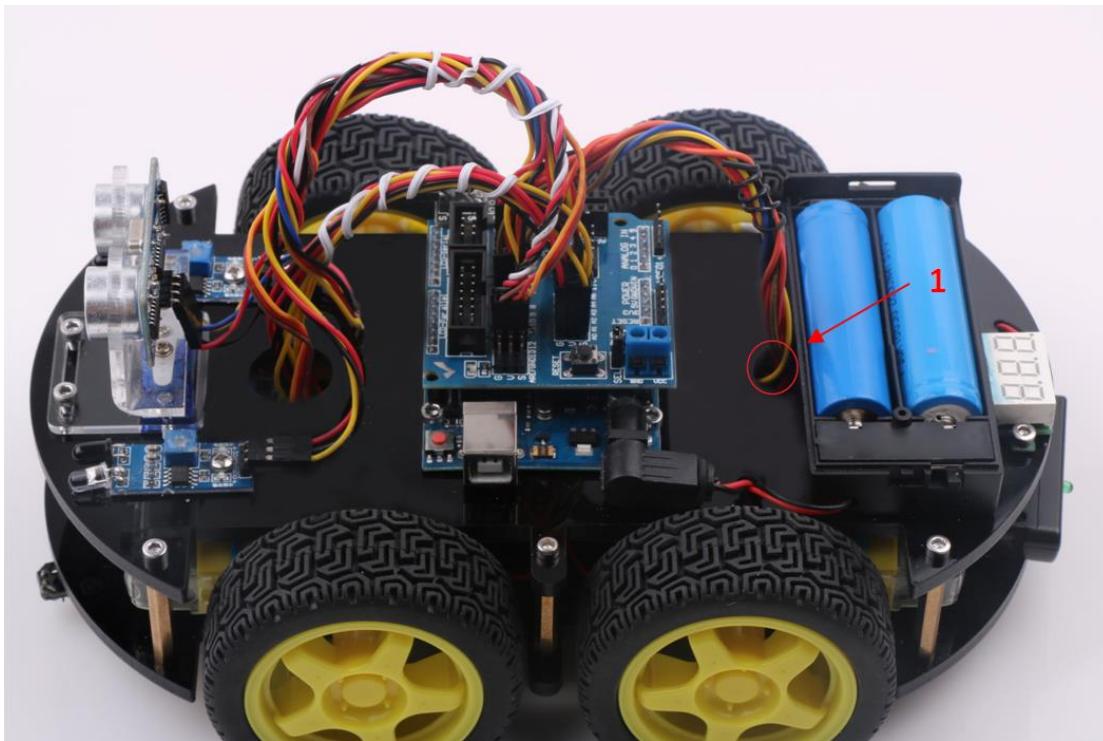


Figure 3.2.57 Wire Connection Diagram

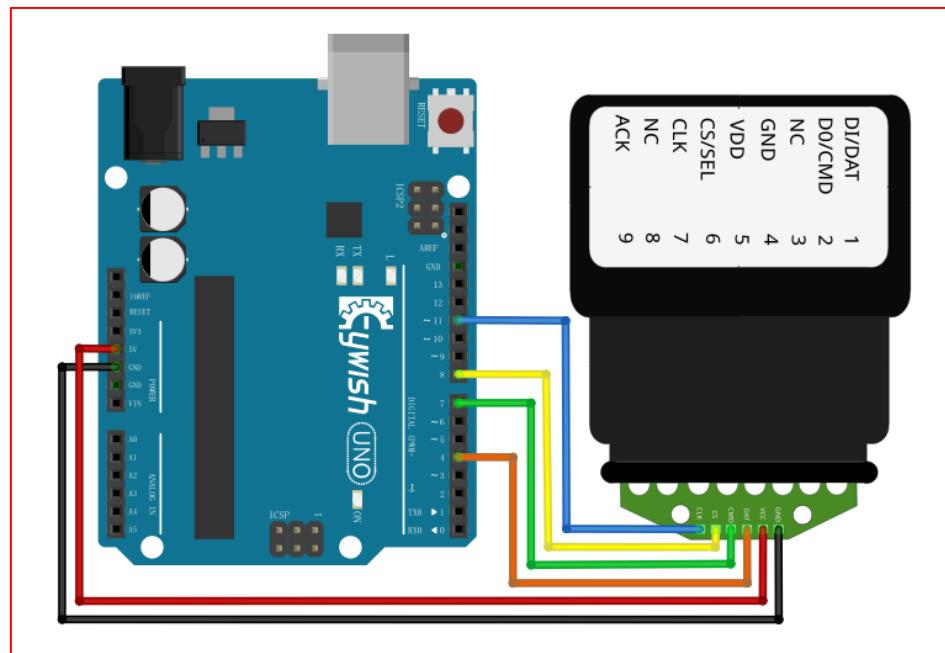
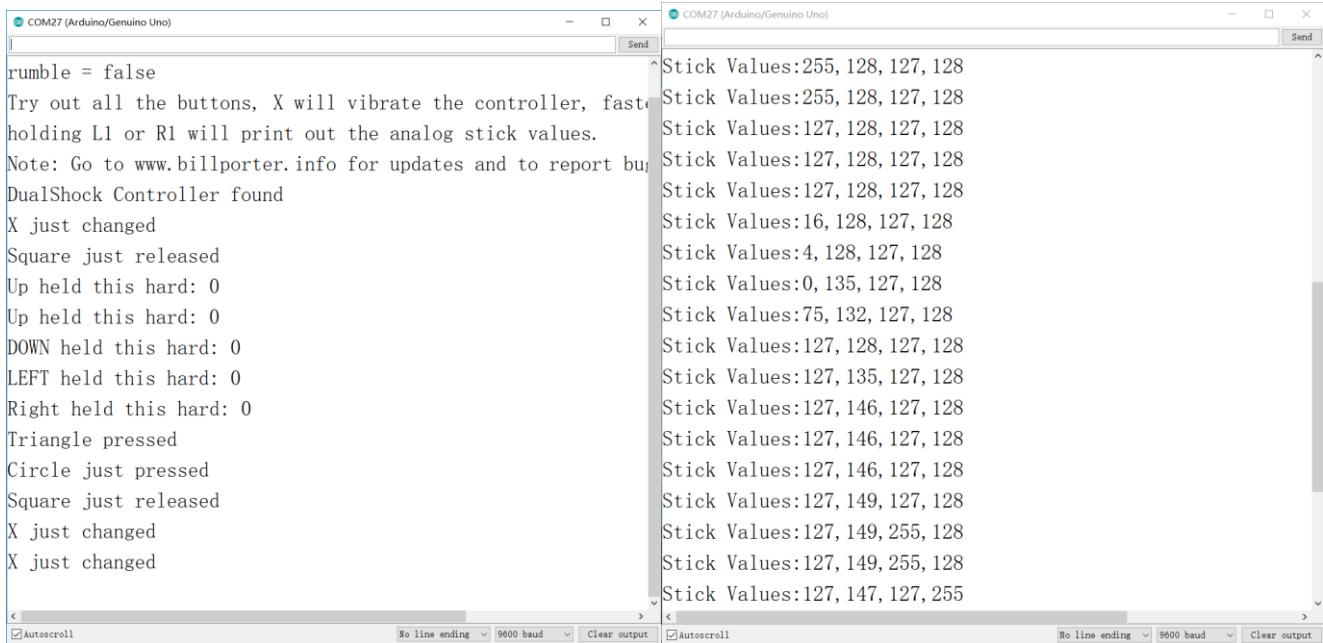


Figure 3.2.58 Connection of Arduino and Receiving Head Wires

4、Open “**Lesson\ModuleDemo\PS2X\PS2X.ino**”

Finally, download the program to the Arduino development board and turn on the PS2 remote control. If the receiver head is connected to the remote controller (or the pairing is successful), the indicator light on the receiver head is long, and the LED light is blinking. Finally, we open the "serial monitor", press any button

on the remote control, you can see the corresponding data on the "serial monitor", as shown in Figure 3.2.59.



```

COM27 (Arduino/Genuino Uno)           COM27 (Arduino/Genuino Uno)
rumble = false                         Stick Values:255, 128, 127, 128
Try out all the buttons, X will vibrate the controller, faster   Stick Values:255, 128, 127, 128
holding L1 or R1 will print out the analog stick values.          Stick Values:127, 128, 127, 128
Note: Go to www.billporter.info for updates and to report bu   Stick Values:127, 128, 127, 128
DualShock Controller found             Stick Values:127, 128, 127, 128
X just changed                      Stick Values:16, 128, 127, 128
Square just released                 Stick Values:4, 128, 127, 128
Up held this hard: 0                  Stick Values:0, 135, 127, 128
Up held this hard: 0                  Stick Values:75, 132, 127, 128
DOWN held this hard: 0                Stick Values:127, 128, 127, 128
LEFT held this hard: 0                Stick Values:127, 135, 127, 128
Right held this hard: 0               Stick Values:127, 146, 127, 128
Triangle pressed                     Stick Values:127, 146, 127, 128
Circle just pressed                  Stick Values:127, 146, 127, 128
Square just released                 Stick Values:127, 149, 127, 128
X just changed                       Stick Values:127, 149, 255, 128
X just changed                       Stick Values:127, 149, 255, 128
X just changed                       Stick Values:127, 147, 127, 255

```

The screenshot displays two side-by-side serial monitor windows. The left window shows the output of an Arduino sketch that handles button presses (X, Square, Up, Down, Left, Right, Triangle, Circle) and rumble settings. It also prints out raw analog stick values. The right window shows a continuous stream of raw analog stick value data. Both windows have identical configurations at the bottom: 'No line ending', '9600 baud', and 'Autoscroll' checked.

