

ChipChipArray

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Chapter 1

Namespace Index

1.1 Namespace List

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Chapter 2

Class Index

2.1 Class List

Here are the classes, structs, unions and interfaces with brief descriptions:

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ChipChipArray::Grabber	33
ChipChipArray::Log	45
ChipChipArray::PiCamera	51

Chapter 3

File Index

3.1 File List

Here is a list of all files with brief descriptions:

makefile	Project makefile containing recipes for compiling the actual application, test applications, and generating documentation	56
etc/doxygen.config	Doxygen configuration file	55
src/Adafruit_PWMServoDriver.cpp	Contains the function and class definitions necessary for the PWM servo driver	57
src/Adafruit_PWMServoDriver.h	60
src/Arm.hpp	Contains the Arm class used to control the robotic arm	64
src/Block.hpp	Contains Block class	67
src/cv_hue.cpp	Contains program formally used to find HSV values for blocks	70
src/cv_shape.cpp	Contains a program to aid in determining HSV ranges	72
src/cv_test.cpp	Contains program used to test PiCamera class	76
src/dark_magic.cpp	Contains test code for arm	77
src/definitions.hpp	Contains definitions for architecture-independant numeric variables, enumerations and enumerated classes, and #define'd constants, and to_sting() overloads for the enumerated classes . .	79
src/Grabber.hpp	Contains the Grabber class	87
src/img.cpp	Contains a program to display the current camera image	93
src/jacob_alg_test.cpp	Contains a program that tests Jacob's yellow-detection algorithm	94
src/loading_test.cpp	Contains a program to test Grabber class	96
src/Log.hpp	Contains Log class	98
src/log_test.cpp	Contains a program to test partially the Log class	101
src/main.cpp	Contains the main() function to the whole project	103

src/ NavigationControl.cpp	Contains the navigation control function definitions	113
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Chapter 4

Namespace Documentation

4.1 ChipChipArray Namespace Reference

Classes

- class [Arm](#)
- class [Block](#)
- class [Grabber](#)
- class [Log](#)
- class [PiCamera](#)

Functions

- int [main](#) (int argc, char **argv)
- [Color ScanQR](#) ()

Variables

- [uint8 qrInvokeCount](#) = 0
- [Log scanQrLog](#) ("logs/ScanQR", LogMode::Multi)

4.1.1 Function Documentation

4.1.1.1 int ChipChipArray::main (int argc, char ** argv)

This program was used before [cv_shape.cpp](#) was written to find HSV ranges for the different color blocks. This is a slightly modified version of some code written by Shermal Fernando in the blog post "Color Detection & Object Tracking" at <http://opencv-srf.blogspot.com/2010/09/object-detection-using-color-seperation.html>.

Definition at line 27 of file [cv_hue.cpp](#).

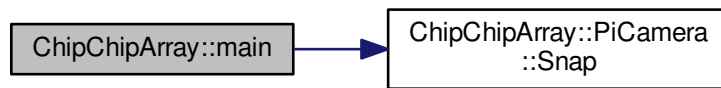
```
00027                                     {
00028     PiCamera cam;
00029     namedWindow("Control", CV_WINDOW_AUTOSIZE); //create a window called "Control"
00030
00031     int iLowH = 170;
00032     int iHighH = 179;
00033
00034     int iLowS = 150;
00035     int iHighS = 255;
00036
00037     int iLowV = 60;
```

```

00038         int iHighV = 255;
00039
00040         //Create trackbars in "Control" window
00041         createTrackbar("LowH", "Control", &iLowH, 179); //Hue (0 - 179)
00042         createTrackbar("HighH", "Control", &iHighH, 179);
00043
00044         createTrackbar("LowS", "Control", &iLowS, 255); //Saturation (0 - 255)
00045         createTrackbar("HighS", "Control", &iHighS, 255);
00046
00047         createTrackbar("LowV", "Control", &iLowV, 255); //Value (0 - 255)
00048         createTrackbar("HighV", "Control", &iHighV, 255);
00049
00050         int iLastX = -1;
00051         int iLastY = -1;
00052
00053         //Capture a temporary image from the camera
00054         Mat imgTmp = cam.Snap();
00055
00056         //Create a black image with the size as the camera output
00057         Mat imgLines = Mat::zeros( imgTmp.size(), CV_8UC3 );
00058
00059
00060         while (true)
00061         {
00062             Mat imgOriginal = cam.Snap(); // read a new frame from video
00063             Mat imgHSV;
00064
00065             cvtColor(imgOriginal, imgHSV, COLOR_BGR2HSV); //Convert the captured frame from BGR to HSV
00066
00067             Mat imgThresholded;
00068
00069             inRange(imgHSV, Scalar(iLowH, iLowS, iLowV), Scalar(iHighH, iHighS, iHighV), imgThresholded);
00070             //Threshold the image
00071
00072             //morphological opening (removes small objects from the foreground)
00073             erode(imgThresholded, imgThresholded, getStructuringElement(MORPH_ELLIPSE,
00074             Size(5, 5) ));
00075             dilate( imgThresholded, imgThresholded, getStructuringElement(MORPH_ELLIPSE,
00076             Size(5, 5) ));
00077
00078             //morphological closing (removes small holes from the foreground)
00079             dilate( imgThresholded, imgThresholded, getStructuringElement(MORPH_ELLIPSE,
00080             Size(5, 5) ));
00081             erode(imgThresholded, imgThresholded, getStructuringElement(MORPH_ELLIPSE,
00082             Size(5, 5) ));
00083
00084             //Calculate the moments of the thresholded image
00085             Moments oMoments = moments(imgThresholded);
00086
00087             /*double dM01 = oMoments.m01;
00088             double dM10 = oMoments.m10;
00089             double dArea = oMoments.m00;
00090
00091             // if the area <= 10000, I consider that the there are no object in the image and it's because
00092             of the noise, the area is not zero
00093             if (dArea > 50000)
00094             {
00095                 //calculate the position of the ball
00096                 int posX = dM10 / dArea;
00097                 int posY = dM01 / dArea;
00098
00099                 if (iLastX >= 0 && iLastY >= 0 && posX >= 0 && posY >= 0)
00100                 {
00101                     //Draw a red line from the previous point to the current point
00102                     line(imgLines, Point(posX, posY), Point(iLastX, iLastY), Scalar(0,0,255), 2);
00103                 }
00104
00105                 iLastX = posX;
00106                 iLastY = posY;
00107             }
00108             */
00109             imshow("Thresholded Image", imgThresholded); //show the thresholded image
00110
00111             //
00112             imgOriginal = imgOriginal + imgLines;
00113             imshow("Original", imgOriginal); //show the original image
00114
00115             if (waitKey(30) == 27) //wait for 'esc' key press for 30ms. If 'esc' key is pressed, break loop
00116             {
00117                 cout << "esc key is pressed by user" << endl;
00118                 break;
00119             }
00120         }
00121
00122         return 0;
00123     }

```

Here is the call graph for this function:



4.1.1.2 Color ChipChipArray::ScanQR ()

This function maneuvers arm to look at the QR code on a train car as the robot is backing up to the car. It attempts to find the code in multiple images before finally throwing an exception if a code is not found. If multiple codes are found, it returns a single Color by (seemingly) arbitrary decision.

This function is based on code written by Michael Young (<https://github.com/ayoungprogrammer/↵WebcamCodeScanner>).

Definition at line 41 of file [ScanQR.hpp](#).

```

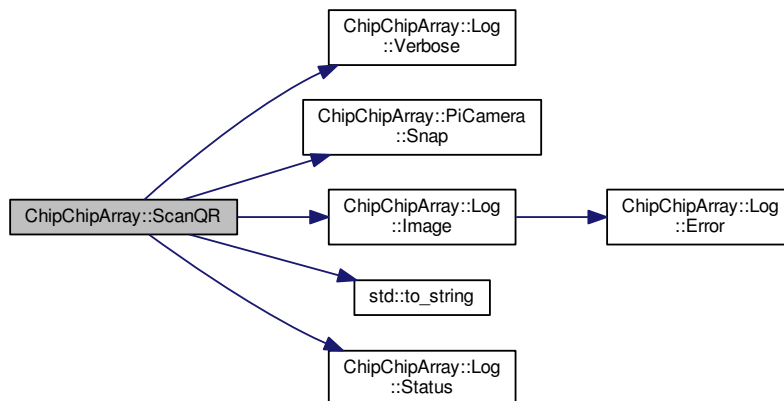
00041         {
00042             // 0. Initialize variables
00043             Color color;
00044             PiCamera cam(false);
00045
00046             // 1. Position arm
00047             scanQrLog.Verbose("Positioning arm");
00048
00049             // 2. Scan images from camera
00050             scanQrLog.Verbose("Scanning for QR code");
00051
00052             // Nick's supposed to make sure this isn't an endless loop
00053             while(true) {
00054                 // get image
00055                 cv::Mat frame = cam.Snap();
00056                 cv::Mat canvas;
00057                 cv::cvtColor(frame, canvas, CV_BGR2GRAY);
00058                 scanQrLog.Image(canvas, std::to_string(++
qrInvokeCount)
00059                             + ".bmp");
00060
00061                 uint32 width = canvas.cols;
00062                 uint32 height = canvas.rows;
00063                 zbar::Image image(width, height, "Y800",
                                (uchar*)canvas.data, width * height);
00064
00065                 zbar::ImageScanner scanner;
00066                 scanner.set_config(zbar::ZBAR_NONE, zbar::ZBAR_CFG_ENABLE, 1);
00067                 scanner.scan(image);
00068                 zbar::Image::SymbolIterator symbol = image.symbol_begin();
00069
00070                 if(symbol != image.symbol_end()) {
00071                     switch(symbol->get_data()[0]) {
00072                         case 'r':
00073                             color = Color::Red;
00074                             break;
00075
00076                         case 'y':
00077                             color = Color::Yellow;
00078                             break;
00079
00080                         case 'g':
00081                             color = Color::Green;
00082                             break;
00083
00084                         case 'b':
00085                             color = Color::Blue;
00086                             break;
00087                     }
00088                 }
00089             }
  
```

```

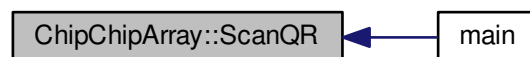
00090         scanQrLog.Status("Detected " + std::to_string(color)
00091             + " train car");
00092         break;
00093     }
00094 }
00095
00096 // 3. Retract arm
00097 scanQrLog.Verbose("Retracting arm");
00098 return color;
00099 }

```

Here is the call graph for this function:



Here is the caller graph for this function:



4.1.2 Variable Documentation

4.1.2.1 uint8 ChipChipArray::qrInvokeCount = 0

The number of times `ScanQR()` has been called. Used for ScanQR log.

Definition at line 24 of file [ScanQR.hpp](#).

4.1.2.2 Log ChipChipArray::scanQrLog("logs/ScanQR", LogMode::Multi)

The `Log` instance used by the `ScanQR()` function.

4.2 std Namespace Reference

Functions

- string `to_string` (`BlockPosition` pos)
- string `to_string` (`Color` color)
- string `to_string` (`LogMode` mode)
- string `to_string` (`Result` res)
- string `to_string` (`Side` side)
- string `to_string` (`Size` size)
- string `to_string` (`Zone` zone)

4.2.1 Function Documentation

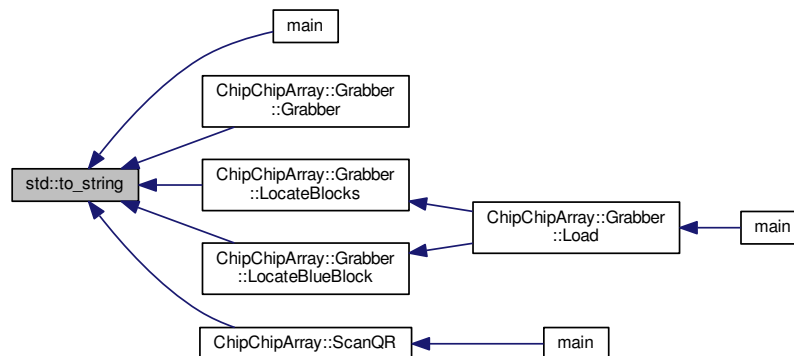
4.2.1.1 string `std::to_string` (`BlockPosition` pos)

Converts a `BlockPosition` to a string.

Definition at line 107 of file [definitions.hpp](#).

```
00107         {
00108             if (pos == BlockPosition::Front) return string("Front");
00109             else return string("Back");
00110         }
```

Here is the caller graph for this function:



4.2.1.2 string `std::to_string` (`Color` color)

Converts a `Color` to a string.

Definition at line 115 of file [definitions.hpp](#).

```
00115         {
00116             string ret;
00117             switch((ENUM)color) {
00118                 case 0:
00119                     ret = "Red";
00120                     break;
00121                 case 1:
00122                     ret = "Yellow";
00123                     break;
00124                 case 2:
00125                     ret = "Blue";
00126                     break;
00127             }
```

```

00128         ret = "Green";
00129         break;
00130
00131     case 3:
00132         ret = "Blue";
00133         break;
00134
00135     case 4:
00136         ret = "All";
00137         break;
00138     }
00139
00140     return ret;
00141 }

```

4.2.1.3 string std::to_string (LogMode mode)

Converts a LogMode to a string.

Definition at line 146 of file [definitions.hpp](#).

```

00146     {
00147         if(mode == LogMode::Multi) return string("Text");
00148         else return string("Multi");
00149     }

```

4.2.1.4 string std::to_string (Result res)

Converts a Result to a string.

Definition at line 154 of file [definitions.hpp](#).

```

00154     {
00155         string ret;
00156
00157         switch((ENUM)res) {
00158             case -1:
00159                 ret = "No Blocks";
00160                 break;
00161
00162             case 0:
00163                 ret = "Two whole, no halves";
00164                 break;
00165
00166             case 2:
00167                 ret = "Two whole, two halves";
00168                 break;
00169
00170             case 4:
00171                 ret = "No whole, four halves";
00172                 break;
00173         }
00174
00175         return ret;
00176     }

```

4.2.1.5 string std::to_string (Side side)

Converts a Side to a string.

Definition at line 181 of file [definitions.hpp](#).

```

00181     {
00182         if(side == Side::Left) return string("Left");
00183         else return string("Right");
00184     }

```


4.2.1.6 string std::to_string (Size size)

Converts a Size to a string.

Definition at line 189 of file [definitions.hpp](#).

```
00189             {  
00190         if(size == Size::Long) return string("Long");  
00191         else return string("Short");  
00192     }
```

4.2.1.7 string std::to_string (Zone zone)

Converts a Zone to a string.

Definition at line 197 of file [definitions.hpp](#).

```
00197             {  
00198         return string(1, (char)zone);  
00199     }
```


Chapter 5

Class Documentation

5.1 Adafruit_PWMServoDriver Class Reference

```
#include <Adafruit_PWMServoDriver.h>
```

Public Member Functions

- [Adafruit_PWMServoDriver](#) ([uint8_t](#) addr=0x41)
- void [begin](#) (void)
- void [reset](#) (void)
- void [setPWMFreq](#) (float freq)
- void [setPWM](#) ([uint8_t](#) num, [uint16_t](#) on, [uint16_t](#) off)
- void [setPin](#) ([uint8_t](#) num, [uint16_t](#) val, bool invert=false)

5.1.1 Detailed Description

Definition at line 73 of file [Adafruit_PWMServoDriver.h](#).

5.1.2 Constructor & Destructor Documentation

5.1.2.1 Adafruit_PWMServoDriver::Adafruit_PWMServoDriver ([uint8_t](#) *addr* = 0x41)

Definition at line 37 of file [Adafruit_PWMServoDriver.cpp](#).

```
00037                                     {
00038     _i2caddr = addr;
00039     _i2cFD = -1;
00040 }
```

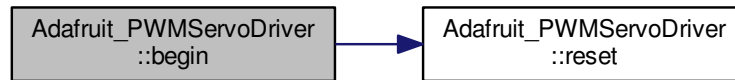
5.1.3 Member Function Documentation

5.1.3.1 void Adafruit_PWMServoDriver::begin (void)

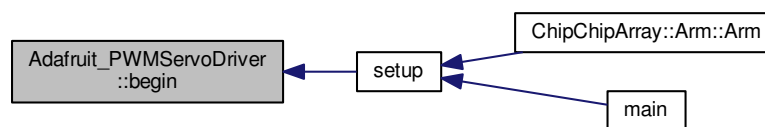
Definition at line 42 of file [Adafruit_PWMServoDriver.cpp](#).

```
00042                                     {
00043     _i2cFD = wiringPiI2CSetup(_i2caddr);
00044     if (_i2cFD < 0) {
00045         //FIXME: error occurred
00046     }
00047     reset();
00048 }
```

Here is the call graph for this function:



Here is the caller graph for this function:



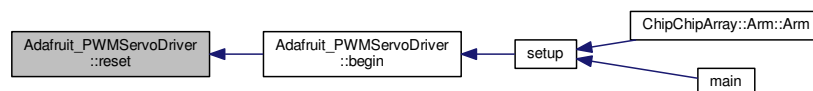
5.1.3.2 void Adafruit_PWMServoDriver::reset (void)

Definition at line 50 of file [Adafruit_PWMServoDriver.cpp](#).

```

00050                                     {
00051     write8(PCA9685_MODE1, 0x0);
00052 }
  
```

Here is the caller graph for this function:



5.1.3.3 void Adafruit_PWMServoDriver::setPin (uint8_t num, uint16_t val, bool invert = false)

Definition at line 116 of file [Adafruit_PWMServoDriver.cpp](#).

```

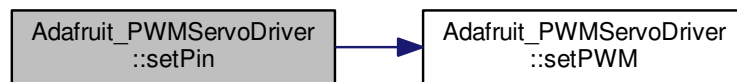
00116                                     {
00117     // Clamp value between 0 and 4095 inclusive.
00118     val = min(val, (uint16_t)4095);
00119     if (invert) {
00120         if (val == 0) {
00121             // Special value for signal fully on.
00122             setPWM(num, 4096, 0);
00123         } else if (val == 4095) {
00124             // Special value for signal fully off.
00125             setPWM(num, 0, 4096);
00126         }
00127     }
00128 }
  
```

```

00126         } else {
00127             setPWM(num, 0, 4095 - val);
00128         }
00129     } else {
00130         if (val == 4095) {
00131             // Special value for signal fully on.
00132             setPWM(num, 4096, 0);
00133         } else if (val == 0) {
00134             // Special value for signal fully off.
00135             setPWM(num, 0, 4096);
00136         } else {
00137             setPWM(num, 0, val);
00138         }
00139     }
00140 }

```

Here is the call graph for this function:



5.1.3.4 void Adafruit_PWMServoDriver::setPWM (uint8_t num, uint16_t on, uint16_t off)

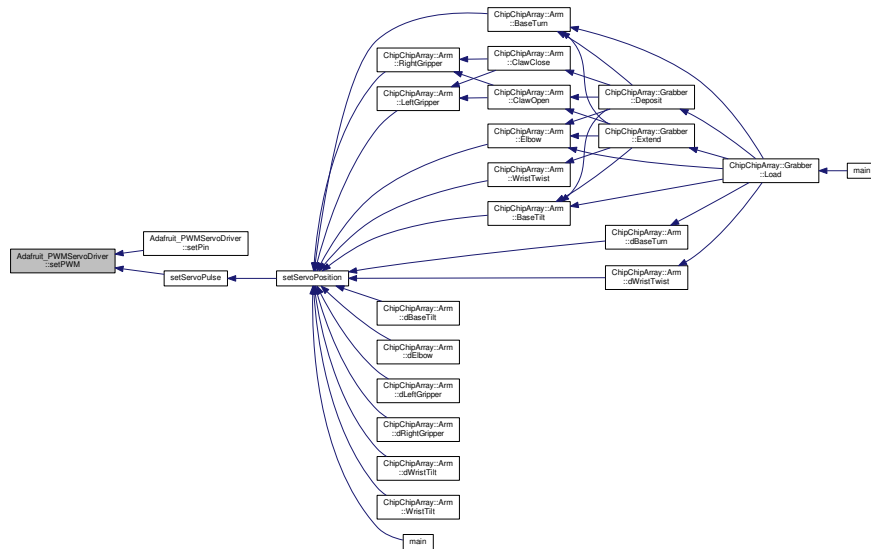
Definition at line 81 of file [Adafruit_PWMServoDriver.cpp](#).

```

00081                                     {
00082         //Serial.print("Setting PWM "); Serial.print(num); Serial.print(": "); Serial.print(on);
00083         Serial.print("->"); Serial.println(off);
00084         int result = wiringPiI2CWriteReg16(_i2cFD, LED0_ON_L + 4 * num, on);
00085         if (result < 0) {
00086             string s(strerror(errno));
00087             cout << "setPWM error: " << s.c_str() << endl;
00088         }
00089         result = wiringPiI2CWrite(_i2cFD, on);
00090         if (result < 0) {
00091             string s(strerror(errno));
00092             cout << "setPWM error: " << s.c_str() << endl;
00093         }
00094         result = wiringPiI2CWrite(_i2cFD, on >> 8);
00095         if (result < 0) {
00096             string s(strerror(errno));
00097             cout << "setPWM error: " << s.c_str() << endl;
00098         }
00099         result = wiringPiI2CWriteReg16(_i2cFD, LED0_OFF_L + 4 * num, off);
00100         result = wiringPiI2CWrite(_i2cFD, off);
00101         if (result < 0) {
00102             string s(strerror(errno));
00103             cout << "setPWM error: " << s.c_str() << endl;
00104         }
00105         result = wiringPiI2CWrite(_i2cFD, off >> 8);
00106         if (result < 0) {
00107             string s(strerror(errno));
00108             cout << "setPWM error: " << s.c_str() << endl;
00109         }
00110     }

```

Here is the caller graph for this function:



5.1.3.5 void Adafruit_PWMServoDriver::setPWMFreq (float freq)

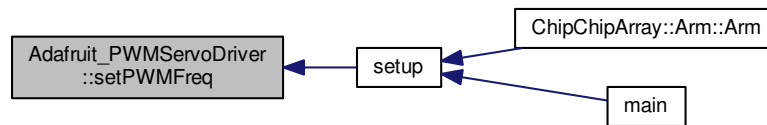
Definition at line 54 of file [Adafruit_PWMServoDriver.cpp](#).

```

00054                                     {
00055     //Serial.print("Attempting to set freq ");
00056     //Serial.println(freq);
00057     freq *= 0.9; // Correct for overshoot in the frequency setting (see issue #11).
00058     float prescaleval = 25000000;
00059     prescaleval /= 4096;
00060     prescaleval /= freq;
00061     prescaleval -= 1;
00062     if (ENABLE_DEBUG_OUTPUT) {
00063         cout << "Estimated pre-scale: " << prescaleval << endl;
00064     }
00065     uint8_t prescale = floor(prescaleval + 0.5);
00066     if (ENABLE_DEBUG_OUTPUT) {
00067         cout << "Final pre-scale: " << prescale << endl;
00068     }
00069
00070     uint8_t oldmode = read8(PCA9685_MODE1);
00071     uint8_t newmode = (oldmode & 0x7F) | 0x10; // sleep
00072     write8(PCA9685_MODE1, newmode); // go to sleep
00073     write8(PCA9685_PRESCALE, prescale); // set the prescaler
00074     write8(PCA9685_MODE1, oldmode);
00075     usleep(5000);
00076     write8(PCA9685_MODE1, oldmode | 0x01); // This sets the MODE1 register to turn on auto
00077     increment.
00078     // This is why the beginTransmission below was not working.
00079     // Serial.print("Mode now 0x"); Serial.println(read8(PCA9685_MODE1), HEX);
00079 }

```

Here is the caller graph for this function:



The documentation for this class was generated from the following files:

- [src/Adafruit_PWMServoDriver.h](#)
- [src/Adafruit_PWMServoDriver.cpp](#)

5.2 ChipChipArray::Arm Class Reference

```
#include <Arm.hpp>
```

Public Member Functions

- [Arm](#) ()
- void [BaseTilt](#) (uint8 a)
- void [BaseTurn](#) (uint8 a)
- void [ClawOpen](#) ()
- void [ClawClose](#) ()
- void [dBaseTilt](#) (sint16 a)
- void [dBaseTurn](#) (sint16 a)
- void [dElbow](#) (sint16 a)
- void [dWristTilt](#) (sint16 a)
- void [dWristTwist](#) (sint16 a)
- void [Elbow](#) (uint8 a)
- void [Hover](#) (Zone zone)
- void [WristTilt](#) (uint8 a)
- void [WristTwist](#) (uint8 a)

Public Attributes

- [uint8 servoPos](#) [7] = { 0, 0, 0, 0, 0, 0, 0 }

Protected Member Functions

- void [dLeftGripper](#) (sint16 a)
- void [dRightGripper](#) (sint16 a)
- void [LeftGripper](#) (uint8 a)
- void [RightGripper](#) (uint8 a)

5.2.1 Detailed Description

This class provides a layer of abstraction from the existing servo interface. It is designed to make more sense programmatically and to be easier to use.

Definition at line 23 of file [Arm.hpp](#).

5.2.2 Constructor & Destructor Documentation

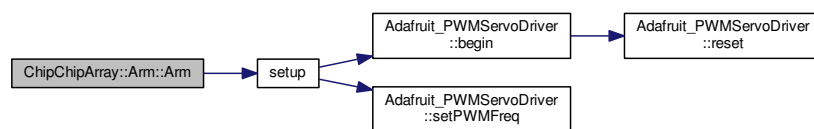
5.2.2.1 ChipChipArray::Arm::Arm ()

Initializes the I2C interface for the arm if another instance of the [Arm](#) class has not already.

Definition at line 173 of file [Arm.hpp](#).

```
00173     {
00174         if(!init) {
00175             setup();
00176             init = true;
00177         }
00178     }
```

Here is the call graph for this function:



5.2.3 Member Function Documentation

5.2.3.1 void ChipChipArray::Arm::BaseTilt (uint8 a)

Tilts the base of the arm.

Parameters

a	desired servo position in degrees
----------	-----------------------------------

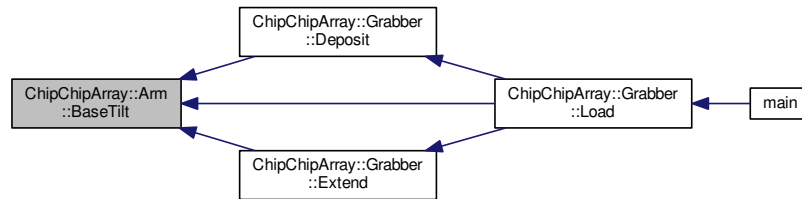
Definition at line 180 of file [Arm.hpp](#).

```
00180     {
00181         setServoPosition(BASE_TILT, a);
00182         servoPos[BASE_TILT] = a;
00183     }
```

Here is the call graph for this function:



Here is the caller graph for this function:



5.2.3.2 void ChipChipArray::Arm::BaseTurn (uint8 a)

Twists the entire arm.

Parameters

a	desired servo position in degrees
----------	-----------------------------------

Definition at line 185 of file [Arm.hpp](#).

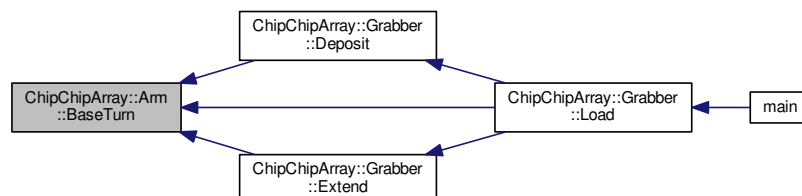
```

00185         {
00186             setServoPosition(BASE_TURN, a);
00187             servoPos[BASE_TURN] = a;
00188         }
  
```

Here is the call graph for this function:



Here is the caller graph for this function:



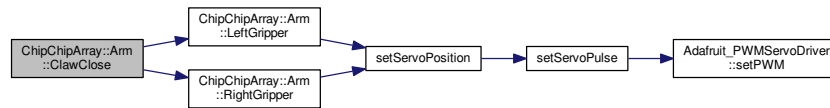
5.2.3.3 void ChipChipArray::Arm::ClawClose ()

Closes the claw enough to hold a block in place during movement but does not attempt to completely close the claw in order to prevent unnecessary strain on the servos.

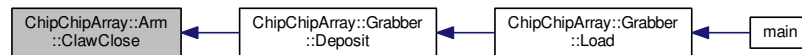
Definition at line 195 of file [Arm.hpp](#).

```
00195         {
00196     LeftGripper(180);
00197     RightGripper(0);
00198 }
```

Here is the call graph for this function:



Here is the caller graph for this function:



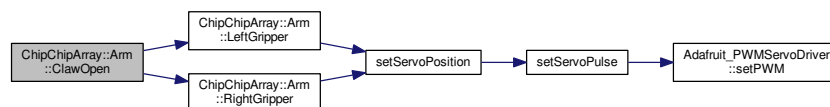
5.2.3.4 void ChipChipArray::Arm::ClawOpen ()

Opens the claw completely (within safe limits).

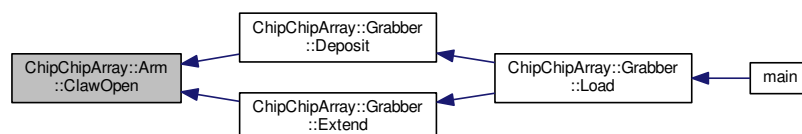
Definition at line 190 of file [Arm.hpp](#).

```
00190         {
00191     LeftGripper(0);
00192     RightGripper(180);
00193 }
```

Here is the call graph for this function:



Here is the caller graph for this function:



5.2.3.5 void ChipChipArray::Arm::dBaseTilt (sint16 a)

Tilts the base a certain number of degrees.

Parameters

<i>degrees</i>	to move servo. Positive values add to the servo angle, and negative values subtract from the servo angle.
----------------	---

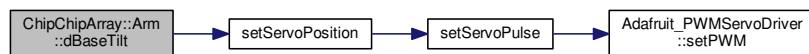
Definition at line 200 of file [Arm.hpp](#).

```

00200             {
00201     a += servoPos[BASE_TILT];
00202     setServoPosition(BASE_TILT, a);
00203     servoPos[BASE_TILT] = a;
00204 }

```

Here is the call graph for this function:



5.2.3.6 void ChipChipArray::Arm::dBaseTurn (sint16 a)

Turn the base a certain number of degrees.

Parameters

<i>degrees</i>	to move servo. Positive values add to the servo angle, and negative values subtract from the servo angle.
----------------	---

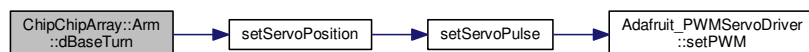
Definition at line 206 of file [Arm.hpp](#).

```

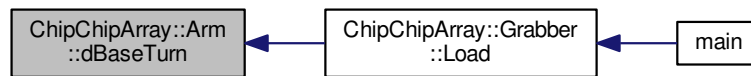
00206             {
00207     a += servoPos[BASE_TURN];
00208     setServoPosition(BASE_TURN, a);
00209     servoPos[BASE_TURN] = a;
00210 }

```

Here is the call graph for this function:



Here is the caller graph for this function:



5.2.3.7 void ChipChipArray::Arm::dElbow (sint16 a)

Bend the elbow a certain number of degrees.

Parameters

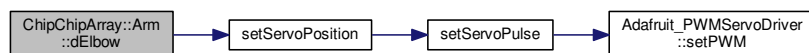
<i>degrees</i>	to move servo. Positive values add to the servo angle, and negative values subtract from the servo angle.
----------------	---

Definition at line 212 of file [Arm.hpp](#).

```

00212         {
00213     a += servoPos[ELBOW];
00214     setServoPosition(ELBOW, a);
00215     servoPos[ELBOW] = a;
00216 }
  
```

Here is the call graph for this function:



5.2.3.8 void ChipChipArray::Arm::dLeftGripper (sint16 a) [protected]

Moves the left gripper servo a certain number of degrees.

Parameters

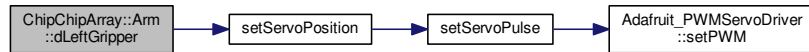
<i>degrees</i>	to move servo. Positive values add to the servo angle, and negative values subtract from the servo angle.
----------------	---

Definition at line 218 of file [Arm.hpp](#).

```

00218         {
00219     a += servoPos[GRIP_LEFT];
00220     setServoPosition(GRIP_LEFT, a);
00221     servoPos[GRIP_LEFT] = a;
00222 }
  
```

Here is the call graph for this function:



5.2.3.9 void ChipChipArray::Arm::dRightGripper (sint16 a) [protected]

Moves the right gripper servo a certain number of degrees.

Parameters

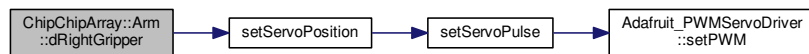
<i>degrees</i>	to move servo. Positive values add to the servo angle, and negative values subtract from the servo angle.
----------------	---

Definition at line 224 of file [Arm.hpp](#).

```

00224     {
00225         a += servoPos[GRIP_RIGHT];
00226         setServoPosition(GRIP_RIGHT, a);
00227         servoPos[GRIP_RIGHT] = a;
00228     }
  
```

Here is the call graph for this function:



5.2.3.10 void ChipChipArray::Arm::dWristTilt (sint16 a)

Tilt the wrist a certain number of degrees.

Parameters

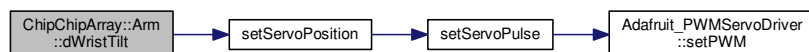
<i>degrees</i>	to move servo. Positive values add to the servo angle, and negative values subtract from the servo angle.
----------------	---

Definition at line 230 of file [Arm.hpp](#).

```

00230     {
00231         a += servoPos[WRIST_TILT];
00232         setServoPosition(WRIST_TILT, a);
00233         servoPos[WRIST_TILT] = a;
00234     }
  
```

Here is the call graph for this function:



5.2.3.11 void ChipChipArray::Arm::dWristTwist (sint16 a)

Twist the wrist a certain number of degrees.

Parameters

<i>degrees</i>	to move servo. Positive values add to the servo angle, and negative values subtract from the servo angle.
----------------	---

Definition at line 236 of file [Arm.hpp](#).

```

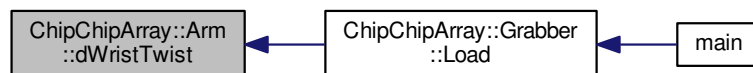
00236         {
00237             a += servoPos[WRIST_TWIST];
00238             setServoPosition(WRIST_TWIST, a);
00239             servoPos[WRIST_TWIST] = a;
00240         }

```

Here is the call graph for this function:



Here is the caller graph for this function:



5.2.3.12 void ChipChipArray::Arm::Elbow (uint8 a)

Bend the elbow to a specific position.

Parameters

<i>a</i>	desired servo position in degrees
----------	-----------------------------------

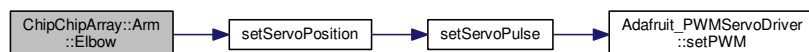
Definition at line 242 of file [Arm.hpp](#).

```

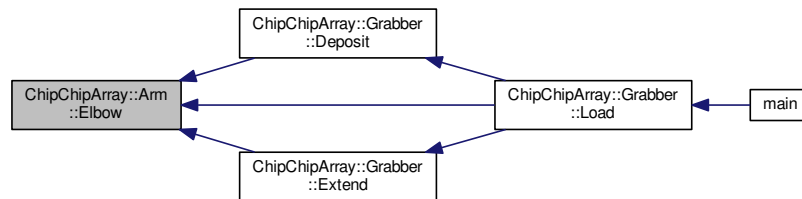
00242         {
00243             setServoPosition(ELBOW, a);
00244             servoPos[ELBOW] = a;
00245         }

```

Here is the call graph for this function:



Here is the caller graph for this function:



5.2.3.13 void ChipChipArray::Arm::Hover (Zone zone)

Moves arm into its "hovering" position over the blocks. The position changes with the zone.

Parameters

<i>zone</i>	the zone for which the arm should position itself
-------------	---

5.2.3.14 void ChipChipArray::Arm::LeftGripper (uint8 a) [protected]

Moves the left gripper to a specific position.

Parameters

<i>a</i>	desired servo position in degrees
----------	-----------------------------------

Definition at line 247 of file [Arm.hpp](#).

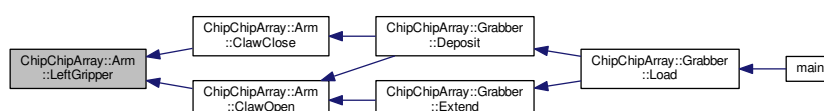
```

00247     {
00248         setServoPosition(GRIP_LEFT, a);
00249         servoPos[GRIP_LEFT] = a;
00250     }
  
```

Here is the call graph for this function:



Here is the caller graph for this function:



5.2.3.15 `void ChipChipArray::Arm::RightGripper (uint8 a)` `[protected]`

Moves the right gripper to a specific position.

Parameters

<i>a</i>	desired servo position in degrees
----------	-----------------------------------

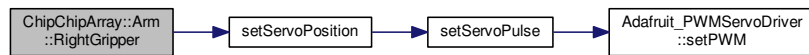
Definition at line 252 of file [Arm.hpp](#).

```

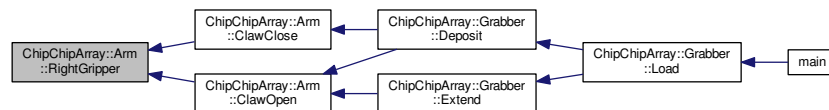
00252     {
00253         setServoPosition(GRIP_RIGHT, a);
00254         servoPos[GRIP_RIGHT] = a;
00255     }

```

Here is the call graph for this function:



Here is the caller graph for this function:



5.2.3.16 void ChipChipArray::Arm::WristTilt (uint8 a)

Tilt the wrist to a specific position.

Parameters

<i>a</i>	desired servo position in degrees
----------	-----------------------------------

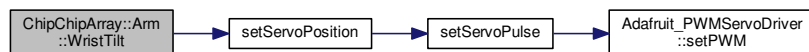
Definition at line 257 of file [Arm.hpp](#).

```

00257     {
00258         setServoPosition(WRIST_TILT, a);
00259         servoPos[WRIST_TILT] = a;
00260     }

```

Here is the call graph for this function:



5.2.3.17 void ChipChipArray::Arm::WristTwist (uint8 a)

Twist the wrist to a specific position.

Parameters

<i>a</i>	desired servo position in degrees
-----------------	-----------------------------------

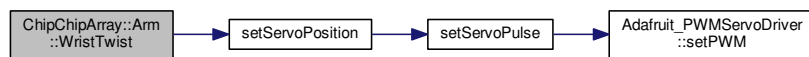
Definition at line 262 of file [Arm.hpp](#).

```

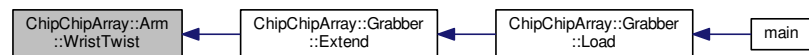
00262         {
00263             setServoPosition(WRIST_TWIST, a);
00264             servoPos[WRIST_TWIST] = a;
00265         }

```

Here is the call graph for this function:



Here is the caller graph for this function:



5.2.4 Member Data Documentation

5.2.4.1 uint8 ChipChipArray::Arm::servoPos[7] = { 0, 0, 0, 0, 0, 0, 0 }

The instantaneous position of each arm servo.

Definition at line 34 of file [Arm.hpp](#).

The documentation for this class was generated from the following file:

- [src/Arm.hpp](#)

5.3 ChipChipArray::Block Class Reference

```
#include <Block.hpp>
```

Public Member Functions

- [Block](#) (cv::Rect rect, [Color](#) color)

Public Attributes

- [uint32](#) area
- cv::Point [bottomLeft](#)
- cv::Point [bottomRight](#)
- [sint16](#) dBottom

- [sint16 dLeft](#)
- [sint16 dRight](#)
- [sint16 dTop](#)
- [sint16 dTopBottom](#)
- [sint16 dRightLeft](#)
- [sint16 offset](#)
- [uint16 height](#)
- [cv::Point topLeft](#)
- [cv::Point topRight](#)
- [uint16 width](#)
- [Color color](#)
- [Size size](#)

5.3.1 Detailed Description

This class represents a block. It only works for blocks found with the "boundingRect" algorithm (i.e., it doesn't work for blocks that are skewed on the image).

Definition at line 20 of file [Block.hpp](#).

5.3.2 Constructor & Destructor Documentation

5.3.2.1 ChipChipArray::Block::Block (cv::Rect rect, Color color)

Creates a new [Block](#) using the Points in the cv::Rect and the color. Also determines the size based on the area of the [Block](#).

Definition at line 139 of file [Block.hpp](#).

```

00139                                     {
00140         // basic geometric properties
00141         area = rect.area();
00142         height = rect.height;
00143         width = rect.width;
00144
00145         // assigning corners
00146         topLeft = rect.tl();
00147         bottomRight = rect.br();
00148         topRight = cv::Point(topLeft.x + width, topLeft.y);
00149         bottomLeft = cv::Point(topLeft.x, topLeft.y +
height);
00150         offset = (sint16)(topLeft.x + width / 2) - IMG_WIDTH / 2;
00151
00152         // calculating offsets (opencv low coordinates start top left)
00153         dLeft = topLeft.x;
00154         dRight = IMG_WIDTH - topRight.x;
00155         dTop = topLeft.y;
00156         dBottom = IMG_HEIGHT - bottomRight.y;
00157         dTopBottom = dTop - dBottom;
00158         dRightLeft = dRight - dLeft;
00159
00160         // set color and size
00161         this->color = color;
00162         size = area > MIN_WHOLE_BLOCK_SIZE ? Size::Long :
Size::Short;
00163     }
```

5.3.3 Member Data Documentation

5.3.3.1 uint32 ChipChipArray::Block::area

The area of the block in pixels

Definition at line 25 of file [Block.hpp](#).

5.3.3.2 `cv::Point` `ChipChipArray::Block::bottomLeft`

Point of the block's bottom-left corner

Definition at line 30 of file [Block.hpp](#).

5.3.3.3 `cv::Point` `ChipChipArray::Block::bottomRight`

Point of the block's bottom-right corner

Definition at line 35 of file [Block.hpp](#).

5.3.3.4 `Color` `ChipChipArray::Block::color`

The detected color of the block

Definition at line 107 of file [Block.hpp](#).

5.3.3.5 `sint16` `ChipChipArray::Block::dBottom`

Number of pixels from the block's bottom edge to the bottom edge of the image frame.

Definition at line 41 of file [Block.hpp](#).

5.3.3.6 `sint16` `ChipChipArray::Block::dLeft`

Number of pixels from the block's left edge to the left edge of the image frame.

Definition at line 47 of file [Block.hpp](#).

5.3.3.7 `sint16` `ChipChipArray::Block::dRight`

Number of pixels from the block's right edge to the right edge of the image frame.

Definition at line 53 of file [Block.hpp](#).

5.3.3.8 `sint16` `ChipChipArray::Block::dRightLeft`

The difference between `dRight` and `dLeft`. It indicates the relative vertical positioning of the block regardless of the block's area. A positive value indicates the block is off-center towards the left.

Definition at line 75 of file [Block.hpp](#).

5.3.3.9 `sint16` `ChipChipArray::Block::dTop`

Number of pixels from the block's top edge to the top edge of the image frame.

Definition at line 59 of file [Block.hpp](#).

5.3.3.10 `sint16` `ChipChipArray::Block::dTopBottom`

The difference between `dTop` and `dBottom`. It indicates the relative vertical positioning of the block regardless of the block's area. A positive value indicates the block is off-center towards the bottom.

Definition at line 67 of file [Block.hpp](#).

5.3.3.11 uint16 ChipChipArray::Block::height

The height of the block in pixels

Definition at line 87 of file [Block.hpp](#).

5.3.3.12 sint16 ChipChipArray::Block::offset

The difference in pixels between the vertical center of the image and the vertical center of the block. Assumes image is 1280 pixels wide (like the Raspicam images).

Definition at line 82 of file [Block.hpp](#).

5.3.3.13 Size ChipChipArray::Block::size

The size of the block (half or whole)

Definition at line 112 of file [Block.hpp](#).

5.3.3.14 cv::Point ChipChipArray::Block::topLeft

Point of the block's top-left corner

Definition at line 92 of file [Block.hpp](#).

5.3.3.15 cv::Point ChipChipArray::Block::topRight

Point of the block's top-right corner

Definition at line 97 of file [Block.hpp](#).

5.3.3.16 uint16 ChipChipArray::Block::width

The width of the block in pixels

Definition at line 102 of file [Block.hpp](#).

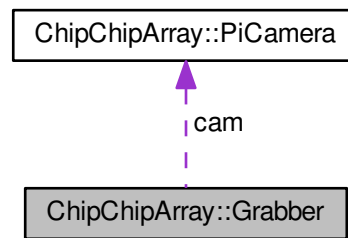
The documentation for this class was generated from the following file:

- [src/Block.hpp](#)

5.4 ChipChipArray::Grabber Class Reference

```
#include <Grabber.hpp>
```

Collaboration diagram for ChipChipArray::Grabber:



Public Member Functions

- [Grabber](#) ([Zone zone](#), [Side side](#))
- void [Close](#) ()
- [Result Load](#) ()

Protected Member Functions

- void [Deposit](#) ([Color color=Color::Blue](#))
- void [Extend](#) ()
- [Block LocateBlocks](#) ([Color color=Color::Perrywinkle](#))
- [Block LocateBlueBlock](#) ()

Protected Attributes

- [PiCamera cam](#)
- [Side side](#)
- [Zone zone](#)

5.4.1 Detailed Description

This class finds blocks, identifies them, and sorts them according to color, size, and zone.

Definition at line 30 of file [Grabber.hpp](#).

5.4.2 Constructor & Destructor Documentation

5.4.2.1 ChipChipArray::Grabber::Grabber ([Zone zone](#), [Side side](#))

Initializes the class according to the side and zone and extends the robotic arm into position.

Parameters

<i>zone</i>	the zone (A, B, or C) for which to pick up blocks.
<i>side</i>	the side from which the robot is moving and the position of the blocks (right or left) in the view of the camera to pick up first

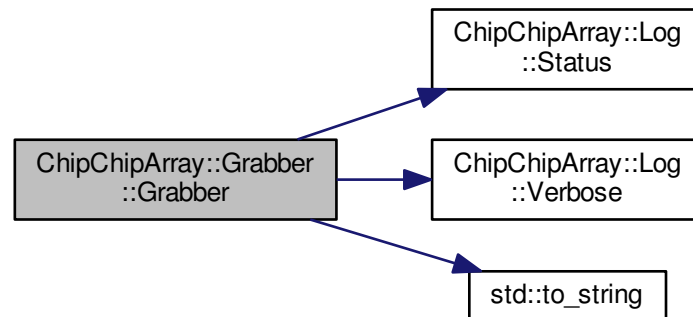
Definition at line 143 of file [Grabber.hpp](#).

```

00143     {
00144         log.Status("Opening Grabber");
00145         log.Verbose("Zone: " + std::to_string(zone));
00146         log.Verbose("Side: " + std::to_string(side));
00147
00148         this->zone = zone;
00149         this->side = side;
00150
00151         log.Verbose("Setting HSV threshold values");
00152
00153         rangeVals[Color::Red] = { cv::Scalar(0, 20, 60),
00154             cv::Scalar(12, 255, 255) };
00155         rangeVals[Color::Green] = { cv::Scalar(49, 41, 17),
00156             cv::Scalar(63, 255, 255) };
00157         rangeVals[Color::Blue] = { cv::Scalar(70, 0, 0),
00158             cv::Scalar(100, 255, 255) };
00159
00160         /* Remember, we're only pretending this color's image is in HSV space.
00161          * It's really in YUV, as required by Jacob yellow-detection algorithm. */
00162         rangeVals[Color::Yellow] = { cv::Scalar(0, 0, 0),
00163             cv::Scalar(255, 255, 20) };
00164     }

```

Here is the call graph for this function:



5.4.3 Member Function Documentation

5.4.3.1 void ChipChipArray::Grabber::Close ()

Closes the [Grabber](#). Retracts the arm and closes the camera.

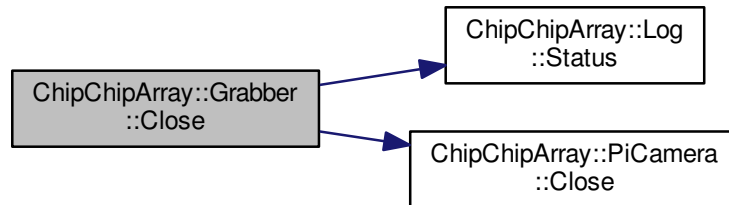
Definition at line 166 of file [Grabber.hpp](#).

```

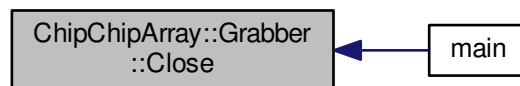
00166     {
00167         log.Status("Closing Grabber");
00168         cam.Close();
00169     }

```

Here is the call graph for this function:



Here is the caller graph for this function:



5.4.3.2 void ChipChipArray::Grabber::Deposit (Color color = Color::Blue) [protected]

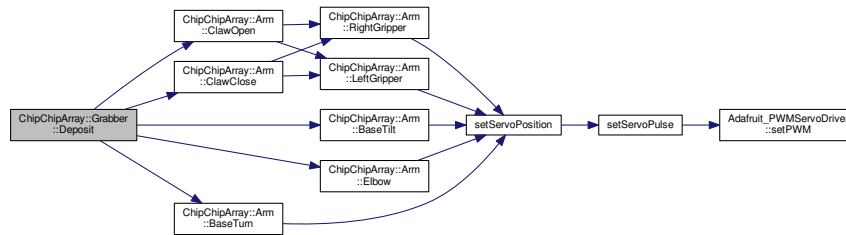
Deposits blocks in the storage/unloading unit.