Figure 3.2.59 "serial monitor" data display

### 3.2.6.3 Software Design

```
#include "PS2X_lib.h" //for v1.6

/*
 * set pins connected to PS2 controller:
 * - 1e column: original
 * - 2e colmun: Stef?
 * replace pin numbers by the ones you use
 */

#define PS2_DAT      4
#define PS2_CMD      7
#define PS2_SEL      8
#define PS2_CLK      11

/*
 * select modes of PS2 controller:
 * - pressures = analog reading of push-buttons
 * - rumble    = motor rumbling
 * uncomment 1 of the lines for each mode selection
 */

//#define pressures  true
#define pressures  false
//#define rumble    true
#define rumble    false

PS2X ps2x; // create PS2 Controller Class

//right now, the library does NOT support hot pluggable controllers, meaning
//you must always either restart your Arduino after you connect the controller,
//or call config_gamepad(pins) again after connecting the controller.

int error = 0;
byte type = 0;
byte vibrate = 0;

// Reset func
void (* resetFunc) (void) = 0;
```

```
void setup() {
    Serial.begin(9600);
    delay(500); //added delay to give wireless ps2 module some time to startup, before
    configuring it
    //CHANGES for v1.6 HERE!!! *****PAY ATTENTION*****
    //setup pins and settings: GamePad(clock, command, attention, data, Pressures?, Rumble?) check for error
    error = ps2x.config_gamepad(PS2_CLK, PS2_CMD, PS2_SEL, PS2_DAT, pressures, rumble);

    if(error == 0){
        Serial.print("Found Controller, configured successful ");
        Serial.print("pressures = ");
        if (pressures)
            Serial.println("true ");
        else
            Serial.println("false");
        Serial.print("rumble = ");
        if (rumble)
            Serial.println("true");
        else
            Serial.println("false");
        Serial.println("Try out all the buttons, X will vibrate the controller, faster as
you press harder;");
        Serial.println("holding L1 or R1 will print out the analog stick values.");
        Serial.println("Note: Go to www.billporter.info for updates and to report bugs.");
    }
    else if(error == 1)
        Serial.println("No controller found, check wiring, see readme.txt to enable debug.
visit www.billporter.info for troubleshooting tips");

    else if(error == 2)
        Serial.println("Controller found but not accepting commands. see readme.txt to enable
debug. Visit www.billporter.info for troubleshooting tips");

    else if(error == 3)
        Serial.println("Controller refusing to enter Pressures mode, may not support it. ");

    type = ps2x.readType();
```

```
switch(type) {
    case 0:
        Serial.println("Unknown Controller type found ");
        break;
    case 1:
        Serial.println("DualShock Controller found ");
        break;
    case 2:
        Serial.println("GuitarHero Controller found ");
        break;
    case 3:
        Serial.println("Wireless Sony DualShock Controller found ");
        break;
}
}

void loop() {
/* You must Read Gamepad to get new values and set vibration values
   ps2x.read_gamepad(small motor on/off, larger motor strenght from 0-255)
   if you don't enable the rumble, use ps2x.read_gamepad(); with no values
   You should call this at least once a second
*/
    if(error == 1){ //skip loop if no controller found
        resetFunc();
    }
    if(type == 2){ //Guitar Hero Controller
        ps2x.read_gamepad();           //read controller

        if(ps2x.ButtonPressed(GREEN_FRET))
            Serial.println("Green Fret Pressed");
        if(ps2x.ButtonPressed(RED_FRET))
            Serial.println("Red Fret Pressed");
        if(ps2x.ButtonPressed(YELLOW_FRET))
            Serial.println("Yellow Fret Pressed");
        if(ps2x.ButtonPressed(BLUE_FRET))
            Serial.println("Blue Fret Pressed");
        if(ps2x.ButtonPressed(ORANGE_FRET))
            Serial.println("Orange Fret Pressed");
        if(ps2x.ButtonPressed(STAR_POWER))
            Serial.println("Star Power Command");
    }
}
```

```

if(ps2x.Button(UP_STRUM))           //will be TRUE as long as button is pressed
    Serial.println("Up Strum");
if(ps2x.Button(DOWN_STRUM))
    Serial.println("DOWN Strum");
if(ps2x.Button(PSB_START))          //will be TRUE as long as button is pressed
    Serial.println("Start is being held");
if(ps2x.Button(PSB_SELECT))
    Serial.println("Select is being held");
if(ps2x.Button(ORANGE_FRET)) {      // print stick value IF TRUE
    Serial.print("Wammy Bar Position:");
    Serial.println(ps2x.Analog(WHAMMY_BAR), DEC);
}
}

else { //DualShock Controller
    ps2x.read_gamepad(false, vibrate); //read controller and set large motor to spin at
'vibrate' speed
    if(ps2x.Button(PSB_START))          //will be TRUE as long as button is pressed
        Serial.println("Start is being held");
    if(ps2x.Button(PSB_SELECT))
        Serial.println("Select is being held");

    if(ps2x.Button(PSB_PAD_UP)) {        //will be TRUE as long as button is pressed
        Serial.print("Up held this hard: ");
        Serial.println(ps2x.Analog(PSAB_PAD_UP), DEC);
    }
    if(ps2x.Button(PSB_PAD_RIGHT)){
        Serial.print("Right held this hard: ");
        Serial.println(ps2x.Analog(PSAB_PAD_RIGHT), DEC);
    }
    if(ps2x.Button(PSB_PAD_LEFT)){
        Serial.print("LEFT held this hard: ");
        Serial.println(ps2x.Analog(PSAB_PAD_LEFT), DEC);
    }
    if(ps2x.Button(PSB_PAD_DOWN)){
        Serial.print("DOWN held this hard: ");
        Serial.println(ps2x.Analog(PSAB_PAD_DOWN), DEC);
    }
}