Definition at line 171 of file [Grabber.hpp](#).

```

00171     {
00172         if(color == Color::Blue) {
00173             arm.ClawClose();
00174             sleep(1);
00175             arm.BaseTilt(160);
00176             sleep(1);
00177             arm.Elbow(130);
00178             sleep(1);
00179             arm.BaseTurn(47);
00180             sleep(1);
00181             arm.ClawOpen();
00182             sleep(1);
00183         } else {
00184             throw std::runtime_error("Du Idiot! Die Armbewegungen für diese "
00185                                     "Farbe sind noch nicht implementiert. Vielleicht sollst "
00186                                     "'du die englische Phrase lernen 'Would you like fries "
00187                                     "'with that?'");
00188         }
00189     }
  
```


Here is the call graph for this function:



Here is the caller graph for this function:



5.4.3.3 void ChipChipArray::Grabber::Extend () [protected]

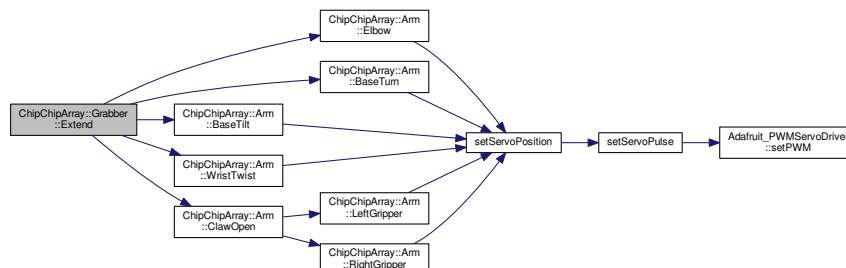
Sets arm to generic position roughly right above a stack of blocks.

Definition at line 191 of file [Grabber.hpp](#).

```

00191         {
00192             arm.Elbow(180);
00193             usleep(500000);
00194             arm.BaseTurn(132);
00195             arm.BaseTilt(125);
00196             arm.Elbow(150);
00197             arm.WristTwist(90);
00198             arm.ClawOpen();
00199             sleep(2);
00200         }
  
```

Here is the call graph for this function:



Here is the caller graph for this function:



5.4.3.4 Result ChipChipArray::Grabber::Load ()

Loads a block(s) (if possible) at the robot's current position.

Returns

the number of half and whole blocks loaded

Definition at line 202 of file [Grabber.hpp](#).

```

00202         {
00203     for(uint8 i = 0; i < 2; i++) {
00204         Extend();
00205
00206         try {
00207             Block block = (zone == Zone::A)
00208                 ? LocateBlocks(Color::Blue) :
00209                 LocateBlueBlock();
00210
00211             float32 baseKonstant = 0.5;
00212             if(block.dRightLeft > 0) baseKonstant *= -1;
00213             float32 degree = baseKonstant * std::sqrt(block.dRightLeft);
00214             arm.dBaseTurn(degree);
00215             arm.dWristTwist(-degree);
00216             sleep(1);
00217             arm.BaseTilt(140);
00218             sleep(1);
00219
00220             uint8 bend = (i == 0 ? 100 : 90);
00221
00222             // lower claw over block
00223             for(uint8 j = 140; j >= bend; j -= 10) {
00224                 arm.Elbow(j);
00225                 sleep(1);
00226             }
00227
00228             // deposit in bin
00229             sleep(1);
00230             Deposit();
00231         } catch(std::exception ex) {
00232             log.Error(std::string("An exception occurred attempting "
00233                 "to load the blocks in function Grabber::Load(): ")
00234                 + ex.what());
00235         }
00236
00237         if(i == 0) {
00238             arm.BaseTurn(132);
00239         } else {
00240             arm.BaseTurn(135);
00241             sleep(1);
00242             arm.BaseTilt(180);
00243             sleep(1);
00244             arm.Elbow(90);
00245             sleep(1);
00246             arm.Elbow(45);
00247             sleep(1);
00248             arm.Elbow(0);
00249         }
00250     }
00251 }
  
```

```
graph LR
    main --> Grabber[ChipChipArray::Grabber  
::Load]
```

Loads a stack of blocks for all zones. Does multiple colors and both sizes.

<i>color</i>	the color block for which to search. Perrywinkle denotes searching for all colors (because who actually knows what color perrywinkle is?).
--------------	--

Block instance representing the block found

```
00254                                     {
00255         invokeCount++;
00256         std::string logstr = "Locating blocks";
00257
00258         if (color == Color::Perrywinkle) {
00259             logstr += " (" + std::to_string(color) + ")";
```

```

00260     }
00261
00262     log.Verbose(logstr);
00263
00264     cv::Mat imgOrig;
00265     cv::transpose(cam.Snap(), imgOrig);
00266
00267     cv::Mat imgHSV;
00268     cv::Mat imgThresh;
00269     std::vector<cv::Rect> blocks;
00270     std::vector<Color> colors;
00271
00272     uint8 loopNum = (color == Color::Perrywinkle ? rangeVals.size() : 1);
00273
00274     for(int i = 0; i < loopNum; i++) {
00275         if(loopNum > 1) {
00276             switch(i) {
00277                 case 0:
00278                     color = Color::Red;
00279                     break;
00280
00281                 case 1:
00282                     color = Color::Green;
00283                     break;
00284
00285                 case 2:
00286                     color = Color::Blue;
00287                     break;
00288
00289                 /* Must be last, because it changes imgHSV from HSV space
00290                  * to YUV space. */
00291                 case 3:
00292                     color = Color::Yellow;
00293                     break;
00294             }
00295         }
00296
00297         log.Verbose("Searching: " + std::to_string(color));
00298
00299         if(color == Color::Yellow) {
00300             cv::Mat temp;
00301             imgOrig.copyTo(temp);
00302             cv::cvtColor(imgOrig, imgHSV, CV_BGR2YUV);
00303             cv::cvtColor(imgHSV, temp, CV_HSV2BGR);
00304             cv::cvtColor(temp, imgHSV, cv::COLOR_BGR2HSV);
00305             log.Image(temp, "yuv_yellow_" + std::to_string(color)
00306                     + "_" + std::to_string(zone)
00307                     + std::to_string(invokeCount)
00308                     + ".bmp");
00309         } else {
00310             cv::cvtColor(imgOrig, imgHSV, cv::COLOR_BGR2HSV);
00311         }
00312
00313         cv::inRange(imgHSV, rangeVals[color][0],
00314                   rangeVals[color][1], imgThresh);
00315
00316         /*
00317          * Not quite sure what all this does, but it seems to
00318          * relate to smoothing the image
00319          */
00320         cv::erode(imgThresh, imgThresh,
00321                  cv::getStructuringElement(
00322                      cv::MORPH_ELLIPSE,
00323                      cv::Size(5, 5)));
00324         cv::dilate(imgThresh, imgThresh,
00325                   cv::getStructuringElement(
00326                      cv::MORPH_ELLIPSE,
00327                      cv::Size(5, 5)));
00328         cv::dilate(imgThresh, imgThresh,
00329                   cv::getStructuringElement(
00330                      cv::MORPH_ELLIPSE,
00331                      cv::Size(5, 5)));
00332         cv::erode(imgThresh, imgThresh,
00333                  cv::getStructuringElement(
00334                      cv::MORPH_ELLIPSE,
00335                      cv::Size(5, 5)));
00336
00337         log.Image(imgThresh, "thresh_" + std::to_string(color)
00338                 + "_" + std::to_string(zone)
00339                 + std::to_string(invokeCount)
00340                 + ".bmp");
00341
00342         // calculate contours
00343         std::vector<std::vector<cv::Point>> contours;
00344         cv::findContours(imgThresh, contours, CV_RETR_TREE,
00345                         CV_CHAIN_APPROX_SIMPLE,
00346                         cv::Point(0, 0));

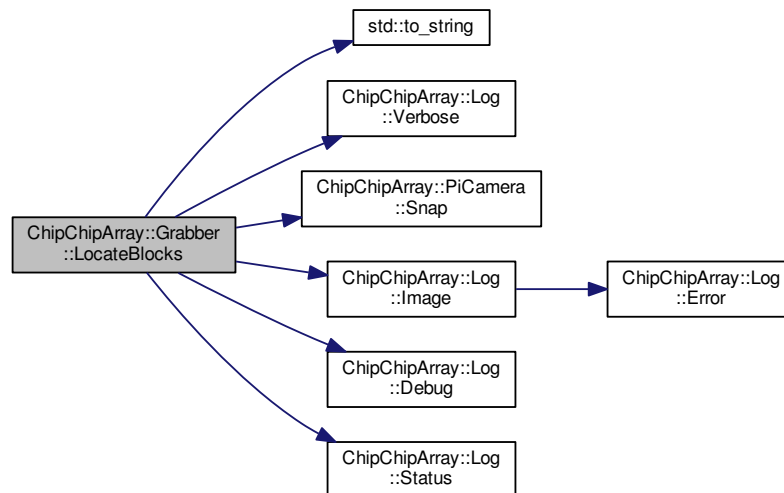
```

```

00347         std::vector<std::vector<cv::Point>>
00348             contours_poly(contours.size());
00349         std::vector<cv::Rect> bounds(contours.size());
00350
00351         // find rectangle around polygon-ish shapes
00352         for(int i = 0; i < contours.size(); i++) {
00353             uint32 area = cv::contourArea(contours[i]);
00354
00355             // determine if block and add to blocks vector
00356             if(area > MIN_HALF_BLOCK_SIZE) {
00357                 cv::approxPolyDP(cv::Mat(contours[i]),
00358                     contours_poly[i], 20,
00359                     false);
00360                 cv::Rect rect = cv::boundingRect(
00361                     cv::Mat(contours_poly[i]));
00362                 log.Debug(std::to_string(color)
00363                     + " block detected "
00364                     + "with area "
00365                     + std::to_string(
00366                         area));
00367                 blocks.push_back(rect);
00368                 colors.push_back(color);
00369             }
00370         }
00371     }
00372
00373     if(blocks.size() == 0) {
00374         log.Image(imgOrig, "original_" + std::to_string(
zone)
00375             + std::to_string(invokeCount)
00376             + "_no_blocks.bmp");
00377         throw std::runtime_error("No blocks found!");
00378     } else {
00379         log.Status(std::to_string(blocks.size())
00380             + " blocks found");
00381     }
00382
00383     // coordinates start in top right
00384     Block block = Block(blocks[0], colors[0]);
00385
00386     if(blocks.size() > 1) {
00387         for(int i = 1; i < blocks.size(); i++) {
00388             if((side == Side::Right && blocks[i].x
00389                 > block.topLeft.x)
00390                 || (side == Side::Left
00391                     && blocks[i].x
00392                     < block.topLeft.x)) {
00393                 block = Block(blocks[i], colors[i]);
00394             }
00395         }
00396     }
00397
00398     log.Status(std::to_string(block.color) + " block is located");
00399
00400     log.Debug("Block properties => area: " + std::to_string(block.area)
00401         + ", height: " + std::to_string(block.height) + ", width: "
00402         + std::to_string(block.width) + ", offset: "
00403         + std::to_string(block.offset) + ", color: "
00404         + std::to_string(block.color) + ", size: "
00405         + std::to_string(block.size));
00406
00407     /*
00408     * Draw surrounding rectangles from above on original
00409     * image.
00410     */
00411     cv::rectangle(imgOrig, block.topLeft, block.bottomRight,
00412         cv::Scalar(255, 0, 0), 4, 8);
00413     log.Image(imgOrig, "original_" + std::to_string(zone)
00414         + std::to_string(invokeCount)
00415         + ".bmp");
00416
00417     return block;
00418 }

```

Here is the call graph for this function:



Here is the caller graph for this function:



5.4.3.6 Block `ChipChipArray::Grabber::LocateBlueBlock ()` [protected]

Finds whole, blue blocks.

Returns

[Block](#) instance representing the block found

Definition at line 420 of file [Grabber.hpp](#).

```

00420         {
00421             std::vector<cv::Mat> channels;
00422             std::vector<cv::Rect> blocks;
00423
00424             invokeCount++;
00425             log.Status("Locating blue blocks");
00426
00427             cv::Mat img;
00428             cv::Mat imgThresh;
00429             cv::split(cam.Snap(), channels);
00430             cv::transpose(channels[0], img);
00431
00432             log.Verbose("Searching: Blue block");
00433             cv::inRange(img, 30, 255, imgThresh);
00434             log.Image(imgThresh, "thresh_blue" + std::to_string(
zone)

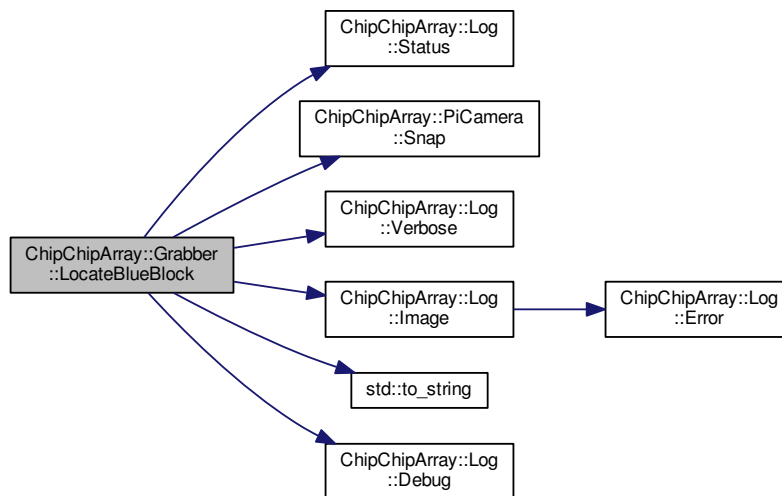
```

```

00435         + std::to_string(invokeCount) + ".bmp");
00436
00437     // calculate contours
00438     std::vector<std::vector<cv::Point>> contours;
00439     cv::findContours(imgThresh, contours, CV_RETR_TREE,
00440         CV_CHAIN_APPROX_SIMPLE,
00441         cv::Point(0, 0));
00442     std::vector<std::vector<cv::Point>>
00443         contours_poly(contours.size());
00444     std::vector<cv::Rect> bounds(contours.size());
00445
00446     // find rectangle around polygon-ish shapes
00447     for(int i = 0; i < contours.size(); i++) {
00448         uint32 area = cv::contourArea(contours[i]);
00449
00450         // determine if block and add to blocks vector
00451         if(area > MIN_HALF_BLOCK_SIZE) {
00452             cv::approxPolyDP(cv::Mat(contours[i]),
00453                 contours_poly[i], 20,
00454                 false);
00455             cv::Rect rect = cv::boundingRect(
00456                 cv::Mat(contours_poly[i]));
00457             log.Debug("Blue block detected with area "
00458                 + std::to_string(area));
00459             blocks.push_back(rect);
00460         }
00461     }
00462
00463     if(blocks.size() == 0) {
00464         log.Image(img, "original_" + std::to_string(zone)
00465             + std::to_string(invokeCount)
00466             + "_no_blocks.bmp");
00467         throw std::runtime_error("No blocks found!");
00468     } else {
00469         log.Status(std::to_string(blocks.size())
00470             + " blocks found");
00471     }
00472
00473     // coordinates start in top right
00474     Block block = Block(blocks[0], Color::Blue);
00475
00476     if(blocks.size() > 1) {
00477         for(int i = 1; i < blocks.size(); i++) {
00478             if((side == Side::Right && blocks[i].x
00479                 > block.topLeft.x
00480                 || (side == Side::Left
00481                     && blocks[i].x
00482                     < block.topLeft.x)) {
00483                 block = Block(blocks[i], Color::Blue);
00484             }
00485         }
00486     }
00487
00488     log.Status(std::to_string(block.color) + " block is located");
00489
00490     log.Debug("Block properties => area: " + std::to_string(block.area)
00491         + ", height: " + std::to_string(block.height) + ", width: "
00492         + std::to_string(block.width) + ", offset: "
00493         + std::to_string(block.offset) + ", color: "
00494         + std::to_string(block.color) + ", size: "
00495         + std::to_string(block.size));
00496
00497     /*
00498     * Draw surrounding rectangles from above on original
00499     * image.
00500     */
00501     cv::rectangle(img, block.topLeft, block.bottomRight,
00502         cv::Scalar(255, 0, 0), 4, 8);
00503     log.Image(img, "original_" + std::to_string(zone)
00504         + std::to_string(invokeCount)
00505         + ".bmp");
00506
00507     return block;
00508 }
00509

```

Here is the call graph for this function:



Here is the caller graph for this function:



5.4.4 Member Data Documentation

5.4.4.1 PiCamera `ChipChipArray::Grabber::cam` [protected]

The Raspicam

Definition at line 64 of file [Grabber.hpp](#).

5.4.4.2 Side `ChipChipArray::Grabber::side` [protected]

The side from which the robot is coming (i.e., the side where the higher priority blocks are to be picked up).

Definition at line 71 of file [Grabber.hpp](#).

5.4.4.3 Zone `ChipChipArray::Grabber::zone` [protected]

The zone in which blocks are being loaded.

Definition at line 76 of file [Grabber.hpp](#).

The documentation for this class was generated from the following file:

- [src/Grabber.hpp](#)

5.5 ChipChipArray::Log Class Reference

```
#include <Log.hpp>
```

Public Member Functions

- [Log](#) ()
- [Log](#) (auto dir, [LogMode](#) mode=[LogMode::Text](#))
- [~Log](#) ()
- void [Debug](#) (auto mesg)
- void [Error](#) (auto mesg)
- void [Image](#) (cv::Mat image, auto filename)
- void [Open](#) (auto dir, [LogMode](#) mode=[LogMode::Text](#))
- void [Status](#) (auto mesg)
- void [Variable](#) (auto name, auto value)
- void [Verbose](#) (auto mesg)

5.5.1 Detailed Description

This class logs the text and images passed to it to specified directory.

A "container" directory to which the class can write is passed in the constructor. When the [Log](#) is initialized with [LogMode::Text](#), a new log file is created with a filename based on the time of initialization in the given directory. When initialized in [LogMode::Multi](#), it will create a subdirectory in the given directory with a name based on time. In this new directory, a log file will be created. Images may later be stored in this directory with names based on the order in which they were saved.

This class DOES NOT WORK without compiling without a "LOG" definition (#define LOG or -DLOG).

Definition at line 35 of file [Log.hpp](#).

5.5.2 Constructor & Destructor Documentation

5.5.2.1 ChipChipArray::Log::Log () [inline]

Initializes [Log](#) object but does not open log. [Open\(\)](#) must be called.

Definition at line 41 of file [Log.hpp](#).

```
00041 {};
```

5.5.2.2 ChipChipArray::Log::Log (auto dir, [LogMode](#) mode = [LogMode::Text](#))

Initializes the [Log](#).

A new log file is created in dir if [LogMode::Text](#) is given. The file will have a name based on the current date and time. If [LogMode::Multi](#) is given, a new directory is created, and a log file with a name based on the current date and time is created inside it.

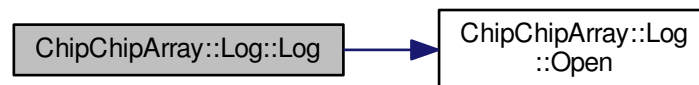
Parameters

<i>dir</i>	the directory for the newly created logfile/folder
<i>mode</i>	the LogMode

Definition at line 187 of file [Log.hpp](#).

```
00187                                     {
00188     #ifdef LOG
00189         Open(dir, mode);
00190     #endif
00191 }
```

Here is the call graph for this function:



5.5.2.3 ChipChipArray::Log::~~Log ()

Destroys the [Log](#) and closes the logfile.

Definition at line 193 of file [Log.hpp](#).

```
00193     {
00194     #ifdef LOG
00195         try {
00196             file.flush();
00197             file.close();
00198         } catch (std::ofstream::failure f) {
00199             LogError("Gosh dang it! A fatal error has occurred "
00200                     "closing the logfile.", f);
00201         }
00202     #endif
00203 }
```

5.5.3 Member Function Documentation

5.5.3.1 void ChipChipArray::Log::Debug (auto mesg)

Writes "DEBUG: " to the log file along with the message passed. Should be used for generic debugging information. If recording the value of a variable in the [Log](#) is desired, use the function [Variable\(\)](#) instead.

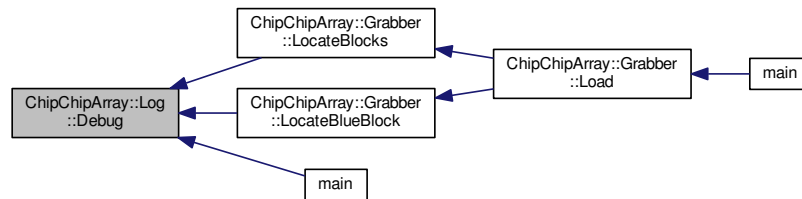
Parameters

<i>mesg</i>	the message to record in the logfile
-------------	--------------------------------------

Definition at line 205 of file [Log.hpp](#).

```
00205                                     {
00206     #ifdef LOG
00207         try {
00208             file << "DEBUG: " << mesg << std::endl;
00209             file.flush();
00210         } catch (std::ofstream::failure f) {
00211             LogError("Debug() write error", f);
00212         }
00213     #endif
00214 }
```

Here is the caller graph for this function:



5.5.3.2 void ChipChipArray::Log::Error (auto mesg)

Writes "ERROR: " to the log file. Should only be use when an exception is thrown.

Parameters

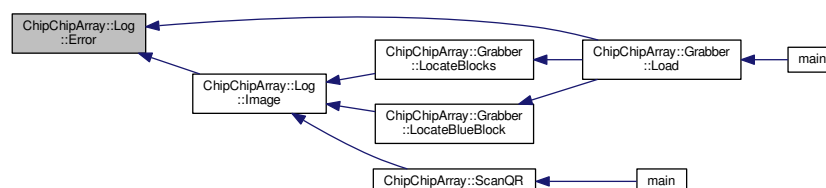
<i>mesg</i>	the message to record in the log
-------------	----------------------------------

Definition at line 216 of file [Log.hpp](#).

```

00216                                     {
00217     #ifdef LOG
00218         try {
00219             file << "ERROR: " << mesg << std::endl;
00220             file.flush();
00221         } catch (std::ofstream::failure f) {
00222             LogError("Error() write error", f);
00223         }
00224     #endif
00225 }
  
```

Here is the caller graph for this function:



5.5.3.3 void ChipChipArray::Log::Image (cv::Mat image, auto filename)

Creates a bitmap image in the subdirectory created by the [Log](#) during initialization. Does nothing if [LogMode::Text](#) was passed in the constructor.

Parameters

<i>image</i>	the image to save
<i>filename</i>	the filename for the saved image

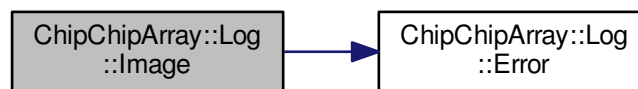
Definition at line 227 of file [Log.hpp](#).

```

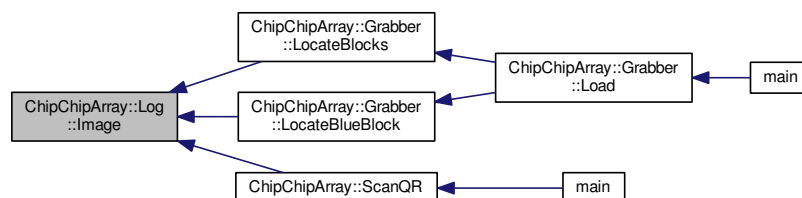
00227                                     {
00228 #ifdef LOG
00229     try {
00230         cv::imwrite(dir + std::string(filename), image);
00231     } catch(std::ofstream::failure f) {
00232         LogError("Image() write error", f);
00233     } catch(std::exception ex) {
00234         Error("Error writing image " + std::string(filename));
00235     }
00236 #endif
00237 }

```

Here is the call graph for this function:



Here is the caller graph for this function:



5.5.3.4 void ChipChipArray::Log::Open (auto dir, LogMode mode = LogMode::Text)

Definition at line 247 of file [Log.hpp](#).

```

00247                                     {
00248 #ifdef LOG
00249     // format date and time
00250     char date[32];
00251     time_t sec = time(nullptr);
00252     struct tm * loctime = localtime(&sec);
00253     strftime(date, 32, "%m-%d_%H-%M-%S", loctime);
00254
00255     // create temporary strings
00256     this->dir = std::string(dir);
00257     std::string datestr = std::string(date);
00258
00259     // add path separator if necessary
00260     if(this->dir[this->dir.length() - 1] != PATH_SEP) {
00261         this->dir += PATH_SEP;
00262     }

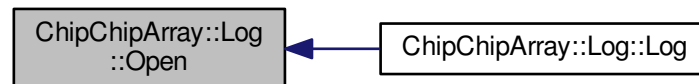
```

```

00263
00264 // add directory for log and images if necessary
00265 if(mode == LogMode::Multi) this->dir += datestr + PATH_SEP;
00266
00267 int ret = mkdir(this->dir.c_str(), S_IRUSR | S_IWUSR | S_IRGRP | S_IWGRP
00268               | S_IROTH | S_IWOTH | S_IXUSR | S_IXGRP
00269               | S_IXOTH);
00270
00271 filename = this->dir + datestr + ".log";
00272
00273 // set class mode
00274 this->mode = mode;
00275
00276 // Initializing file
00277 file.exceptions(std::ofstream::failbit
00278               | std::ofstream::badbit);
00279
00280 try {
00281     file.open(filename, std::ofstream::out
00282               | std::ofstream::app);
00283 } catch(std::ofstream::failure ex) {
00284     LogError("Oh, no! An error has occurred opening the "
00285             "log file.", ex);
00286 }
00287 #endif
00288 }

```

Here is the caller graph for this function:



5.5.3.5 void ChipChipArray::Log::Status (auto mesg)

Writes "STATUS: " to the log file. Should be used when recording the status or state of the program. It should not be used to record microalgorithmic changes. Use [Verbose\(\)](#) for these instead.

Parameters

<i>mesg</i>	the message to record in the logfile
-------------	--------------------------------------

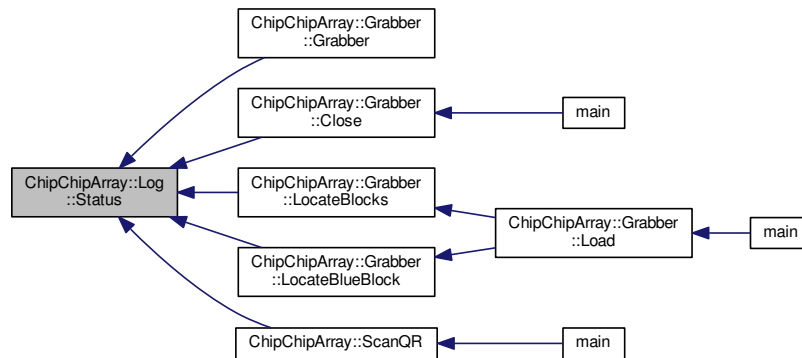
Definition at line 290 of file [Log.hpp](#).

```

00290
00291 #ifdef LOG
00292     try {
00293         file << "STATUS: " << mesg << std::endl;
00294         file.flush();
00295     } catch (std::ofstream::failure f) {
00296         LogError("Status() write error", f);
00297     }
00298 #endif
00299 }

```

Here is the caller graph for this function:



5.5.3.6 void ChipChipArray::Log::Variable (auto *name*, auto *value*)

Writes "VARIABLE: " to the log file. Should be used whenever recording the value of a variable is desired.

Parameters

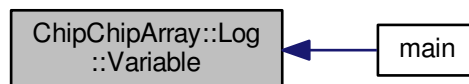
<i>name</i>	the variable name to record
<i>value</i>	the variable value to record

Definition at line 301 of file [Log.hpp](#).

```

00301                                     {
00302     #ifdef LOG
00303         try {
00304             file << "VARIABLE: " << name << " = " << value
00305                 << std::endl;
00306             file.flush();
00307         } catch (std::ofstream::failure f) {
00308             LogError("Variable() write error", f);
00309         }
00310     #endif
00311 }
  
```

Here is the caller graph for this function:



5.5.3.7 void ChipChipArray::Log::Verbose (auto *mesg*)

Writes "VERBOSE: " to the log file. Should only be used for recording small, specific portions of code. To record a change in the more general state of the program, use [Status\(\)](#) instead.

Parameters

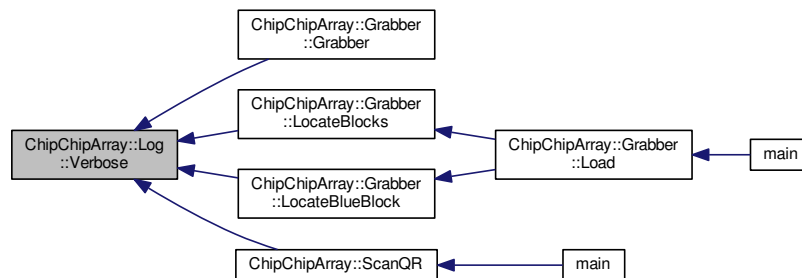
<i>mesg</i>	the message to record in the logfile
-------------	--------------------------------------

Definition at line 313 of file [Log.hpp](#).

```

00313                                     {
00314     #ifdef LOG
00315         try {
00316             file << "VERBOSE: " << mesg << std::endl;
00317             file.flush();
00318         } catch(std::ofstream::failure f) {
00319             LogError("Verbose() write error", f);
00320         }
00321     #endif
00322 }
```

Here is the caller graph for this function:



The documentation for this class was generated from the following file:

- [src/Log.hpp](#)

5.6 ChipChipArray::PiCamera Class Reference

```
#include <PiCamera.hpp>
```

Public Member Functions

- [PiCamera](#) ()
- [PiCamera](#) (bool useColor)
- void [Close](#) ()
- cv::Mat [Snap](#) ()

5.6.1 Detailed Description

This class is a basic wrapper to allow the Raspicam to interface with OpenCV. It uses another wrapper class, Raspicam, provided by Cédric Verstraeten (<https://github.com/cedricve/raspicam>).

Definition at line 24 of file [PiCamera.hpp](#).

5.6.2 Constructor & Destructor Documentation

5.6.2.1 ChipChipArray::PiCamera::PiCamera () [inline]

Opens the camera and configures it for color images.

Definition at line 29 of file [PiCamera.hpp](#).

```
00029 : PiCamera(true) {};
```

5.6.2.2 ChipChipArray::PiCamera::PiCamera (bool useColor)

Opens the camera.

Parameters

<i>useColor</i>	Specifies whether camera should make color images. TRUE = color, FALSE = grayscale.
-----------------	---

Definition at line 59 of file [PiCamera.hpp](#).

```
00059         {
00060             cam.set(CV_CAP_PROP_FORMAT, (useColor ? CV_16UC3 : CV_16UC1));
00061             cam.open();
00062             usleep(500000); // required to allow camera time to adjust!
00063         }
```

5.6.3 Member Function Documentation

5.6.3.1 void ChipChipArray::PiCamera::Close ()

Closes connection to camera.

Definition at line 65 of file [PiCamera.hpp](#).

```
00065         {
00066             cam.release();
00067         }
```

Here is the caller graph for this function:



5.6.3.2 cv::Mat ChipChipArray::PiCamera::Snap ()

Makes picture.

Chapter 6

File Documentation

6.1 etc/doxygen.config File Reference

Doxygen configuration file.

6.1.1 Detailed Description

Doxygen configuration file.

Author

Samuel Andrew Wisner, awisner94@gmail.com

Definition in file [doxygen.config](#).

6.2 doxygen.config

```
00001 PROJECT_NAME = "ChipChipArray"
00002
00003 INPUT = src/ etc/doxygen.config makefile
00004 OUTPUT_DIRECTORY = doc/
00005
00006 GENERATE_HTML = YES
00007 GENERATE_RTF = YES
00008 GENERATE_LATEX = YES
00009 GENERATE_MAN = YES
00010 GENERATE_XML = NO
00011 GENERATE_DOCBOOK = NO
00012
00013 USE_PDF_LATEX = YES
00014 USE_PDF_HYPERLINKS = YES
00015
00016 RECURSIVE = YES
00017 SOURCE_BROWSER = YES
00018 SOURCE_TOOLTIPS = YES
00019 EXTRACT_ALL = YES
00020 DISABLE_INDEX = NO
00021 GENERATE_TREEVIEW = YES
00022 SEARCHENGINE = YES
00023 SERVER_BASED_SEARCH = NO
00024 USE_MDFILE_AS_MAINPAGE = README.md
00025
00026 LATEX_SOURCE_CODE = YES
00027 STRIP_CODE_COMMENTS = YES
00028 INLINE_SOURCES = YES
00029
00030 HAVE_DOT = YES
00031 CALL_GRAPH = YES
00032 CALLER_GRAPH = YES
```

6.3 makefile File Reference

Project makefile containing recipes for compiling the actual application, test applications, and generating documentation.

6.3.1 Detailed Description

Project makefile containing recipes for compiling the actual application, test applications, and generating documentation.

Author

Samuel Andrew Wisner, awisner94@gmail.com

Definition in file [makefile](#).

6.4 makefile

```

00001 GCC = g++-4.9
00002 ARM = -L/usr/local/lib -lwiringPi
00003 CPPFLAGS = -g -std=gnu++14
00004 CVFLAGS = -lraspicam -lraspicam_cv -lmmal -lmmal_core -lmmal_util -lzbar -lopencv_core
             -lopencv_highgui -lopencv_imgproc
00005 LOG = -DLOG
00006
00007 export LIBRARY_PATH=/opt/vc/lib:/usr/lib/arm-linux-gnueabi
00008
00009 arm:
00010     $(GCC) src/dark_magic.cpp -o bin/arm $(ARM) $(CPPFLAGS)
00011
00012 block-test:
00013     $(GCC) src/cv_shape.cpp -o bin/cvshape $(CVFLAGS) $(CPPFLAGS)
00014
00015 channel-test:
00016     $(GCC) src/cv_channel_test.cpp -o bin/channeltest $(CVFLAGS) $(CPPFLAGS)
00017
00018
00019 comp:
00020     $(GCC) src/main.cpp -o bin/main $(CVFLAGS) $(CPPFLAGS) $(ARM) -lpthread
00021
00022 configure:
00023     sudo apt-get install -y libopencv-dev libzbar-dev cmake doxygen libglib2.0-dev
00024     git clone https://github.com/cedricve/raspicam
00025     cd raspicam; mkdir build; cd build; cmake ..; make; sudo make install; sudo ldconfig;
00026     sudo rm -r raspicam
00027     mkdir docs
00028
00029 cv-test:
00030     $(GCC) src/cv_test.cpp -o bin/cvtest $(CVFLAGS) $(CPPFLAGS) $(LOG)
00031
00032 img:
00033     $(GCC) src/img.cpp -o bin/img $(CVFLAGS) $(CPPFLAGS)
00034
00035 jacob-algorithm-test:
00036     $(GCC) src/jacob_alg_test.cpp -o bin/jacobalgtest $(CVFLAGS) $(CPPFLAGS)
00037
00038 loading-test:
00039     $(GCC) src/loading_test.cpp -o bin/loadingtest $(CPPFLAGS) $(LOG) $(ARM) $(CVFLAGS)
00040
00041 log-test:
00042     $(GCC) src/log_test.cpp -o bin/logtest $(CPPFLAGS) $(LOG)
00043
00044 net-cv-hue-test:
00045     $(GCC) src/cv_hue.cpp -o bin/cvhue $(CPPFLAGS) $(CVFLAGS)
00046
00047 net-qr-test:
00048     $(GCC) src/net_qr_test.cpp -o bin/netqrtest $(CPPFLAGS) $(CVFLAGS)
00049
00050 qr-test:
00051     $(GCC) src/qr_test.cpp -o bin/qrtest $(CPPFLAGS) $(CVFLAGS) $(LOG)
00052
00053 servotrip:
00054     $(GCC) src/main.cpp -o bin/servotrip $(CPPFLAGS) $(ARM)
00055
00056 docs:

```

```

00057  rm -r doc/
00058  doxygen etc/doxygen.config
00059  cd doc/latex; make pdf;
00060  git reset
00061  git add doc/.
00062  git commit -m "Updated documentation."
00063  git push
00064
00065 count:
00066  grep -r "src/" -e "Samuel Andrew Wisner" -l | xargs wc -l # works assuming there's no
    subdirectories

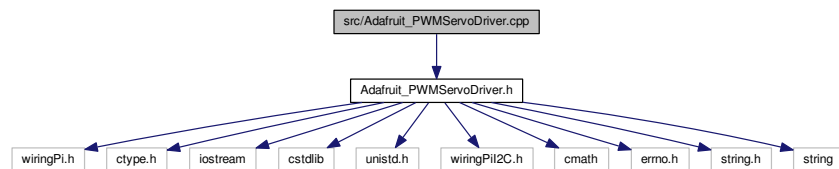
```

6.5 src/Adafruit_PWMServoDriver.cpp File Reference

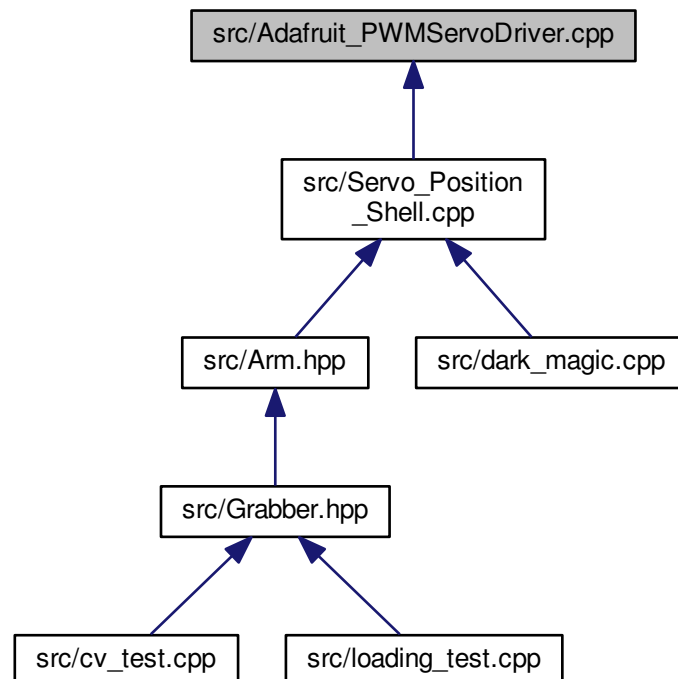
Contains the function and class definitions necessary for the PWM servo driver.

```
#include "Adafruit_PWMServoDriver.h"
```

Include dependency graph for Adafruit_PWMServoDriver.cpp:



This graph shows which files directly or indirectly include this file:



Macros

- `#define ENABLE_DEBUG_OUTPUT false`

6.5.1 Detailed Description

Contains the function and class definitions necessary for the PWM servo driver.

Author

Limor Frief/Ladyada
Nickolas Neely

Definition in file [Adafruit_PWMServoDriver.cpp](#).

6.5.2 Macro Definition Documentation

6.5.2.1 `#define ENABLE_DEBUG_OUTPUT false`

Definition at line 35 of file [Adafruit_PWMServoDriver.cpp](#).

6.6 Adafruit_PWMServoDriver.cpp

```

00001
00009 /* File: Adafruit_PWMServoDriver.cpp
00010  * Credit to Limor Fried/Ladyada for PWM servo driver code.
00011  * Editted by: Nickolas Neely for ChipChipArray Raspberry Pi
00012  */
00013
00014 /*****
00015  This is a library for our Adafruit 16-channel PWM & Servo driver
00016
00017  Pick one up today in the adafruit shop!
00018  -----> http://www.adafruit.com/products/815
00019
00020  These displays use I2C to communicate, 2 pins are required to
00021  interface. For Arduino UNOs, thats SCL -> Analog 5, SDA -> Analog 4
00022
00023  Adafruit invests time and resources providing this open source code,
00024  please support Adafruit and open-source hardware by purchasing
00025  products from Adafruit!
00026
00027  Written by Limor Fried/Ladyada for Adafruit Industries.
00028  BSD license, all text above must be included in any redistribution
00029  *****/
00030
00031 #include "Adafruit_PWMServoDriver.h"
00032
00033
00034 // Set to true to print some debug messages, or false to disable them.
00035 #define ENABLE_DEBUG_OUTPUT false
00036
00037 Adafruit_PWMServoDriver::Adafruit_PWMServoDriver(
00038     uint8_t addr) {
00039     _i2caddr = addr;
00040     _i2cFD = -1;
00041 }
00042 void Adafruit_PWMServoDriver::begin(void) {
00043     _i2cFD = wiringPiI2CSetup(_i2caddr);
00044     if (_i2cFD < 0) {
00045         //FIXME: error occurred
00046     }
00047     reset();
00048 }
00049
00050 void Adafruit_PWMServoDriver::reset(void) {
00051     write8(PC9685_MODEL1, 0x0);
00052 }
00053
00054 void Adafruit_PWMServoDriver::setPWMFreq(float freq) {

```

```

00055     //Serial.print("Attempting to set freq ");
00056     //Serial.println(freq);
00057     freq *= 0.9; // Correct for overshoot in the frequency setting (see issue #11).
00058     float prescaleval = 25000000;
00059     prescaleval /= 4096;
00060     prescaleval /= freq;
00061     prescaleval -= 1;
00062     if (ENABLE_DEBUG_OUTPUT) {
00063         cout << "Estimated pre-scale: " << prescaleval << endl;
00064     }
00065     uint8_t prescale = floor(prescaleval + 0.5);
00066     if (ENABLE_DEBUG_OUTPUT) {
00067         cout << "Final pre-scale: " << prescale << endl;
00068     }
00069
00070     uint8_t oldmode = read8(PCA9685_MODEL);
00071     uint8_t newmode = (oldmode & 0x7F) | 0x10; // sleep
00072     write8(PCA9685_MODEL, newmode); // go to sleep
00073     write8(PCA9685_PRESCALE, prescale); // set the prescaler
00074     write8(PCA9685_MODEL, oldmode);
00075     usleep(5000);
00076     write8(PCA9685_MODEL, oldmode | 0x01); // This sets the MODEL register to turn on auto
    increment.
00077     // This is why the beginTransmission below was not working.
00078     // Serial.print("Mode now 0x"); Serial.println(read8(PCA9685_MODEL), HEX);
00079 }
00080
00081 void Adafruit_PWMServoDriver::setPWM(uint8_t num,
    uint16_t on, uint16_t off) {
00082     //Serial.print("Setting PWM "); Serial.print(num); Serial.print(": "); Serial.print(on);
    Serial.print("->"); Serial.println(off);
00083
00084     int result = wiringPiI2CWriteReg16(_i2cFD, LED0_ON_L + 4 * num, on);
00085     if (result < 0) {
00086         string s(strerror(errno));
00087         cout << "setPWM error: " << s.c_str() << endl;
00088     }
00089     // result = wiringPiI2CWrite(_i2cFD, on);
00090     // if (result < 0) {
00091     //     string s(strerror(errno));
00092     //     cout << "setPWM error: " << s.c_str() << endl;
00093     // }
00094     // result = wiringPiI2CWrite(_i2cFD, on >> 8);
00095     // if (result < 0) {
00096     //     string s(strerror(errno));
00097     //     cout << "setPWM error: " << s.c_str() << endl;
00098     // }
00099     result = wiringPiI2CWriteReg16(_i2cFD, LED0_OFF_L + 4 * num, off);
00100     // result = wiringPiI2CWrite(_i2cFD, off);
00101     if (result < 0) {
00102         string s(strerror(errno));
00103         cout << "setPWM error: " << s.c_str() << endl;
00104     }
00105     // result = wiringPiI2CWrite(_i2cFD, off >> 8);
00106     // if (result < 0) {
00107     //     string s(strerror(errno));
00108     //     cout << "setPWM error: " << s.c_str() << endl;
00109     // }
00110 }
00111
00112 // Sets pin without having to deal with on/off tick placement and properly handles
00113 // a zero value as completely off. Optional invert parameter supports inverting
00114 // the pulse for sinking to ground. Val should be a value from 0 to 4095 inclusive.
00115
00116 void Adafruit_PWMServoDriver::setPin(uint8_t num,
    uint16_t val, bool invert) {
00117     // Clamp value between 0 and 4095 inclusive.
00118     val = min(val, (uint16_t)4095);
00119     if (invert) {
00120         if (val == 0) {
00121             // Special value for signal fully on.
00122             setPWM(num, 4096, 0);
00123         } else if (val == 4095) {
00124             // Special value for signal fully off.
00125             setPWM(num, 0, 4096);
00126         } else {
00127             setPWM(num, 0, 4095 - val);
00128         }
00129     } else {
00130         if (val == 4095) {
00131             // Special value for signal fully on.
00132             setPWM(num, 4096, 0);
00133         } else if (val == 0) {
00134             // Special value for signal fully off.
00135             setPWM(num, 0, 4096);
00136         } else {
00137             setPWM(num, 0, val);

```

```

00138     }
00139   }
00140 }
00141
00142 uint8_t Adafruit_PWMServoDriver::read8(uint8_t addr) {
00143   int result = wiringPiI2CReadReg8(_i2cFD, addr);
00144   if (result < 0) {
00145     string s(strerror(errno));
00146     cout << "Error read8: " << std::dec << (unsigned int)addr << " -> " << s.c_str() << endl;
00147   }
00148   return result;
00149 }
00150
00151 void Adafruit_PWMServoDriver::write8(uint8_t addr, uint8_t d) {
00152   int result = wiringPiI2CWriteReg8(_i2cFD, addr, d);
00153   if (result < 0) {
00154     string s(strerror(errno));
00155     cout << "Error write8: " << std::dec << (unsigned int)addr << " -> " << (unsigned int)d << " -> " <
< s.c_str() << endl;
00156   }
00157 }

```

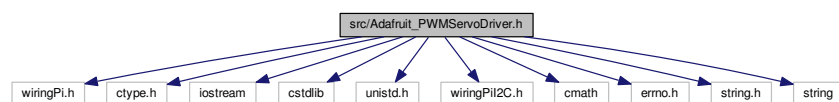
6.7 src/Adafruit_PWMServoDriver.h File Reference

```

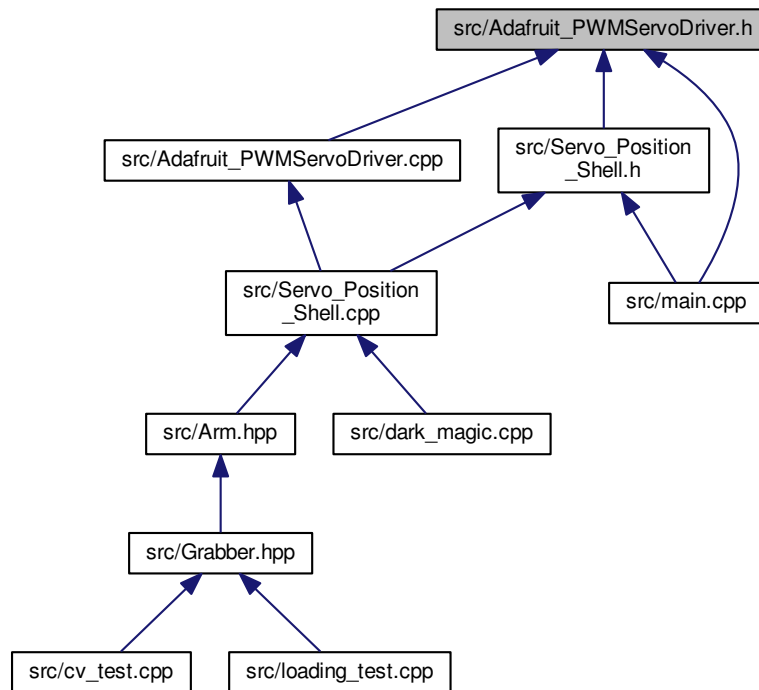
#include <wiringPi.h>
#include <ctype.h>
#include <iostream>
#include <cstdlib>
#include <unistd.h>
#include <wiringPiI2C.h>
#include <cmath>
#include <errno.h>
#include <string.h>
#include <string>

```

Include dependency graph for Adafruit_PWMServoDriver.h:



This graph shows which files directly or indirectly include this file:



Classes

- class [Adafruit_PWMServoDriver](#)

Macros

- #define [PCA9685_SUBADR1](#) 0x2
- #define [PCA9685_SUBADR2](#) 0x3
- #define [PCA9685_SUBADR3](#) 0x4
- #define [PCA9685_MODE1](#) 0x0
- #define [PCA9685_PRESCALE](#) 0xFE
- #define [LED0_ON_L](#) 0x6
- #define [LED0_ON_H](#) 0x7
- #define [LED0_OFF_L](#) 0x8
- #define [LED0_OFF_H](#) 0x9
- #define [ALLLED_ON_L](#) 0xFA
- #define [ALLLED_ON_H](#) 0xFB
- #define [ALLLED_OFF_L](#) 0xFC
- #define [ALLLED_OFF_H](#) 0xFD
- #define [uint8_t](#) unsigned char
- #define [uint16_t](#) unsigned short int

6.7.1 Detailed Description

Author

Limor Fried/Ladyada

Nickolas Neely Contains the function and class headers necessary for the PWM servo driver.

Definition in file [Adafruit_PWMServoDriver.h](#).

6.7.2 Macro Definition Documentation

6.7.2.1 `#define ALLLED_OFF_H 0xFD`

Definition at line 62 of file [Adafruit_PWMServoDriver.h](#).

6.7.2.2 `#define ALLLED_OFF_L 0xFC`

Definition at line 61 of file [Adafruit_PWMServoDriver.h](#).

6.7.2.3 `#define ALLLED_ON_H 0xFB`

Definition at line 60 of file [Adafruit_PWMServoDriver.h](#).

6.7.2.4 `#define ALLLED_ON_L 0xFA`

Definition at line 59 of file [Adafruit_PWMServoDriver.h](#).

6.7.2.5 `#define LED0_OFF_H 0x9`

Definition at line 57 of file [Adafruit_PWMServoDriver.h](#).

6.7.2.6 `#define LED0_OFF_L 0x8`

Definition at line 56 of file [Adafruit_PWMServoDriver.h](#).

6.7.2.7 `#define LED0_ON_H 0x7`

Definition at line 55 of file [Adafruit_PWMServoDriver.h](#).

6.7.2.8 `#define LED0_ON_L 0x6`

Definition at line 54 of file [Adafruit_PWMServoDriver.h](#).

6.7.2.9 `#define PCA9685_MODE1 0x0`

Definition at line 51 of file [Adafruit_PWMServoDriver.h](#).

6.7.2.10 `#define PCA9685_PRESCALE 0xFE`

Definition at line 52 of file [Adafruit_PWMServoDriver.h](#).

6.7.2.11 #define PCA9685_SUBADR1 0x2

Definition at line 47 of file [Adafruit_PWMServoDriver.h](#).

6.7.2.12 #define PCA9685_SUBADR2 0x3

Definition at line 48 of file [Adafruit_PWMServoDriver.h](#).

6.7.2.13 #define PCA9685_SUBADR3 0x4

Definition at line 49 of file [Adafruit_PWMServoDriver.h](#).

6.7.2.14 #define uint16_t unsigned short int

Definition at line 69 of file [Adafruit_PWMServoDriver.h](#).

6.7.2.15 #define uint8_t unsigned char

Definition at line 65 of file [Adafruit_PWMServoDriver.h](#).

6.8 Adafruit_PWMServoDriver.h

```

00001
00009 /* File: Adafruit_PWMServoDriver.h
00010  * Credit to Limor Fried/Ladyada for PWM servo driver code.
00011  * Editted by: Nickolas Neely for ChipChipArray Raspberry Pi
00012  */
00013
00014 /*****
00015  This is a library for our Adafruit 16-channel PWM & Servo driver
00016
00017  Pick one up today in the adafruit shop!
00018  -----> http://www.adafruit.com/products/815
00019
00020  These displays use I2C to communicate, 2 pins are required to
00021  interface. For Arduino UNOs, thats SCL -> Analog 5, SDA -> Analog 4
00022
00023  Adafruit invests time and resources providing this open source code,
00024  please support Adafruit and open-source hardware by purchasing
00025  products from Adafruit!
00026
00027  Written by Limor Fried/Ladyada for Adafruit Industries.
00028  BSD license, all text above must be included in any redistribution
00029  *****/
00030
00031 #ifndef _ADAFRUIT_PWMServoDriver_H
00032 #define _ADAFRUIT_PWMServoDriver_H
00033
00034 #include <wiringPi.h>
00035 #include <ctype.h>
00036 #include <iostream>
00037 #include <cstdlib>
00038 #include <unistd.h>
00039 #include <wiringPiI2C.h>
00040 #include <cmath>
00041 #include <errno.h>
00042 #include <string.h>
00043 #include <string>
00044
00045 using namespace std;
00046
00047 #define PCA9685_SUBADR1 0x2
00048 #define PCA9685_SUBADR2 0x3
00049 #define PCA9685_SUBADR3 0x4
00050
00051 #define PCA9685_MODE1 0x0
00052 #define PCA9685_PRESCALE 0xFE
00053
00054 #define LED0_ON_L 0x6

```

```

00055 #define LED0_ON_H 0x7
00056 #define LED0_OFF_L 0x8
00057 #define LED0_OFF_H 0x9
00058
00059 #define ALLLED_ON_L 0xFA
00060 #define ALLLED_ON_H 0xFB
00061 #define ALLLED_OFF_L 0xFC
00062 #define ALLLED_OFF_H 0xFD
00063
00064 #ifndef uint8_t
00065 #define uint8_t unsigned char
00066 #endif
00067
00068 #ifndef uint16_t
00069 #define uint16_t unsigned short int
00070 #endif
00071
00072
00073 class Adafruit_PWMServoDriver {
00074 public:
00075     Adafruit_PWMServoDriver(uint8_t addr = 0x41);
00076     void begin(void);
00077     void reset(void);
00078     void setPWMFreq(float freq);
00079     void setPWM(uint8_t num, uint16_t on, uint16_t off);
00080     void setPin(uint8_t num, uint16_t val, bool invert=false);
00081
00082 private:
00083     uint8_t _i2caddr;
00084     int _i2cFD;
00085
00086     uint8_t read8(uint8_t addr);
00087     void write8(uint8_t addr, uint8_t d);
00088 };
00089
00090 #endif

```

6.9 src/Arm.hpp File Reference

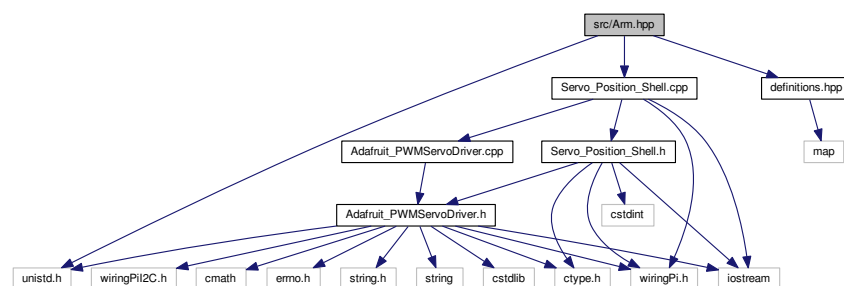
Contains the Arm class used to control the robotic arm.

```

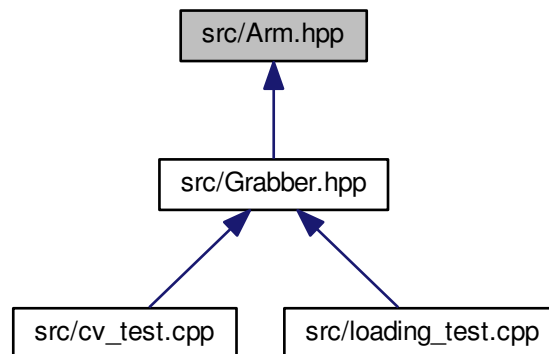
#include <unistd.h>
#include "definitions.hpp"
#include "Servo_Position_Shell.cpp"

```

Include dependency graph for Arm.hpp:



This graph shows which files directly or indirectly include this file:



Classes

- class [ChipChipArray::Arm](#)

Namespaces

- [ChipChipArray](#)

Macros

- `#define` [WRIST_TWIST](#) [WRIST_PAN](#)

6.9.1 Detailed Description

Contains the Arm class used to control the robotic arm.

Author

Samuel Andrew Wisner, awisner94@gmail.com

Definition in file [Arm.hpp](#).

6.9.2 Macro Definition Documentation

6.9.2.1 `#define` [WRIST_TWIST](#) [WRIST_PAN](#)

Definition at line 15 of file [Arm.hpp](#).

6.10 Arm.hpp

00001

```

00007 #ifndef Arm_H
00008 #define Arm_H
00009
00010 #include <unistd.h>
00011
00012 #include "definitions.hpp"
00013 #include "Servo_Position_Shell.cpp"
00014
00015 #define WRIST_TWIST WRIST_PAN
00016
00017 namespace ChipChipArray {
00023     class Arm {
00024     public:
00029         Arm();
00030
00034         uint8 servoPos[7] = { 0, 0, 0, 0, 0, 0, 0 };
00035
00041         void BaseTilt(uint8 a);
00042
00048         void BaseTurn(uint8 a);
00049
00053         void ClawOpen();
00054
00060         void ClawClose();
00061
00068         void dBaseTilt(sint16 a);
00069
00076         void dBaseTurn(sint16 a);
00077
00084         void dElbow(sint16 a);
00085
00092         void dWristTilt(sint16 a);
00093
00100         void dWristTwist(sint16 a);
00101
00107         void Elbow(uint8 a);
00108
00115         void Hover(Zone zone);
00116
00122         void WristTilt(uint8 a);
00123
00129         void WristTwist(uint8 a);
00130
00131     protected:
00132
00139         void dLeftGripper(sint16 a);
00140
00147         void dRightGripper(sint16 a);
00148
00154         void LeftGripper(uint8 a);
00155
00161         void RightGripper(uint8 a);
00162
00163     private:
00168         static bool init;
00169 };
00170
00171 bool Arm::init = false;
00172
00173 Arm::Arm() {
00174     if(!init) {
00175         setup();
00176         init = true;
00177     }
00178 }
00179
00180 void Arm::BaseTilt(uint8 a) {
00181     setServoPosition(BASE_TILT, a);
00182     servoPos[BASE_TILT] = a;
00183 }
00184
00185 void Arm::BaseTurn(uint8 a) {
00186     setServoPosition(BASE_TURN, a);
00187     servoPos[BASE_TURN] = a;
00188 }
00189
00190 void Arm::ClawOpen() {
00191     LeftGripper(0);
00192     RightGripper(180);
00193 }
00194
00195 void Arm::ClawClose() {
00196     LeftGripper(180);
00197     RightGripper(0);
00198 }
00199
00200 void Arm::dBaseTilt(sint16 a) {

```

```

00201     a += servoPos[BASE_TILT];
00202     setServoPosition(BASE_TILT, a);
00203     servoPos[BASE_TILT] = a;
00204 }
00205
00206 void Arm::dBaseTurn(sint16 a) {
00207     a += servoPos[BASE_TURN];
00208     setServoPosition(BASE_TURN, a);
00209     servoPos[BASE_TURN] = a;
00210 }
00211
00212 void Arm::dElbow(sint16 a) {
00213     a += servoPos[ELBOW];
00214     setServoPosition(ELBOW, a);
00215     servoPos[ELBOW] = a;
00216 }
00217
00218 void Arm::dLeftGripper(sint16 a) {
00219     a += servoPos[GRIP_LEFT];
00220     setServoPosition(GRIP_LEFT, a);
00221     servoPos[GRIP_LEFT] = a;
00222 }
00223
00224 void Arm::dRightGripper(sint16 a) {
00225     a += servoPos[GRIP_RIGHT];
00226     setServoPosition(GRIP_RIGHT, a);
00227     servoPos[GRIP_RIGHT] = a;
00228 }
00229
00230 void Arm::dWristTilt(sint16 a) {
00231     a += servoPos[WRIST_TILT];
00232     setServoPosition(WRIST_TILT, a);
00233     servoPos[WRIST_TILT] = a;
00234 }
00235
00236 void Arm::dWristTwist(sint16 a) {
00237     a += servoPos[WRIST_TWIST];
00238     setServoPosition(WRIST_TWIST, a);
00239     servoPos[WRIST_TWIST] = a;
00240 }
00241
00242 void Arm::Elbow(uint8 a) {
00243     setServoPosition(ELBOW, a);
00244     servoPos[ELBOW] = a;
00245 }
00246
00247 void Arm::LeftGripper(uint8 a) {
00248     setServoPosition(GRIP_LEFT, a);
00249     servoPos[GRIP_LEFT] = a;
00250 }
00251
00252 void Arm::RightGripper(uint8 a) {
00253     setServoPosition(GRIP_RIGHT, a);
00254     servoPos[GRIP_RIGHT] = a;
00255 }
00256
00257 void Arm::WristTilt(uint8 a) {
00258     setServoPosition(WRIST_TILT, a);
00259     servoPos[WRIST_TILT] = a;
00260 }
00261
00262 void Arm::WristTwist(uint8 a) {
00263     setServoPosition(WRIST_TWIST, a);
00264     servoPos[WRIST_TWIST] = a;
00265 }
00266 }
00267
00268 #endif

```

6.11 src/Block.hpp File Reference

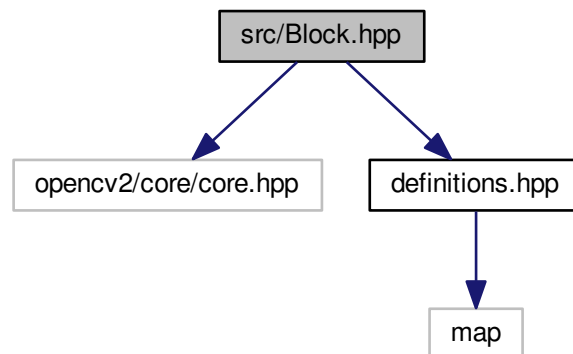
Contains Block class.

```

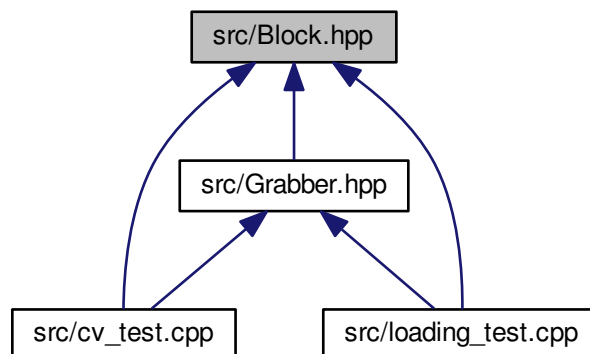
#include <opencv2/core/core.hpp>
#include "definitions.hpp"

```

Include dependency graph for Block.hpp:



This graph shows which files directly or indirectly include this file:



Classes

- class [ChipChipArray::Block](#)

Namespaces

- [ChipChipArray](#)

6.11.1 Detailed Description

Contains Block class.

Author

Samuel Andrew Wisner, awisner94@gmail.com

Definition in file [Block.hpp](#).

6.12 Block.hpp

```

00001
00007 #ifndef Block_H
00008 #define Block_H
00009
00010 #include <opencv2/core/core.hpp>
00011
00012 #include "definitions.hpp"
00013
00014 namespace ChipChipArray {
00020     class Block {
00021     public:
00025         uint32 area;
00026
00030         cv::Point bottomLeft;
00031
00035         cv::Point bottomRight;
00036
00041         sint16 dBottom;
00042
00047         sint16 dLeft;
00048
00053         sint16 dRight;
00054
00059         sint16 dTop;
00060
00067         sint16 dTopBottom;
00068
00075         sint16 dRightLeft;
00076
00082         sint16 offset;
00083
00087         uint16 height;
00088
00092         cv::Point topLeft;
00093
00097         cv::Point topRight;
00098
00102         uint16 width;
00103
00107         Color color;
00108
00112         Size size;
00113
00119         Block(cv::Rect rect, Color color);
00120
00121     private:
00125         static const uint16 IMG_HEIGHT = 1280;
00126
00130         static const uint16 IMG_WIDTH = 720;
00131
00136         static const uint32 MIN_WHOLE_BLOCK_SIZE = 50000;
00137     };
00138
00139     Block::Block(cv::Rect rect, Color color) {
00140         // basic geometric properties
00141         area = rect.area();
00142         height = rect.height;
00143         width = rect.width;
00144
00145         // assigning corners
00146         topLeft = rect.tl();
00147         bottomRight = rect.br();
00148         topRight = cv::Point(topLeft.x + width, topLeft.y);
00149         bottomLeft = cv::Point(topLeft.x, topLeft.y +
height);
00150         offset = (sint16)(topLeft.x + width / 2) - IMG_WIDTH / 2;
00151
00152         // calculating offsets (opencv low coordinates start top left)
00153         dLeft = topLeft.x;
00154         dRight = IMG_WIDTH - topRight.x;
00155         dTop = topLeft.y;
00156         dBottom = IMG_HEIGHT - bottomRight.y;
00157         dTopBottom = dTop - dBottom;
00158         dRightLeft = dRight - dLeft;

```

```

00159
00160         // set color and size
00161         this->color = color;
00162         size = area > MIN_WHOLE_BLOCK_SIZE ? Size::Long :
           Size::Short;
00163     }
00164 }
00165 #endif

```

6.13 src/cv_hue.cpp File Reference

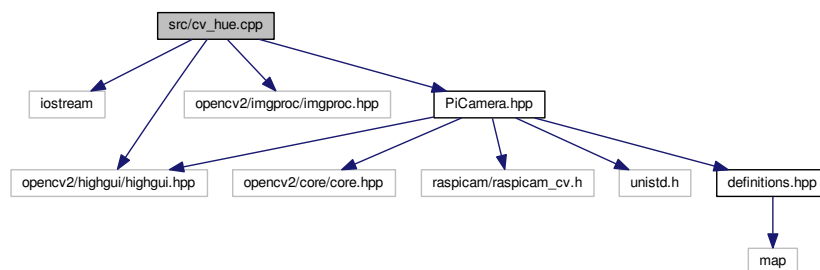
Contains program formally used to find HSV values for blocks.

```

#include <iostream>
#include "opencv2/highgui/highgui.hpp"
#include "opencv2/imgproc/imgproc.hpp"
#include "PiCamera.hpp"

```

Include dependency graph for cv_hue.cpp:



Namespaces

- [ChipChipArray](#)

Functions

- `int ChipChipArray::main (int argc, char **argv)`

6.13.1 Detailed Description

Contains program formally used to find HSV values for blocks.

Author

Shermal Fernando
 Samuel Andrew Wisner, awisner94@gmail.com

Definition in file [cv_hue.cpp](#).

6.14 cv_hue.cpp

```

00001
00008 #include <iostream>

```

```

00009 #include "opencv2/highgui/highgui.hpp"
00010 #include "opencv2/imgproc/imgproc.hpp"
00011
00012 #include "PiCamera.hpp"
00013
00014 using namespace cv;
00015 using namespace std;
00016 using namespace ChipChipArray;
00017
00018 namespace ChipChipArray {
00019
00027 int main( int argc, char** argv ) {
00028     PiCamera cam;
00029     namedWindow("Control", CV_WINDOW_AUTOSIZE); //create a window called "Control"
00030
00031     int iLowH = 170;
00032     int iHighH = 179;
00033
00034     int iLowS = 150;
00035     int iHighS = 255;
00036
00037     int iLowV = 60;
00038     int iHighV = 255;
00039
00040     //Create trackbars in "Control" window
00041     createTrackbar("LowH", "Control", &iLowH, 179); //Hue (0 - 179)
00042     createTrackbar("HighH", "Control", &iHighH, 179);
00043
00044     createTrackbar("LowS", "Control", &iLowS, 255); //Saturation (0 - 255)
00045     createTrackbar("HighS", "Control", &iHighS, 255);
00046
00047     createTrackbar("LowV", "Control", &iLowV, 255); //Value (0 - 255)
00048     createTrackbar("HighV", "Control", &iHighV, 255);
00049
00050     int iLastX = -1;
00051     int iLastY = -1;
00052
00053     //Capture a temporary image from the camera
00054     Mat imgTmp = cam.Snap();
00055
00056     //Create a black image with the size as the camera output
00057     Mat imgLines = Mat::zeros( imgTmp.size(), CV_8UC3 );
00058
00059     while (true)
00060     {
00061         Mat imgOriginal = cam.Snap(); // read a new frame from video
00062         Mat imgHSV;
00063
00064         cvtColor(imgOriginal, imgHSV, COLOR_BGR2HSV); //Convert the captured frame from BGR to HSV
00065
00066         Mat imgThresholded;
00067
00068         inRange(imgHSV, Scalar(iLowH, iLowS, iLowV), Scalar(iHighH, iHighS, iHighV), imgThresholded);
00069         //Threshold the image
00070
00071         //morphological opening (removes small objects from the foreground)
00072         erode(imgThresholded, imgThresholded, getStructuringElement(MORPH_ELLIPSE,
00073             Size(5, 5) ));
00074         dilate( imgThresholded, imgThresholded, getStructuringElement(MORPH_ELLIPSE,
00075             Size(5, 5) ));
00076
00077         //morphological closing (removes small holes from the foreground)
00078         dilate( imgThresholded, imgThresholded, getStructuringElement(MORPH_ELLIPSE,
00079             Size(5, 5) ));
00080         erode(imgThresholded, imgThresholded, getStructuringElement(MORPH_ELLIPSE,
00081             Size(5, 5) ));
00082
00083         //Calculate the moments of the thresholded image
00084         Moments oMoments = moments(imgThresholded);
00085
00086         /*double dM01 = oMoments.m01;
00087         double dM10 = oMoments.m10;
00088         double dArea = oMoments.m00;
00089
00090         // if the area <= 10000, I consider that there are no object in the image and it's because
00091         of the noise, the area is not zero
00092         if (dArea > 50000)
00093         {
00094             //calculate the position of the ball
00095             int posX = dM10 / dArea;
00096             int posY = dM01 / dArea;
00097
00098             if (iLastX >= 0 && iLastY >= 0 && posX >= 0 && posY >= 0)
00099             {
00100                 //Draw a red line from the previous point to the current point
00101                 line(imgLines, Point(posX, posY), Point(iLastX, iLastY), Scalar(0,0,255), 2);
00102             }
00103         }
00104     }

```

```

00097         }
00098
00099         iLastX = posX;
00100         iLastY = posY;
00101     }
00102     */
00103     imshow("Thresholded Image", imgThresholded); //show the thresholded image
00104
00105     //     imgOriginal = imgOriginal + imgLines;
00106     imshow("Original", imgOriginal); //show the original image
00107
00108     if (waitKey(30) == 27) //wait for 'esc' key press for 30ms. If 'esc' key is pressed, break loop
00109     {
00110         cout << "esc key is pressed by user" << endl;
00111         break;
00112     }
00113 }
00114
00115 return 0;
00116 }
00117 }

```

6.15 src/cv_shape.cpp File Reference

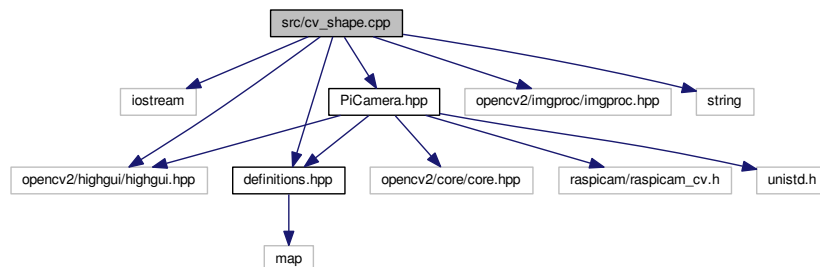
Contains a program to aid in determining HSV ranges.

```

#include <iostream>
#include <opencv2/highgui/highgui.hpp>
#include <opencv2/imgproc/imgproc.hpp>
#include <string>
#include "definitions.hpp"
#include "PiCamera.hpp"

```

Include dependency graph for cv_shape.cpp:



Functions

- int [main](#) ()

6.15.1 Detailed Description

Contains a program to aid in determining HSV ranges.

Author

Shermal Fernando
 Samuel Andrew Wisner, awisner94@gmail.com

Definition in file [cv_shape.cpp](#).

6.15.2 Function Documentation

6.15.2.1 int main ()

This program (a single function) is a test of the computer vision algorithms for loading the blocks. It will likely be in development for some time to come. The plan currently is to develop and test all CV algorithms for block loading here before moving it all into class functions and testing again.

This code is based on several online articles:

- "Color Detectionn & Object Tracking" by Shermal Fernando (<http://opencv-srf.blogspot.com/2010/09/object-detection-using-color-seperation.html>)
- "Shape Detection & Tracking using Contours" by Shermal Fernando (<http://opencv-srf.blogspot.com/2011/09/object-detection-tracking-using-contours.html>)
- "Creating Bounding boxes and circles for contours" in the OpenCV 2.4 Tutorials (<http://opencv-srf.blogspot.com/2011/09/object-detection-tracking-using-contours.html>)

Definition at line 37 of file `cv_shape.cpp`.

```

00037     {
00038         PiCamera cam;
00039
00040         // window names
00041         string control = "Settings";
00042         string winThresh = "Image Threshold";
00043         string winContours = "Contours Detected";
00044
00045         // control (trackbar) variables
00046         int lowH = 0; // hue
00047         int highH = 255;
00048         int lowS = 0; // saturation
00049         int highS = 255;
00050         int lowV = 0; // value
00051         int highV = 255;
00052         int polyEps = 3; // max dif b/t bin shape edge & est poly edge
00053
00054         // opening windows
00055         namedWindow(control, CV_WINDOW_AUTOSIZE);
00056         namedWindow(winThresh, CV_WINDOW_AUTOSIZE);
00057         namedWindow(winContours, CV_WINDOW_AUTOSIZE);
00058
00059         // creating control trackbars
00060         createTrackbar("Hue Min", control, &lowH, highH);
00061         createTrackbar("Hue Max", control, &highH, highH);
00062         createTrackbar("Sat Min", control, &lowS, highS);
00063         createTrackbar("Sat Max", control, &highS, highS);
00064         createTrackbar("Val Min", control, &lowV, highV);
00065         createTrackbar("Val Max", control, &highV, highV);
00066         createTrackbar("Polygon Epsilon", control, &polyEps, 20);
00067
00068         while(true) {
00069             Mat imgOrig = cam.Snap(); // real iage
00070             Mat imgHSV; // RGB image converted to HSV space
00071             Mat imgThresh; // binary threshold image
00072             //cvtColor(imgOrig, imgHSV, CV_BGR2YUV);
00073             //cvtColor(imgHSV, imgOrig, CV_HSV2BGR);
00074             cvtColor(imgOrig, imgHSV, COLOR_BGR2HSV);
00075
00076             // create binary image
00077             inRange(imgHSV, Scalar(lowH, lowS, lowV), Scalar(highH, highS,
00078                 highV), imgThresh);
00079
00080             /*
00081              * Not quite sure what all this does, but it seems to
00082              * relate to smoothing the image
00083              */
00084             erode(imgThresh, imgThresh, getStructuringElement(
00085                 MORPH_ELLIPSE, cv::Size(5, 5)));
00086             dilate(imgThresh, imgThresh, getStructuringElement(
00087                 MORPH_ELLIPSE, cv::Size(5, 5)));
00088             dilate(imgThresh, imgThresh, getStructuringElement(
00089                 MORPH_ELLIPSE, cv::Size(5, 5)));
00090             erode(imgThresh, imgThresh, getStructuringElement(
00091                 MORPH_ELLIPSE, cv::Size(5, 5)));
00092
00093             // show binary image in threshold window

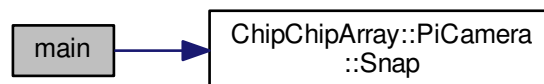
```

```

00094         imshow(winThresh, imgThresh);
00095
00096         // calculate contours
00097         vector<vector<Point>> contours;
00098         findContours(imgThresh, contours, CV_RETR_TREE,
00099                     CV_CHAIN_APPROX_SIMPLE, Point(0, 0));
00100         vector<vector<Point>> contours_poly(contours.size());
00101         vector<Rect> bounds(contours.size());
00102         int maxArea = 0;
00103         int offset;
00104
00105         // find rectangle around polygon-ish shapes
00106         for(int i = 0; i < contours.size(); i++) {
00107             approxPolyDP(Mat(contours[i]), contours_poly[i],
00108                           polyEps, false);
00109             bounds[i] = boundingRect(Mat(contours_poly[i]));
00110         }
00111
00112         /*
00113          * Draw surrounding rectangles from above on original
00114          * image.
00115          */
00116         for(int i = 0; i < contours.size(); i++) {
00117             rectangle(imgOrig, bounds[i].tl(), bounds[i].br(),
00118                      Scalar(255, 0, 0), 2, 8, 0);
00119             //drawContours(imgOrig, contours_poly, i,
00120                          // Scalar(255, 0, 0), 4, 8);
00121             int area = bounds[i].width * bounds[i].height;
00122
00123             if(area > maxArea) {
00124                 offset = abs(640 - (bounds[i].tl().x + bounds[i].width / 2));
00125                 maxArea = area;
00126             }
00127         }
00128
00129         cout << "Block area: " << maxArea << " pixels\t\t"
00130              << "Center offset: " << offset << endl;
00131         imshow(winContours, imgOrig); // show original image with rectangles
00132         waitKey(50); // has to be here :(
00133     }
00134 }

```

Here is the call graph for this function:



6.16 cv_shape.cpp

```

00001
00008 #include <iostream>
00009 #include <opencv2/highgui/highgui.hpp>
00010 #include <opencv2/imgproc/imgproc.hpp>
00011 #include <string>
00012
00013 #include "definitions.hpp"
00014 #include "PiCamera.hpp"
00015
00016 using namespace ChipChipArray;
00017 using namespace cv;
00018 using namespace std;
00019
00037 int main() {
00038     PiCamera cam;
00039
00040     // window names
00041     string control = "Settings";
00042     string winThresh = "Image Threshold";

```

```

00043     string winContours = "Contours Detected";
00044
00045     // control (trackbar) variables
00046     int lowH = 0; // hue
00047     int highH = 255;
00048     int lowS = 0; // saturation
00049     int highS = 255;
00050     int lowV = 0; // value
00051     int highV = 255;
00052     int polyEps = 3; // max dif b/t bin shape edge & est poly edge
00053
00054     // opening windows
00055     namedWindow(control, CV_WINDOW_AUTOSIZE);
00056     namedWindow(winThresh, CV_WINDOW_AUTOSIZE);
00057     namedWindow(winContours, CV_WINDOW_AUTOSIZE);
00058
00059     // creating control trackbars
00060     createTrackbar("Hue Min", control, &lowH, highH);
00061     createTrackbar("Hue Max", control, &highH, highH);
00062     createTrackbar("Sat Min", control, &lowS, highS);
00063     createTrackbar("Sat Max", control, &highS, highS);
00064     createTrackbar("Val Min", control, &lowV, highV);
00065     createTrackbar("Val Max", control, &highV, highV);
00066     createTrackbar("Polygon Epsilon", control, &polyEps, 20);
00067
00068     while(true) {
00069         Mat imgOrig = cam.Snap(); // real iage
00070         Mat imgHSV; // RGB image converted to HSV space
00071         Mat imgThresh; // binary threshold image
00072         //cvtColor(imgOrig, imgHSV, CV_BGR2YUV);
00073         //cvtColor(imgHSV, imgOrig, CV_HSV2BGR);
00074         cvtColor(imgOrig, imgHSV, COLOR_BGR2HSV);
00075
00076         // create binary image
00077         inRange(imgHSV, Scalar(lowH, lowS, lowV), Scalar(highH, highS,
00078             highV), imgThresh);
00079
00080         /*
00081          * Not quite sure what all this does, but it seems to
00082          * relate to smoothing the image
00083          */
00084         erode(imgThresh, imgThresh, getStructuringElement(
00085             MORPH_ELLIPSE, cv::Size(5, 5)));
00086         dilate(imgThresh, imgThresh, getStructuringElement(
00087             MORPH_ELLIPSE, cv::Size(5, 5)));
00088         dilate(imgThresh, imgThresh, getStructuringElement(
00089             MORPH_ELLIPSE, cv::Size(5, 5)));
00090         erode(imgThresh, imgThresh, getStructuringElement(
00091             MORPH_ELLIPSE, cv::Size(5, 5)));
00092
00093         // show binary image in threshold window
00094         imshow(winThresh, imgThresh);
00095
00096         // calculate contours
00097         vector<vector<Point>> contours;
00098         findContours(imgThresh, contours, CV_RETR_TREE,
00099             CV_CHAIN_APPROX_SIMPLE, Point(0, 0));
00100         vector<vector<Point>> contours_poly(contours.size());
00101         vector<Rect> bounds(contours.size());
00102         int maxArea = 0;
00103         int offset;
00104
00105         // find rectangle around polygon-ish shapes
00106         for(int i = 0; i < contours.size(); i++) {
00107             approxPolyDP(Mat(contours[i]), contours_poly[i],
00108                 polyEps, false);
00109             bounds[i] = boundingRect(Mat(contours_poly[i]));
00110         }
00111
00112         /*
00113          * Draw surrounding rectangles from above on original
00114          * image.
00115          */
00116         for(int i = 0; i < contours.size(); i++) {
00117             rectangle(imgOrig, bounds[i].tl(), bounds[i].br(),
00118                 Scalar(255, 0, 0), 2, 8, 0);
00119             //drawContours(imgOrig, contours_poly, i,
00120                 // Scalar(255, 0, 0), 4, 8);
00121             int area = bounds[i].width * bounds[i].height;
00122
00123             if(area > maxArea) {
00124                 offset = abs(640 - (bounds[i].tl().x + bounds[i].width / 2));
00125                 maxArea = area;
00126             }
00127         }
00128
00129         cout << "Block area: " << maxArea << " pixels\t\t"

```

```

00130         << "Center offset: " << offset << endl;
00131         imshow(winContours, imgOrig); // show original image with rectangles
00132         waitKey(50); // has to be here :(
00133     }
00134 }

```

6.17 src/cv_test.cpp File Reference

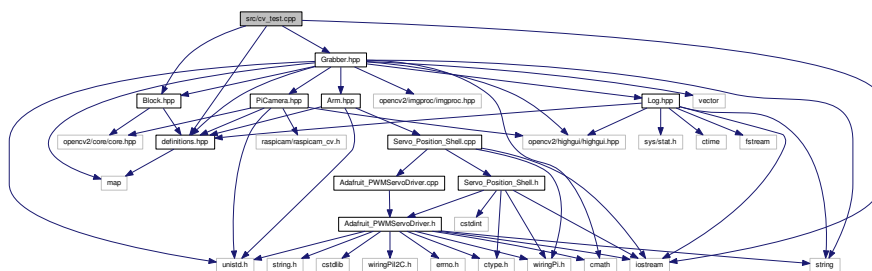
Contains program used to test PiCamera class.

```

#include <iostream>
#include "definitions.hpp"
#include "Block.hpp"
#include "Grabber.hpp"

```

Include dependency graph for cv_test.cpp:



Functions

- `int main ()`

6.17.1 Detailed Description

Contains program used to test PiCamera class.

Author

Samuel Andrew Wisner, awisner94@gmail.com

Definition in file [cv_test.cpp](#).

6.17.2 Function Documentation

6.17.2.1 `int main ()`

This program was used solely to test the PiCamera wrapper class and its compatibility with the raspicam wrapper and ultimately OpenCV.

Definition at line 19 of file [cv_test.cpp](#).

```

00019     {
00020         Grabber g(Zone::C, Side::Left);
00021         Block block = g.LocateBlock();
00022         g.Close();
00023         std::cout << std::to_string(block.color) << std::endl;
00024         std::cout << "Offset: " << block.offset << std::endl;
00025     }
00026     Grabber g2(Zone::B, Side::Right);

```

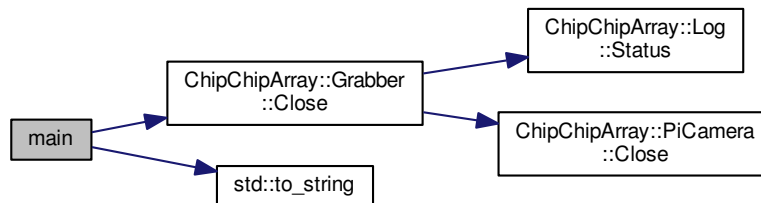


```

00027     Block block2 = g2.LocateBlock();
00028     g2.Close();
00029     std::cout << std::to_string(block2.color) << std::endl;
00030     std::cout << "Offset: " << block2.offset << std::endl;
00031
00032 }

```

Here is the call graph for this function:



6.18 cv_test.cpp

```

00001
00007 #include <iostream>
00008
00009 #include "definitions.hpp"
00010 #include "Block.hpp"
00011 #include "Grabber.hpp"
00012
00013 using namespace ChipChipArray;
00014
00019 int main() {
00020     Grabber g(Zone::C, Side::Left);
00021     Block block = g.LocateBlock();
00022     g.Close();
00023     std::cout << std::to_string(block.color) << std::endl;
00024     std::cout << "Offset: " << block.offset << std::endl;
00025
00026     Grabber g2(Zone::B, Side::Right);
00027     Block block2 = g2.LocateBlock();
00028     g2.Close();
00029     std::cout << std::to_string(block2.color) << std::endl;
00030     std::cout << "Offset: " << block2.offset << std::endl;
00031
00032 }

```

6.19 src/dark_magic.cpp File Reference

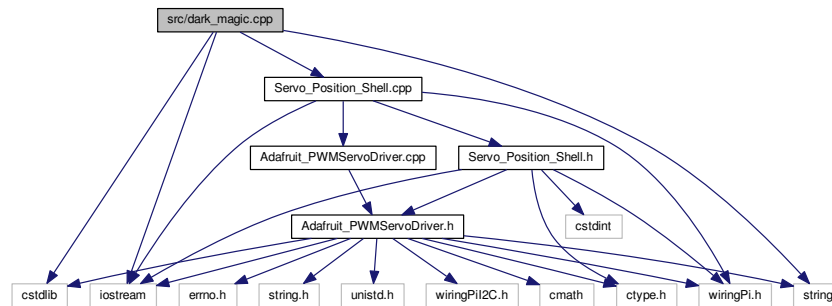
Contains test code for arm.

```

#include <cstdlib>
#include <iostream>
#include <string>
#include "Servo_Position_Shell.cpp"

```

Include dependency graph for `dark_magic.cpp`:



Functions

- `int main (int argc, char **argv)`

6.19.1 Detailed Description

Contains test code for arm.

Author

Samuel Andrew Wisner, awisner94@gmail.com

Definition in file [dark_magic.cpp](#).

6.19.2 Function Documentation

6.19.2.1 `int main (int argc, char ** argv)`

Controls the positions of the arm servos. Will likely work for other servos on the robot, as well.

Usage: `arm [SERVO NUMBER] [ANGULAR POSITION DEGREES]`

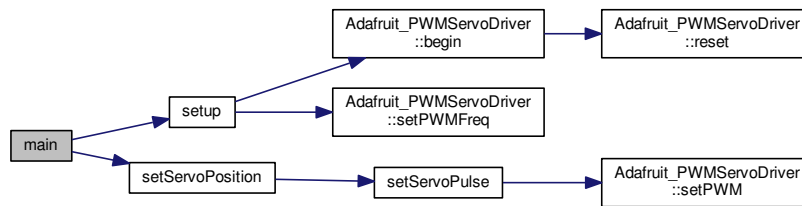
Definition at line 21 of file [dark_magic.cpp](#).

```

00021                                     {
00022     setup();
00023
00024     if(argc != 3) {
00025         cout << "Usage: arm [SERVO] [VALUE]" << endl;
00026     } else {
00027         setServoPosition((Servo)atoi(argv[1]), atoi(argv[2]));
00028     }
00029 }

```

Here is the call graph for this function:



6.20 dark_magic.cpp

```

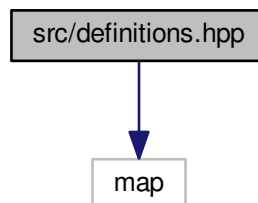
00001
00007 #include <cstdlib>
00008 #include <iostream>
00009 #include <string>
00010
00011 #include "Servo_Position_Shell.cpp"
00012
00013 using namespace std;
00014
00021 int main(int argc, char** argv) {
00022     setup();
00023
00024     if(argc != 3) {
00025         cout << "Usage: arm [SERVO] [VALUE]" << endl;
00026     } else {
00027         setServoPosition((Servo)atoi(argv[1]), atoi(argv[2]));
00028     }
00029 }
  
```

6.21 src/definitions.hpp File Reference

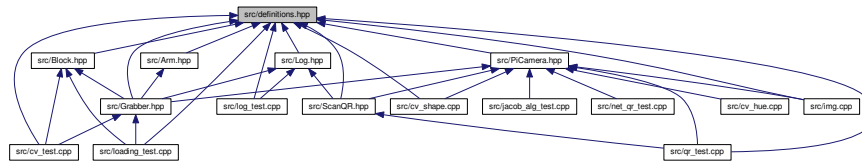
Contains definitions for architecture-independant numeric variables, enumerations and enumerated classes, and #define'd constants, and to_string() overloads for the enumerated classes.

```
#include <map>
```

Include dependency graph for definitions.hpp:



This graph shows which files directly or indirectly include this file:



Namespaces

- [std](#)

Macros

- `#define` [ENUM](#) signed char
- `#define` [ERROR](#) -1

Typedefs

- typedef unsigned char [byte](#)
- typedef unsigned char [uint8](#)
- typedef signed char [sint8](#)
- typedef unsigned short [uint16](#)
- typedef signed short [sint16](#)
- typedef unsigned int [uint32](#)
- typedef signed int [sint32](#)
- typedef unsigned long long [uint64](#)
- typedef signed long long [sint64](#)
- typedef float [float32](#)
- typedef double [float64](#)
- typedef std::map< [Zone](#), std::map< [BlockPosition](#), [uint8](#) > > [PosMap](#)

Enumerations

- enum [BlockPosition](#) : ENUM { [BlockPosition::Front](#), [BlockPosition::Back](#), [BlockPosition::Middle](#) }
- enum [Color](#) : ENUM { [Color::Red](#), [Color::Yellow](#), [Color::Green](#), [Color::Blue](#), [Color::Perrywinkle](#) }
- enum [Layer](#) : ENUM { [Layer::Top](#), [Layer::Bottom](#) }
- enum [LogMode](#) : ENUM { [LogMode::Text](#), [LogMode::Multi](#) }
- enum [Result](#) : ENUM { [Result::NoBlocks](#) = -1, [Result::NoHalves](#) = 0, [Result::TwoHalves](#) = 2, [Result::FourHalves](#) = 4 }
- enum [Side](#) : ENUM { [Side::Left](#), [Side::Right](#) }
- enum [Size](#) : ENUM { [Size::Short](#), [Size::Long](#) }
- enum [Zone](#) : ENUM { [Zone::A](#) = 'A', [Zone::B](#) = 'B', [Zone::C](#) = 'C' }

Functions

- string [std::to_string](#) ([BlockPosition](#) pos)
- string [std::to_string](#) ([Color](#) color)
- string [std::to_string](#) ([LogMode](#) mode)
- string [std::to_string](#) ([Result](#) res)
- string [std::to_string](#) ([Side](#) side)
- string [std::to_string](#) ([Size](#) size)
- string [std::to_string](#) ([Zone](#) zone)

6.21.1 Detailed Description

Contains definitions for architecture-independant numeric variables, enumerations and enumerated classes, and #define'd constants, and to_sting() overloads for the enumerated classes.

Author

Samuel Andrew Wisner, awisner94@gmail.com

Definition in file [definitions.hpp](#).

6.21.2 Macro Definition Documentation

6.21.2.1 #define ENUM signed char

Definition at line 12 of file [definitions.hpp](#).

6.21.2.2 #define ERROR -1

Definition at line 13 of file [definitions.hpp](#).

6.21.3 Typedef Documentation

6.21.3.1 typedef unsigned char byte

Definition at line 17 of file [definitions.hpp](#).

6.21.3.2 typedef float float32

Definition at line 30 of file [definitions.hpp](#).

6.21.3.3 typedef double float64

Definition at line 31 of file [definitions.hpp](#).

6.21.3.4 typedef std::map<Zone, std::map<BlockPosition, uint8> > PosMap

Definition at line 101 of file [definitions.hpp](#).

6.21.3.5 typedef signed short sint16

Definition at line 22 of file [definitions.hpp](#).

6.21.3.6 typedef signed int sint32

Definition at line 25 of file [definitions.hpp](#).

6.21.3.7 typedef signed long long sint64

Definition at line 28 of file [definitions.hpp](#).

6.21.3.8 typedef signed char sint8

Definition at line 19 of file [definitions.hpp](#).

6.21.3.9 typedef unsigned short uint16

Definition at line 21 of file [definitions.hpp](#).

6.21.3.10 typedef unsigned int uint32

Definition at line 24 of file [definitions.hpp](#).

6.21.3.11 typedef unsigned long long uint64

Definition at line 27 of file [definitions.hpp](#).

6.21.3.12 typedef unsigned char uint8

Definition at line 18 of file [definitions.hpp](#).

6.21.4 Enumeration Type Documentation

6.21.4.1 enum BlockPosition : ENUM [strong]

The position of the block relative to the arm.

Enumerator

Front

Back

Middle

Definition at line 37 of file [definitions.hpp](#).

```
00037                                     : ENUM {
00038     Front,
00039     Back,
00040     Middle
00041 };
```

6.21.4.2 enum Color : ENUM [strong]

The color of a block or train car. Perrywinkle represents all colors.

Enumerator

Red

Yellow

Green

Blue

Perrywinkle

Definition at line 46 of file [definitions.hpp](#).

```
00046           : ENUM {
00047     Red,
00048     Yellow,
00049     Green,
00050     Blue,
00051     Perrywinkle // essentially, no color
00052 };
```

6.21.4.3 enum Layer : ENUM [strong]

Defines the location of a block in its stack.

Enumerator

Top

Bottom

Definition at line 57 of file [definitions.hpp](#).

```
00057           : ENUM {
00058     Top,
00059     Bottom
00060 };
```

6.21.4.4 enum LogMode : ENUM [strong]

The mode in which the Log should prepare (i.e., text only or text and images).

Enumerator

Text

Multi

Definition at line 66 of file [definitions.hpp](#).

```
00066           : ENUM {
00067     Text,
00068     Multi
00069 };
```

6.21.4.5 enum Result : ENUM [strong]

The number of half blocks picked up in a stack. The integer value of the

Enumerator

NoBlocks

NoHalves

TwoHalves

FourHalves

Definition at line 75 of file [definitions.hpp](#).

```
00075      : ENUM {
00076      NoBlocks = -1,
00077      NoHalves = 0,
00078      TwoHalves = 2,
00079      FourHalves = 4
00080 };
```

6.21.4.6 enum Side : ENUM [strong]

Represents which block to pick up when multiple blocks are visible.

Enumerator

Left

Right

Definition at line 83 of file [definitions.hpp](#).

```
00083      : ENUM {
00084      Left,
00085      Right
00086 };
```

6.21.4.7 enum Size : ENUM [strong]

The block size, either 2.5" or 5".

Enumerator

Short

Long

Definition at line 89 of file [definitions.hpp](#).

```
00089      : ENUM {
00090      Short,
00091      Long
00092 };
```

6.21.4.8 enum Zone : ENUM [strong]

Zone A, B, or C

Enumerator

A

B**C**Definition at line 95 of file [definitions.hpp](#).

```

00095             : ENUM {
00096     A = 'A',
00097     B = 'B',
00098     C = 'C'
00099 };

```

6.22 definitions.hpp

```

00001
00009 #ifndef definitions_H
00010 #define definitions_H
00011
00012 #define ENUM signed char
00013 #define ERROR -1
00014
00015 #include <map>
00016
00017 typedef unsigned char byte;
00018 typedef unsigned char uint8;
00019 typedef signed char sint8;
00020
00021 typedef unsigned short uint16;
00022 typedef signed short sint16;
00023
00024 typedef unsigned int uint32;
00025 typedef signed int sint32;
00026
00027 typedef unsigned long long uint64;
00028 typedef signed long long sint64;
00029
00030 typedef float float32;
00031 typedef double float64;
00032
00033
00037 enum class BlockPosition : ENUM {
00038     Front,
00039     Back,
00040     Middle
00041 };
00042
00046 enum class Color : ENUM {
00047     Red,
00048     Yellow,
00049     Green,
00050     Blue,
00051     Perrywinkle // essentially, no color
00052 };
00053
00057 enum class Layer : ENUM {
00058     Top,
00059     Bottom
00060 };
00061
00066 enum class LogMode : ENUM {
00067     Text,
00068     Multi
00069 };
00070
00075 enum class Result : ENUM {
00076     NoBlocks = -1,
00077     NoHalves = 0,
00078     TwoHalves = 2,
00079     FourHalves = 4
00080 };
00081
00083 enum class Side : ENUM {
00084     Left,
00085     Right
00086 };
00087
00089 enum class Size : ENUM {
00090     Short,
00091     Long
00092 };
00093

```

```

00095 enum class Zone : ENUM {
00096     A = 'A',
00097     B = 'B',
00098     C = 'C'
00099 };
00100
00101 typedef std::map<Zone, std::map<BlockPosition, uint8>> PosMap;
00102
00103 namespace std {
00104     string to_string(BlockPosition pos) {
00105         if(pos == BlockPosition::Front) return string("Front");
00106         else return string("Back");
00107     }
00108
00109     string to_string(Color color) {
00110         string ret;
00111
00112         switch((ENUM)color) {
00113             case 0:
00114                 ret = "Red";
00115                 break;
00116
00117             case 1:
00118                 ret = "Yellow";
00119                 break;
00120
00121             case 2:
00122                 ret = "Green";
00123                 break;
00124
00125             case 3:
00126                 ret = "Blue";
00127                 break;
00128
00129             case 4:
00130                 ret = "All";
00131                 break;
00132         }
00133
00134         return ret;
00135     }
00136
00137     string to_string(LogMode mode) {
00138         if(mode == LogMode::Multi) return string("Text");
00139         else return string("Multi");
00140     }
00141
00142     string to_string(Result res) {
00143         string ret;
00144
00145         switch((ENUM)res) {
00146             case -1:
00147                 ret = "No Blocks";
00148                 break;
00149
00150             case 0:
00151                 ret = "Two whole, no halves";
00152                 break;
00153
00154             case 2:
00155                 ret = "Two whole, two halves";
00156                 break;
00157
00158             case 4:
00159                 ret = "No whole, four halves";
00160                 break;
00161         }
00162
00163         return ret;
00164     }
00165
00166     string to_string(Side side) {
00167         if(side == Side::Left) return string("Left");
00168         else return string("Right");
00169     }
00170
00171     string to_string(Size size) {
00172         if(size == Size::Long) return string("Long");
00173         else return string("Short");
00174     }
00175
00176     string to_string(Zone zone) {
00177         return string(1, (char)zone);
00178     }
00179 }
00180
00181 // OTHER FILES

```

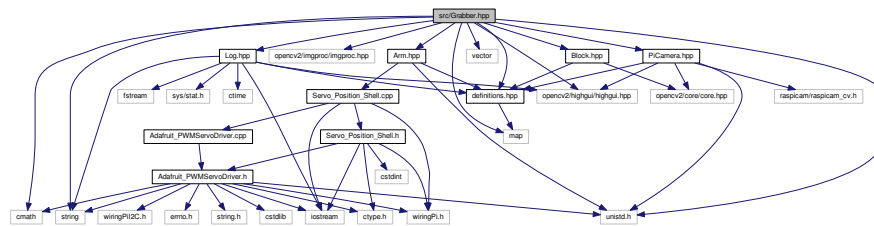
```
00203
00223 #endif
```

6.23 src/Grabber.hpp File Reference

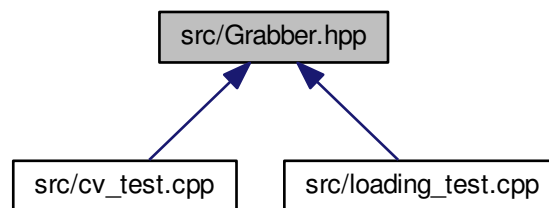
Contains the Grabber class.

```
#include <cmath>
#include <map>
#include <opencv2/highgui/highgui.hpp>
#include <opencv2/imgproc/imgproc.hpp>
#include <string>
#include <unistd.h>
#include <vector>
#include "Arm.hpp"
#include "definitions.hpp"
#include "Block.hpp"
#include "Log.hpp"
#include "PiCamera.hpp"
```

Include dependency graph for Grabber.hpp:



This graph shows which files directly or indirectly include this file:



Classes

- class [ChipChipArray::Grabber](#)

Namespaces

- [ChipChipArray](#)

6.23.1 Detailed Description

Contains the Grabber class.

Author

Samuel Andrew Wisner, awisner94@gmail.com

Definition in file [Grabber.hpp](#).

6.24 Grabber.hpp

```

00001
00007 #ifndef Grabber_H
00008 #define Grabber_H
00009
00010 #include <cmath>
00011 #include <map>
00012 #include <opencv2/highgui/highgui.hpp>
00013 #include <opencv2/imgproc/imgproc.hpp>
00014 #include <string>
00015 #include <unistd.h>
00016 #include <vector>
00017
00018 #include "Arm.hpp"
00019 #include "definitions.hpp"
00020 #include "Block.hpp"
00021 #include "Log.hpp"
00022 #include "PiCamera.hpp"
00023
00024 namespace ChipChipArray {
00025
00030     class Grabber {
00031     public:
00043         Grabber(Zone zone, Side side);
00044
00049         void Close();
00050
00051
00058         Result Load();
00059
00060     protected:
00064         PiCamera cam;
00065
00071         Side side;
00072
00076         Zone zone;
00077
00081         void Deposit(Color color = Color::Blue);
00082
00087         void Extend();
00088
00099         Block LocateBlocks(Color color =
Color::Perrywinkle);
00100
00106         Block LocateBlueBlock();
00107
00108     private:
00112         static const uint32 MIN_HALF_BLOCK_SIZE = 50000;
00113
00118         static Log log;
00119
00124         uint8 invokeCount = 0;
00125
00130         std::map<Color, std::array<cv::Scalar, 2>> rangeVals;
00131
00135         Arm arm;
00136     };
00137
00141     Log Grabber::log("logs/Grabber", LogMode::Multi);
00142
00143     Grabber::Grabber(Zone zone, Side side) {
00144         log.Status("Opening Grabber");
00145         log.Verbose("Zone: " + std::to_string(zone));
00146         log.Verbose("Side: " + std::to_string(side));
00147
00148         this->zone = zone;
00149         this->side = side;
00150
00151         log.Verbose("Setting HSV threshold values");

```

```

00152
00153     rangeVals[Color::Red] = { cv::Scalar(0, 20, 60),
00154         cv::Scalar(12, 255, 255) };
00155     rangeVals[Color::Green] = { cv::Scalar(49, 41, 17),
00156         cv::Scalar(63, 255, 255) };
00157     rangeVals[Color::Blue] = { cv::Scalar(70, 0, 0),
00158         cv::Scalar(100, 255, 255) };
00159
00160     /* Remember, we're only pretending this color's image is in HSV space.
00161     * It's really in YUV, as required by Jacob yellow-detection algorithm. */
00162     rangeVals[Color::Yellow] = { cv::Scalar(0, 0, 0),
00163         cv::Scalar(255, 255, 20) };
00164 }
00165
00166 void Grabber::Close() {
00167     log.Status("Closing Grabber");
00168     cam.Close();
00169 }
00170
00171 void Grabber::Deposit(Color color) {
00172     if(color == Color::Blue) {
00173         arm.ClawClose();
00174         sleep(1);
00175         arm.BaseTilt(160);
00176         sleep(1);
00177         arm.Elbow(130);
00178         sleep(1);
00179         arm.BaseTurn(47);
00180         sleep(1);
00181         arm.ClawOpen();
00182         sleep(1);
00183     } else {
00184         throw std::runtime_error("Du Idiot! Die Armbewegungen für diese "
00185             "Farbe sind noch nicht implementiert. Vielleicht sollst "
00186             "du die englische Phrase lernen 'Would you like fries "
00187             "with that?");
00188     }
00189 }
00190
00191 void Grabber::Extend() {
00192     arm.Elbow(180);
00193     usleep(500000);
00194     arm.BaseTurn(132);
00195     arm.BaseTilt(125);
00196     arm.Elbow(150);
00197     arm.WristTwist(90);
00198     arm.ClawOpen();
00199     sleep(2);
00200 }
00201
00202 Result Grabber::Load() {
00203     for(uint8 i = 0; i < 2; i++) {
00204         Extend();
00205
00206         try {
00207             Block block = (zone == Zone::A
00208                 ? LocateBlocks(Color::Blue) :
00209                 LocateBlueBlock());
00210
00211             float32 baseKonstant = 0.5;
00212             if(block.dRightLeft > 0) baseKonstant *= -1;
00213             float32 degree = baseKonstant * std::sqrt(block.
00214                 dRightLeft);
00215             arm.dBaseTurn(degree);
00216             arm.dWristTwist(-degree);
00217             sleep(1);
00218             arm.BaseTilt(140);
00219             sleep(1);
00220
00221             uint8 bend = (i == 0 ? 100 : 90);
00222
00223             // lower claw over block
00224             for(uint8 j = 140; j >= bend; j -= 10) {
00225                 arm.Elbow(j);
00226                 sleep(1);
00227             }
00228
00229             // deposit in bin
00230             sleep(1);
00231             Deposit();
00232         } catch(std::exception ex) {
00233             log.Error(std::string("An exception occurred attempting "
00234                 "to load the blocks in function Grabber::Load(): ")
00235                 + ex.what());
00236         }
00237     }
00238 }

```

```

00237         if(i == 0) {
00238             arm.BaseTurn(132);
00239         } else {
00240             arm.BaseTurn(135);
00241             sleep(1);
00242             arm.BaseTilt(180);
00243             sleep(1);
00244             arm.Elbow(90);
00245             sleep(1);
00246             arm.Elbow(45);
00247             sleep(1);
00248             arm.Elbow(0);
00249         }
00250     }
00251 }
00252
00253
00254 Block Grabber::LocateBlocks(Color color) {
00255     invokeCount++;
00256     std::string logstr = "Locating blocks";
00257
00258     if(color == Color::Perrywinkle) {
00259         logstr += " (" + std::to_string(color) + ")";
00260     }
00261
00262     log.Verbose(logstr);
00263
00264     cv::Mat imgOrig;
00265     cv::transpose(cam.Snap(), imgOrig);
00266
00267     cv::Mat imgHSV;
00268     cv::Mat imgThresh;
00269     std::vector<cv::Rect> blocks;
00270     std::vector<Color> colors;
00271
00272     uint8 loopNum = (color == Color::Perrywinkle ? rangeVals.size() : 1);
00273
00274     for(int i = 0; i < loopNum; i++) {
00275         if(loopNum > 1) {
00276             switch(i) {
00277                 case 0:
00278                     color = Color::Red;
00279                     break;
00280
00281                 case 1:
00282                     color = Color::Green;
00283                     break;
00284
00285                 case 2:
00286                     color = Color::Blue;
00287                     break;
00288
00289                 /* Must be last, because it changes imgHSV from HSV space
00290                  * to YUV space. */
00291                 case 3:
00292                     color = Color::Yellow;
00293                     break;
00294             }
00295         }
00296
00297         log.Verbose("Searching: " + std::to_string(color));
00298
00299         if(color == Color::Yellow) {
00300             cv::Mat temp;
00301             imgOrig.copyTo(temp);
00302             cv::cvtColor(imgOrig, imgHSV, CV_BGR2YUV);
00303             cv::cvtColor(imgHSV, temp, CV_HSV2BGR);
00304             cv::cvtColor(temp, imgHSV, cv::COLOR_BGR2HSV);
00305             log.Image(temp, "yuv_yellow_" + std::to_string(color)
00306                     + "_" + std::to_string(zone)
00307                     + std::to_string(invokeCount)
00308                     + ".bmp");
00309         } else {
00310             cv::cvtColor(imgOrig, imgHSV, cv::COLOR_BGR2HSV);
00311         }
00312
00313         cv::inRange(imgHSV, rangeVals[color][0],
00314                   rangeVals[color][1], imgThresh);
00315
00316         /*
00317          * Not quite sure what all this does, but it seems to
00318          * relate to smoothing the image
00319          */
00320         cv::erode(imgThresh, imgThresh,
00321                  cv::getStructuringElement(
00322                      cv::MORPH_ELLIPSE,
00323                      cv::Size(5, 5)));
00324     }

```

```

00324         cv::dilate(imgThresh, imgThresh,
00325                     cv::getStructuringElement(
00326                         cv::MORPH_ELLIPSE,
00327                         cv::Size(5, 5)));
00328         cv::dilate(imgThresh, imgThresh,
00329                     cv::getStructuringElement(
00330                         cv::MORPH_ELLIPSE,
00331                         cv::Size(5, 5)));
00332         cv::erode(imgThresh, imgThresh,
00333                   cv::getStructuringElement(
00334                       cv::MORPH_ELLIPSE,
00335                       cv::Size(5, 5)));
00336
00337         log.Image(imgThresh, "thresh_" + std::to_string(color)
00338                  + "_" + std::to_string(zone)
00339                  + std::to_string(invokeCount)
00340                  + ".bmp");
00341
00342         // calculate contours
00343         std::vector<std::vector<cv::Point>> contours;
00344         cv::findContours(imgThresh, contours, CV_RETR_TREE,
00345                         CV_CHAIN_APPROX_SIMPLE,
00346                         cv::Point(0, 0));
00347         std::vector<std::vector<cv::Point>>
00348             contours_poly(contours.size());
00349         std::vector<cv::Rect> bounds(contours.size());
00350
00351         // find rectangle around polygon-ish shapes
00352         for(int i = 0; i < contours.size(); i++) {
00353             uint32 area = cv::contourArea(contours[i]);
00354
00355             // determine if block and add to blocks vector
00356             if(area > MIN_HALF_BLOCK_SIZE) {
00357                 cv::approxPolyDP(cv::Mat(contours[i]),
00358                                 contours_poly[i], 20,
00359                                 false);
00360                 cv::Rect rect = cv::boundingRect(
00361                     cv::Mat(contours_poly[i]));
00362                 log.Debug(std::to_string(color)
00363                          + " block detected "
00364                          + "with area "
00365                          + std::to_string(
00366                              area));
00367                 blocks.push_back(rect);
00368                 colors.push_back(color);
00369             }
00370         }
00371     }
00372
00373     if(blocks.size() == 0) {
00374         log.Image(imgOrig, "original_" + std::to_string(
zone)
00375                  + std::to_string(invokeCount)
00376                  + "_no_blocks.bmp");
00377         throw std::runtime_error("No blocks found!");
00378     } else {
00379         log.Status(std::to_string(blocks.size())
00380                  + " blocks found");
00381     }
00382
00383     // coordinates start in top right
00384     Block block = Block(blocks[0], colors[0]);
00385
00386     if(blocks.size() > 1) {
00387         for(int i = 1; i < blocks.size(); i++) {
00388             if((side == Side::Right && blocks[i].x
00389                > block.topLeft.x)
00390                || (side == Side::Left
00391                   && blocks[i].x
00392                    < block.topLeft.x)) {
00393                 block = Block(blocks[i], colors[i]);
00394             }
00395         }
00396     }
00397
00398     log.Status(std::to_string(block.color) + " block is located");
00399
00400     log.Debug("Block properties => area: " + std::to_string(block.
area)
00401              + ", height: " + std::to_string(block.height) + ", width: "
00402              + std::to_string(block.width) + ", offset: "
00403              + std::to_string(block.offset) + ", color: "
00404              + std::to_string(block.color) + ", size: "
00405              + std::to_string(block.size));
00406
00407     /*
00408     * Draw surrounding rectangles from above on original

```

```

00409         * image.
00410         */
00411         cv::rectangle(imgOrig, block.topLeft, block.bottomRight,
00412             cv::Scalar(255, 0, 0), 4, 8);
00413         log.Image(imgOrig, "original_" + std::to_string(zone)
00414             + std::to_string(invokeCount)
00415             + ".bmp");
00416
00417         return block;
00418     }
00419
00420     Block Grabber::LocateBlueBlock() {
00421         std::vector<cv::Mat> channels;
00422         std::vector<cv::Rect> blocks;
00423
00424         invokeCount++;
00425         log.Status("Locating blue blocks");
00426
00427         cv::Mat img;
00428         cv::Mat imgThresh;
00429         cv::split(cam.Snap(), channels);
00430         cv::transpose(channels[0], img);
00431
00432         log.Verbose("Searching: Blue block");
00433         cv::inRange(img, 30, 255, imgThresh);
00434         log.Image(imgThresh, "thresh_blue" + std::to_string(
zone)
00435             + std::to_string(invokeCount) + ".bmp");
00436
00437         // calculate contours
00438         std::vector<std::vector<cv::Point>> contours;
00439         cv::findContours(imgThresh, contours, CV_RETR_TREE,
00440             CV_CHAIN_APPROX_SIMPLE,
00441             cv::Point(0, 0));
00442         std::vector<std::vector<cv::Point>>
00443             contours_poly(contours.size());
00444         std::vector<cv::Rect> bounds(contours.size());
00445
00446         // find rectangle around polygon-ish shapes
00447         for(int i = 0; i < contours.size(); i++) {
00448             uint32 area = cv::contourArea(contours[i]);
00449
00450             // determine if block and add to blocks vector
00451             if(area > MIN_HALF_BLOCK_SIZE) {
00452                 cv::approxPolyDP(cv::Mat(contours[i]),
00453                     contours_poly[i], 20,
00454                     false);
00455                 cv::Rect rect = cv::boundingRect(
00456                     cv::Mat(contours_poly[i]));
00457                 log.Debug("Blue block detected with area "
00458                     + std::to_string(area));
00459                 blocks.push_back(rect);
00460             }
00461         }
00462
00463         if(blocks.size() == 0) {
00464             log.Image(img, "original_" + std::to_string(zone)
00465                 + std::to_string(invokeCount)
00466                 + "_no_blocks.bmp");
00467             throw std::runtime_error("No blocks found!");
00468         } else {
00469             log.Status(std::to_string(blocks.size())
00470                 + " blocks found");
00471         }
00472
00473         // coordinates start in top right
00474         Block block = Block(blocks[0], Color::Blue);
00475
00476         if(blocks.size() > 1) {
00477             for(int i = 1; i < blocks.size(); i++) {
00478                 if((side == Side::Right && blocks[i].x
00479                     > block.topLeft.x)
00480                     || (side == Side::Left
00481                         && blocks[i].x
00482                         < block.topLeft.x)) {
00483                     block = Block(blocks[i], Color::Blue);
00484                 }
00485             }
00486         }
00487
00488         log.Status(std::to_string(block.color) + " block is located");
00489
00490         log.Debug("Block properties => area: " + std::to_string(block.
area)
00491             + ", height: " + std::to_string(block.height) + ", width: "
00492             + std::to_string(block.width) + ", offset: "

```



```

00494         + std::to_string(block.offset) + ", color: "
00495         + std::to_string(block.color) + ", size: "
00496         + std::to_string(block.size));
00497
00498     /*
00499     * Draw surrounding rectangles from above on original
00500     * image.
00501     */
00502     cv::rectangle(img, block.topLeft, block.bottomRight,
00503                  cv::Scalar(255, 0, 0), 4, 8);
00504     log.Image(img, "original_" + std::to_string(zone)
00505              + std::to_string(invokeCount)
00506              + ".bmp");
00507
00508     return block;
00509 }
00510 }
00511
00512 #endif

```

6.25 src/img.cpp File Reference

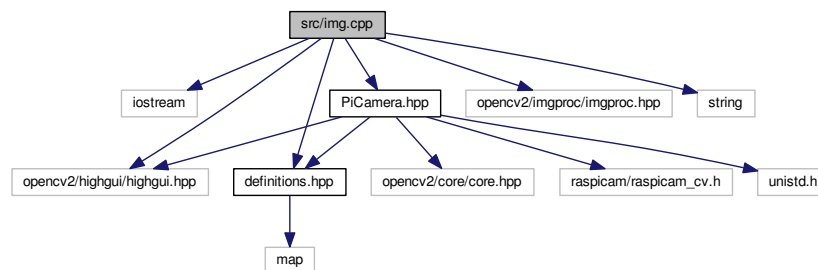
Contains a program to display the current camera image.

```

#include <iostream>
#include <opencv2/highgui/highgui.hpp>
#include <opencv2/imgproc/imgproc.hpp>
#include <string>
#include "definitions.hpp"
#include "PiCamera.hpp"

```

Include dependency graph for img.cpp:



Functions

- int [main](#) ()

6.25.1 Detailed Description

Contains a program to display the current camera image.

Author

Samuel Andrew Wisner, awisner94@gmail.com

Definition in file [img.cpp](#).

6.25.2 Function Documentation

6.25.2.1 int main ()

This program displays the current camera image.

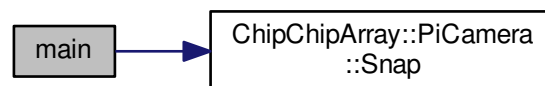
Definition at line 22 of file [img.cpp](#).

```

00022     {
00023         string window = "Current";
00024         PiCamera cam;
00025
00026         namedWindow(window, CV_WINDOW_NORMAL | CV_WINDOW_KEEPRATIO);
00027
00028         while(true) {
00029             Mat image;
00030             transpose(cam.Snap(), image);
00031             imshow(window, image);
00032             waitKey(10); // has to be here :(
00033         }
00034     }

```

Here is the call graph for this function:



6.26 img.cpp

```

00001
00007 #include <iostream>
00008 #include <opencv2/highgui/highgui.hpp>
00009 #include <opencv2/imgproc/imgproc.hpp>
00010 #include <string>
00011
00012 #include "definitions.hpp"
00013 #include "PiCamera.hpp"
00014
00015 using namespace ChipChipArray;
00016 using namespace cv;
00017 using namespace std;
00018
00022 int main() {
00023     string window = "Current";
00024     PiCamera cam;
00025
00026     namedWindow(window, CV_WINDOW_NORMAL | CV_WINDOW_KEEPRATIO);
00027
00028     while(true) {
00029         Mat image;
00030         transpose(cam.Snap(), image);
00031         imshow(window, image);
00032         waitKey(10); // has to be here :(
00033     }
00034 }

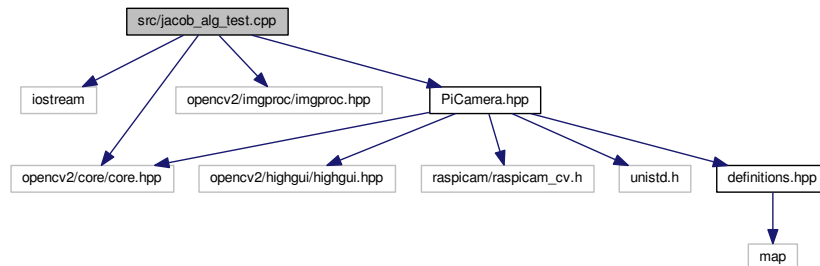
```

6.27 src/jacob_alg_test.cpp File Reference

Contains a program that tests Jacob's yellow-detection algorithm.

```
#include <iostream>
#include <opencv2/core/core.hpp>
#include <opencv2/imgproc/imgproc.hpp>
#include "PiCamera.hpp"
```

Include dependency graph for jacob_alg_test.cpp:



Functions

- `int main ()`

6.27.1 Detailed Description

Contains a program that tests Jacob's yellow-detection algorithm.

Author

Samuel Andrew Wisner, awisner94@gmail.com

Definition in file [jacob_alg_test.cpp](#).

6.27.2 Function Documentation

6.27.2.1 `int main ()`

This program tests Jacob Laurel's algorithm for detecting yellow blocks (RGB=>YUV, HSV=>RGB).

Definition at line 21 of file [jacob_alg_test.cpp](#).

```
00021     {
00022         PiCamera cam;
00023         namedWindow("window", CV_WINDOW_NORMAL);
00024         Mat orig = cam.Snap();
00025         Mat yuv;
00026         Mat fin;
00027         cvtColor(orig, yuv, CV_BGR2YUV);
00028         cvtColor(yuv, fin, CV_HSV2BGR);
00029         imshow("window", fin);
00030         waitKey(-1);
00031     }
```


Functions

- int [main](#) ()

6.29.1 Detailed Description

Contains a program to test Grabber class.

Author

Samuel Andrew Wisner, awisner94@gmail.com

Definition in file [loading_test.cpp](#).

6.29.2 Function Documentation

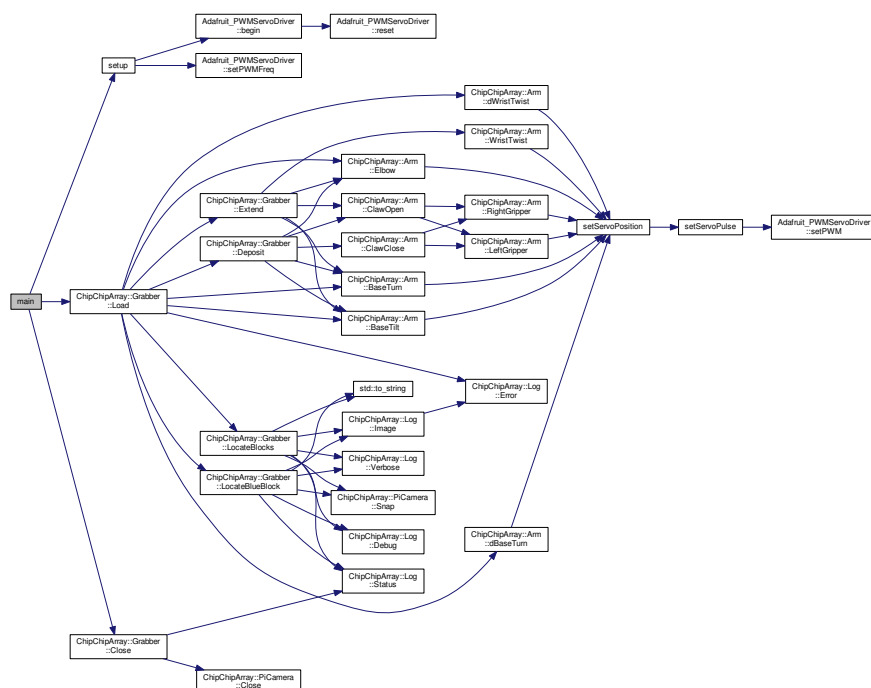
6.29.2.1 int main ()

This program was used solely to test the Grabber class. It moves the arm and picks up blocks.

Definition at line 19 of file [loading_test.cpp](#).

```
00019     {
00020         setup();
00021         Grabber g(Zone::A, Side::Left);
00022         g.Load();
00023         g.Close();
00024     }
```

Here is the call graph for this function:



6.30 loading_test.cpp

```

00001
00007 #include <iostream>
00008
00009 #include "definitions.hpp"
00010 #include "Block.hpp"
00011 #include "Grabber.hpp"
00012
00013 using namespace ChipChipArray;
00014
00019 int main() {
00020     setup();
00021     Grabber g(Zone::A, Side::Left);
00022     g.Load();
00023     g.Close();
00024 }

```

6.31 src/Log.hpp File Reference

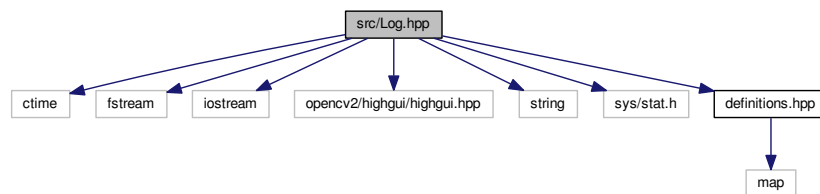
Contains Log class.

```

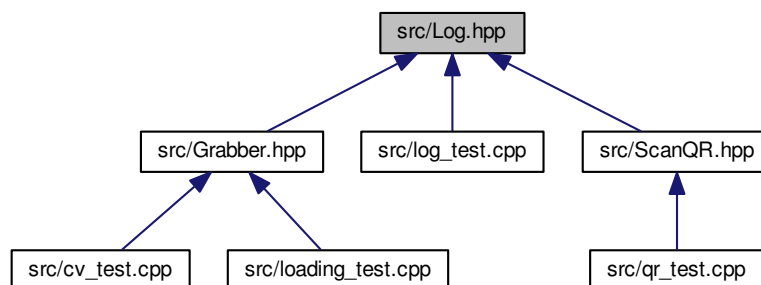
#include <ctime>
#include <fstream>
#include <iostream>
#include <opencv2/highgui/highgui.hpp>
#include <string>
#include <sys/stat.h>
#include "definitions.hpp"

```

Include dependency graph for Log.hpp:



This graph shows which files directly or indirectly include this file:



Classes

- class [ChipChipArray::Log](#)

Namespaces

- [ChipChipArray](#)

6.31.1 Detailed Description

Contains Log class.

Author

Samuel Andrew Wisner, awisner94@gmail.com

Definition in file [Log.hpp](#).

6.32 Log.hpp

```

00001
00007 #ifndef Log_H
00008 #define Log_H
00009
00010 #include <ctime>
00011 #include <fstream>
00012 #include <iostream>
00013 #include <opencv2/highgui/highgui.hpp>
00014 #include <string>
00015 #include <sys/stat.h>
00016
00017 #include "definitions.hpp"
00018
00019 namespace ChipChipArray {
00020
00035     class Log {
00036     public:
00041         Log() {};
00042
00058         Log(auto dir, LogMode mode = LogMode::Text);
00059
00063         ~Log();
00064
00074         void Debug(auto mesg);
00075
00082         void Error(auto mesg);
00083
00092         void Image(cv::Mat image, auto filename);
00093
00097         void Open(auto dir, LogMode mode = LogMode::Text);
00098
00107         void Status(auto mesg);
00108
00117         void Variable(auto name, auto value);
00118
00127         void Verbose(auto mesg);
00128
00129     private:
00130         // CONSTANTS
00131
00136         const char PATH_SEP = '/';
00137
00142         static const uint8 LEN = 255;
00143
00144
00145         // OTHER VARIABLES
00146
00151         std::string dir;
00152
00156         std::string filename;
00157
00162         uint8 imgCount = 0;
00163

```

```

00167         LogMode mode;
00168
00172         std::ofstream file;
00173
00174
00175         // FUNCTIONS
00176
00184         void LogError(auto mesg, std::ofstream::failure f);
00185     };
00186
00187     Log::Log(auto dir, LogMode mode) {
00188 #ifdef LOG
00189         Open(dir, mode);
00190 #endif
00191     }
00192
00193     Log::~Log() {
00194 #ifdef LOG
00195         try {
00196             file.flush();
00197             file.close();
00198         } catch (std::ofstream::failure f) {
00199             LogError("Gosh dang it! A fatal error has occurred "
00200                     "closing the logfile.", f);
00201         }
00202 #endif
00203     }
00204
00205     void Log::Debug(auto mesg) {
00206 #ifdef LOG
00207         try {
00208             file << "DEBUG: " << mesg << std::endl;
00209             file.flush();
00210         } catch (std::ofstream::failure f) {
00211             LogError("Debug() write error", f);
00212         }
00213 #endif
00214     }
00215
00216     void Log::Error(auto mesg) {
00217 #ifdef LOG
00218         try {
00219             file << "ERROR: " << mesg << std::endl;
00220             file.flush();
00221         } catch (std::ofstream::failure f) {
00222             LogError("Error() write error", f);
00223         }
00224 #endif
00225     }
00226
00227     void Log::Image(cv::Mat image, auto filename) {
00228 #ifdef LOG
00229         try {
00230             cv::imwrite(dir + std::string(filename), image);
00231         } catch (std::ofstream::failure f) {
00232             LogError("Image() write error", f);
00233         } catch (std::exception ex) {
00234             Error("Error writing image " + std::string(filename));
00235         }
00236 #endif
00237     }
00238
00239     void Log::LogError(auto mesg, std::ofstream::failure f) {
00240 #ifdef LOG
00241         std::cerr << mesg << std::endl;
00242         std::cerr << "MESSAGE: " << f.what() << std::endl;
00243         exit(ERROR);
00244 #endif
00245     }
00246
00247     void Log::Open(auto dir, LogMode mode) {
00248 #ifdef LOG
00249         // format date and time
00250         char date[32];
00251         time_t sec = time(nullptr);
00252         struct tm * loctime = localtime(&sec);
00253         strftime(date, 32, "%m-%d_%H-%M-%S", loctime);
00254
00255         // create temporary strings
00256         this->dir = std::string(dir);
00257         std::string datestr = std::string(date);
00258
00259         // add path separator if necessary
00260         if(this->dir[this->dir.length() - 1] != PATH_SEP) {
00261             this->dir += PATH_SEP;
00262         }
00263

```



```

00264         // add directory for log and images if necessary
00265         if(mode == LogMode::Multi) this->dir += datestr + PATH_SEP;
00266
00267         int ret = mkdir(this->dir.c_str(), S_IRUSR | S_IWUSR | S_IRGRP | S_IWGRP
00268             | S_IROTH | S_IWOTH | S_IXUSR | S_IXGRP
00269             | S_IXOTH);
00270
00271         filename = this->dir + datestr + ".log";
00272
00273         // set class mode
00274         this->mode = mode;
00275
00276         // Initializing file
00277         file.exceptions(std::ofstream::failbit
00278             | std::ofstream::badbit);
00279
00280         try {
00281             file.open(filename, std::ofstream::out
00282                 | std::ofstream::app);
00283         } catch(std::ofstream::failure ex) {
00284             LogError("Oh, no! An error has occurred opening the "
00285                 "log file.", ex);
00286         }
00287     #endif
00288     }
00289
00290     void Log::Status(auto mesg) {
00291     #ifdef LOG
00292         try {
00293             file << "STATUS: " << mesg << std::endl;
00294             file.flush();
00295         } catch (std::ofstream::failure f) {
00296             LogError("Status() write error", f);
00297         }
00298     #endif
00299     }
00300
00301     void Log::Variable(auto name, auto value) {
00302     #ifdef LOG
00303         try {
00304             file << "VARIABLE: " << name << " = " << value
00305                 << std::endl;
00306             file.flush();
00307         } catch (std::ofstream::failure f) {
00308             LogError("Variable() write error", f);
00309         }
00310     #endif
00311     }
00312
00313     void Log::Verbose(auto mesg) {
00314     #ifdef LOG
00315         try {
00316             file << "VERBOSE: " << mesg << std::endl;
00317             file.flush();
00318         } catch (std::ofstream::failure f) {
00319             LogError("Verbose() write error", f);
00320         }
00321     #endif
00322     }
00323 }
00324 #endif

```

6.33 src/log_test.cpp File Reference

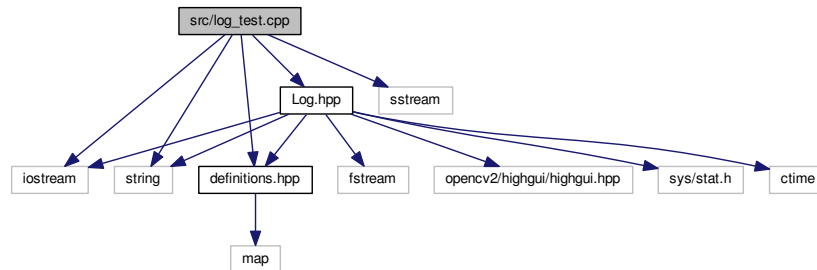
Contains a program to test partially the Log class.

```

#include <iostream>
#include <sstream>
#include <string>
#include "definitions.hpp"
#include "Log.hpp"

```

Include dependency graph for `log_test.cpp`:



Functions

- `int main ()`

6.33.1 Detailed Description

Contains a program to test partially the Log class.

Author

Samuel Andrew Wisner, awisner94@gmail.com

Definition in file `log_test.cpp`.

6.33.2 Function Documentation

6.33.2.1 `int main ()`

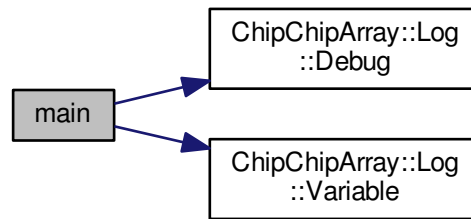
This program partially tests the Log class.

Definition at line 18 of file `log_test.cpp`.

```

00018     {
00019         Log log("logs", LogMode::Text);
00020         log.Debug("yolo!");
00021         log.Variable("mymom", "toldme");
00022     }
  
```

Here is the call graph for this function:



6.34 log_test.cpp

```

00001
00007 #include <iostream>
00008 #include <sstream>
00009 #include <string>
00010
00011 #include "definitions.hpp"
00012 #include "Log.hpp"
00013
00014 using namespace ChipChipArray;
00018 int main() {
00019     Log log("logs", LogMode::Text);
00020     log.Debug("yolo!");
00021     log.Variable("mymom", "toldme");
00022 }
  
```

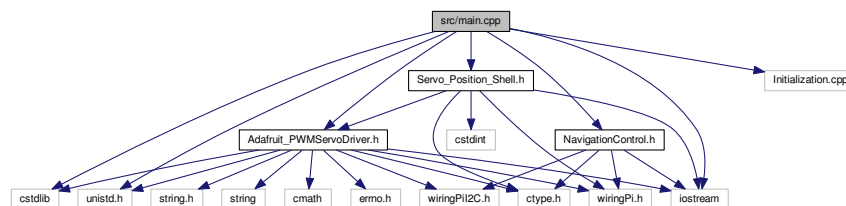
6.35 src/main.cpp File Reference

Contains the `main()` function to the whole project.

```

#include <cstdlib>
#include <unistd.h>
#include "Servo_Position_Shell.h"
#include "Adafruit_PWMServoDriver.h"
#include <iostream>
#include "NavigationControl.h"
#include "Initialization.cpp"
  
```

Include dependency graph for main.cpp:



Macros

- `#define` [READTHINKDO](#)

Functions

- `int` [main](#) ()

Variables

- `int` [startstatus](#)
- `int` [startroboth](#)
- `int` [stoproboth](#)
- `int` [track](#)
- `int` [navigationbusy](#)
- `int` [cleartnavigate](#)
- `int` [cleartoload](#)
- `int` [cleartounload](#)
- `int` [robotismoving](#)
- `int` [whereistherobot](#)
- `int` [loadcounter](#)
- `int` [unloadcounter](#)
- `int` [loadtheblocks](#)
- `int` [unloadtheblocks](#)
- `int` [giveitasec](#)
- `int` [startloadingthread](#)

6.35.1 Detailed Description

Contains the [main\(\)](#) function to the whole project.

Author

Nickolas Neely

Date

1. February 2016, 8:20 AM

Definition in file [main.cpp](#).

6.35.2 Macro Definition Documentation

6.35.2.1 `#define` [READTHINKDO](#)

Definition at line [27](#) of file [main.cpp](#).

6.35.3 Function Documentation

6.35.3.1 int main ()

The `main()` project program function.

Definition at line 51 of file `main.cpp`.

```

00051         {
00052
00053     initialization();
00054     #ifdef READTHINKDO

00055     /*Track selection initialization will allow track select until start condition is true*/
00056     while(1){
00057         while(track == 1 && startroboth == 0){
00058             startstatus = digitalRead(0);
00059             track = digitalRead(1);
00060             cout<<endl<<"I am in left track mode";
00061             if(startstatus == 1){
00062                 startroboth = 1;
00063             }
00064
00065             /* RUN MODE FOR LEFT TRACK GAME START!*/
00066             while(startroboth == 1 && stoproboth == 0){
00067                 //READ for left track
00068
00069                 startstatus = digitalRead(0);
00070                 navigationbusy = digitalRead(2);
00071
00072                 //THINK for left track
00073
00074                 //clearance to do an action;
00075                 if(cleartoload == 1 || cleartounload == 1){
00076                     cleartonavigate = 0;
00077                 }
00078                 else if(cleartonavigate == 1 || cleartounload == 1){
00079                     cleartoload = 0;
00080                 }
00081                 else if(cleartonavigate == 1 || cleartoload == 1){
00082                     cleartounload = 0;
00083                 }
00084
00085
00086                 // latch to figure out robot position in sequence
00087                 if(navigationbusy == 1 && robotismoving == 0){
00088                     robotismoving = 1;
00089                     whereistherobot++;
00090                 }else if(navigationbusy == 0 && robotismoving == 1){
00091                     robotismoving = 0;
00092                 }
00093
00094                 //working actions
00095                 if(whereistherobot > 0 && whereistherobot <=4 &&
navigationbusy == 0){
00096                     cleartoload = 1;
00097                 }else if(whereistherobot > 0 && whereistherobot <=4 &&
navigationbusy == 1){
00098                     cleartoload = 0;
00099                 }else if(whereistherobot == 5 && navigationbusy == 0){
00100                     cleartounload = 1;
00101                 }else if(whereistherobot == 5 && navigationbusy == 1){
00102                     cleartounload = 0;
00103                 }
00104
00105
00106                 //controls load action timing
00107                 if(cleartoload == 1 && loadcounter < 2000){
00108                     loadtheblocks = 1;
00109                     loadcounter ++;
00110                     startloadingthread = 1;
00111                 }else if(loadcounter >= 2000){
00112                     cleartoload = 0;
00113                     loadcounter = 1;
00114                 }
00115
00116
00117                 //controls the unload action timing
00118                 if(cleartounload ==1 && unloadcounter < 150){
00119                     unloadcounter++;
00120                     unloadtheblocks = 1;
00121                 }else if(loadcounter >= 150){
00122                     cleartounload = 0;
00123                     unloadcounter = 1;

```

```

00124         unloadtheblocks = 0;
00125     }
00126
00127 //DO for the left track
00128
00129 //Navigate to next position in sequence
00130 if(cleartounload == 0 && cleartoload == 0 &&
robotismoving == 0){
00131     digitalWrite(3,HIGH);
00132 }else if(robotismoving == 1){
00133     digitalWrite(3,LOW);
00134 }
00135
00136 //load blocks
00137 if(loadtheblocks ==1){
00138     pthread_t andrewthread;
00139     pthread_create(&andrewthread,NULL,grabCall,NULL);
00140
00141     loadtheblocks =0;
00142 }
00143
00144
00145 // unload the blocks
00146 if(unloadtheblocks ==1 && unloadcounter < 100){
00147     setServoPosition(Servo(10),90);
00148     setServoPosition(Servo(11),90);
00149     setServoPosition(Servo(12),90);
00150     setServoPosition(Servo(13),90);
00151 }else if(unloadtheblocks == 1 && unloadcounter >= 100 &&
unloadcounter <140){
00152     setServoPosition(Servo(10),0);
00153     setServoPosition(Servo(11),0);
00154     setServoPosition(Servo(12),0);
00155     setServoPosition(Servo(13),0);
00156 }else if(unloadtheblocks == 1 && unloadcounter >= 140){
00157     setServoPosition(Servo(10),-1);
00158     setServoPosition(Servo(11),-1);
00159     setServoPosition(Servo(12),-1);
00160     setServoPosition(Servo(13),-1);
00161 }
00162
00163 cout<<endl<<"I am in run mode of left track";
00164
00165 /* stops Robot if ever hit on a RTD loop*/
00166 if(startstatus == 0){
00167     digitalWrite(3,LOW);
00168     cout<<endl<<"Halting all function stop engaged after a start";
00169     giveitasec++;
00170     if(giveitasec >= 50){
00171         stoproboth = 1;
00172         giveitasec = 0;
00173     }
00174 }
00175 cout<<endl<<"The current position of robot is:"<<whereistherobot<<endl;
00176
00177 // delay for 20 milliseconds per loop
00178 usleep(20000);
00179
00180 }
00181 }
00182 }
00183 /*Track selection initialization will allow track select until start condition is true*/
00184 while(track == 0 && startroboth ==0){
00185     startstatus = digitalRead(0);
00186     track = digitalRead(1);
00187     if(startstatus == 1){
00188         startroboth = 1;
00189     }
00190     cout<<endl<<"I am in right track mode.";
00191     cout<<"Not yet implemented. Danger. Danger. Danger.";
00192 }
00193 }
00194 #endif
00195 #ifdef SWITCHTEST
00196
00197 int cat;
00198 int dog;
00199 wiringPiSetup();
00200 while(1){
00201     //test each pin if needed for setup and checking
00202     /*
00203     cout<<endl;
00204
00205     cout<<"Input a pin to check:"<<endl;

```

```

00205         cin>>dog;

00206         cat =digitalRead(dog);

00207         cout<<"I am reading:"<<cat<<endl;

00208         */
00209
00210         if(digitalRead(0)==1){
00211             cout<<"Heavy is in stop or idle mode."<<endl;
00212         }else if(digitalRead(0)==0){
00213             cout<<"Heavy is in run mode!"<<endl;
00214         }
00215         if(digitalRead(1)==1){
00216             cout<<"Heavy is set for left track."<<endl;
00217         }else if(digitalRead(1)==0){
00218             cout<<"Heavy is set for right track."<<endl;
00219         }
00220     }
00221
00222     cout<<endl<<"Press enter to continue";
00223     cin.ignore();
00224 }
00225 #endif

00226
00227 #ifdef ARMTEST

00228     Servo whichservo;
00229     int tmpServo = -1;
00230     int position;
00231     setup();
00232     while(1){
00233         cout<<endl;
00234         cout<<"Pick a servo to use: BASE_TURN = 0, BASE_TILT = 1, ELBOW = 2, WRIST_TILT = 3,";
00235         cout<<endl<<"WRIST_PAN = 4, GRIP_LEFT = 5, GRIP_RIGHT = 6";
00236         cout<<endl;
00237         cin>>tmpServo;
00238         if(tmpServo > 6 || tmpServo < 0){
00239             cout<<"Please choose again:"<<endl;
00240             continue;
00241         }
00242         whichservo = (Servo)tmpServo;
00243         cout<<endl;
00244         cout<<"Pick a position (set position to -1 to disengage servo and set pwm to 0):";
00245         cin>>position;
00246         cout<<endl;
00247         setServoPosition(whichservo,position);
00248     }
00249 }
00250 #endif

00251

00252
00253 #ifdef NAVTEST

00254     int cat = 0;
00255     pinMode(2,INPUT);
00256     while(1){
00257         cout<<"High or Low?:"<<endl;
00258         cin>>cat;
00259         digitalWrite(3,cat);
00260         cout<<endl;
00261         if(digitalRead(2)==1){
00262             cout<<"I am getting a high from Micah"<<endl;
00263         }else if(digitalRead(2)==0){
00264             cout<<"I am getting a low from Micah"<<endl;
00265         }
00266     }
00267     cin.ignore();
00268 }
00269 #endif

00270
00271
00272
00273 #endif

00274
00275 #ifdef UNLOADTEST

00276     Servo whichservo;
00277     int tmpServo = -1;
00278     int position;
00279     setup();
00280     while(1){

```

```

00283      /*
00284      cout<<endl;

00285      cout<<"Pick a servo to use: ";

00286      cout<<endl<<"UNLOAD_1= 10, UNLOAD_2 = 11, UNLOAD_3 = 12, UNLOAD_4 = 13";

00287      cout<<endl;

00288      cin>>tmpServo;

00289      if(tmpServo < 10 || tmpServo > 14){

00290          cout<<"Please choose again:"<<endl;

00291          continue;

00292      }

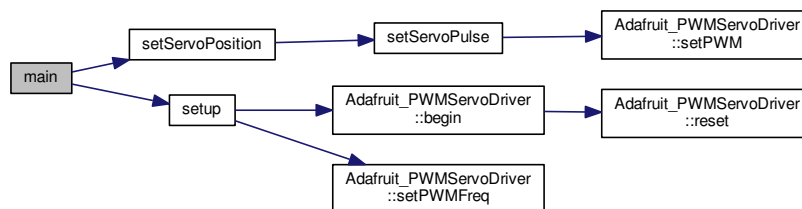
00293      whichservo = (Servo)tmpServo;

00294      */
00295      cout<<endl;
00296      cout<<"Pick a position (set position to -1 to disengage servo and set pwm to 0):";
00297      cin>>position;
00298      cout<<endl;
00299      //setServoPosition((Servo)tmpServo,position);
00300      setServoPosition((Servo)10,position);
00301      setServoPosition((Servo)11,position);
00302      setServoPosition((Servo)12,position);
00303      setServoPosition((Servo)13,position);
00304
00305      }
00306
00307 #endif

00308      return 0;
00309 }

```

Here is the call graph for this function:



6.35.4 Variable Documentation

6.35.4.1 int cleartoload

Definition at line 37 of file [main.cpp](#).

6.35.4.2 int cleartonavigate

Definition at line 36 of file [main.cpp](#).

6.35.4.3 int cleartounload

Definition at line 38 of file [main.cpp](#).

6.35.4.4 int giveitasec

Definition at line 45 of file [main.cpp](#).

6.35.4.5 int loadcounter

Definition at line 41 of file [main.cpp](#).

6.35.4.6 int loadtheblocks

Definition at line 43 of file [main.cpp](#).

6.35.4.7 int navigationbusy

Definition at line 35 of file [main.cpp](#).

6.35.4.8 int robotismoving

Definition at line 39 of file [main.cpp](#).

6.35.4.9 int startloadingthread

Definition at line 46 of file [main.cpp](#).

6.35.4.10 int startroboth

Definition at line 32 of file [main.cpp](#).

6.35.4.11 int startstatus

Definition at line 31 of file [main.cpp](#).

6.35.4.12 int stoproboth

Definition at line 33 of file [main.cpp](#).

6.35.4.13 int track

Definition at line 34 of file [main.cpp](#).

6.35.4.14 int unloadcounter

Definition at line 42 of file [main.cpp](#).

6.35.4.15 int unloadtheblocks

Definition at line 44 of file [main.cpp](#).

6.35.4.16 int whereistherobot

Definition at line 40 of file [main.cpp](#).

6.36 main.cpp

```

00001
00008 /*
00009  * File:    main.cpp
00010  * Author:  Nick
00011  *
00012  * Created on February 1, 2016, 8:20 AM
00013  */
00014
00015 #include <cstdlib>
00016 #include <unistd.h>
00017 #include "Servo_Position_Shell.h"
00018 #include "Adafruit_PWMServoDriver.h"
00019 #include <iostream>
00020 #include "NavigationControl.h"
00