```

```

vibrate = ps2x.Analog(PSAB_CROSS); //this will set the large motor vibrate speed
based on how hard you press the blue (X) button

if (ps2x.NewButtonState()) {           //will be TRUE if any button changes state (on to
off, or off to on)
    if(ps2x.Button(PSB_L3))
        Serial.println("L3 pressed");
    if(ps2x.Button(PSB_R3))
        Serial.println("R3 pressed");
    if(ps2x.Button(PSB_L2))
        Serial.println("L2 pressed");
    if(ps2x.Button(PSB_R2))
        Serial.println("R2 pressed");
    if(ps2x.Button(PSB_TRIANGLE))
        Serial.println("Triangle pressed");
}

if(ps2x.ButtonPressed(PSB_CIRCLE))           //will be TRUE if button was JUST
pressed
    Serial.println("Circle just pressed");
if(ps2x.NewButtonState(PSB_CROSS))           //will be TRUE if button was JUST
pressed OR released
    Serial.println("X just changed");
if(ps2x.ButtonReleased(PSB_SQUARE))           //will be TRUE if button was JUST
released
    Serial.println("Square just released");

if(ps2x.Button(PSB_L1) || ps2x.Button(PSB_R1)) { //print stick values if either is
TRUE
    Serial.print("Stick Values:");
    Serial.print(ps2x.Analog(PSS_LY), DEC); //Left stick, Y axis. Other options: LX,
RY, RX
    Serial.print(",");
    Serial.print(ps2x.Analog(PSS_LX), DEC);
    Serial.print(",");
    Serial.print(ps2x.Analog(PSS_RY), DEC);
    Serial.print(",");
    Serial.println(ps2x.Analog(PSS_RX), DEC);
}
delay(50);
}

```

In the above program, we instructed to read the test button. In this experiment we want to implement the PS2 remote control car function. We firstly define all the button functions as follows:



Figure .3.2.60 Functions of PS2 Handle Buttons

Mark UP: move forward

Mark DOWN: move backward

Mark LEFT: turn left

Mark RIGHT: right

Mark A: speed up

Mark B: servo turns left

Mark C: slow down

Mark D: servo turns right

Mark 3: Right joystick (mark 5) control key, only when you press R1, the Right joystick will work.

Mark 4: Left joystick (mark 6) control key, only when you press L1, the Left joystick will work.

Joystick left: joystick remotes control direction

Joystick Right: joystick remotes control speed

**Ps2 Control program in “hummer-bot\Lesson\Comprehensive Experiment\Hummerbot\_PS2\Hummerbot\_PS2\ Hummerbot\_PS2.ino”**

The program flow chart is as follows:

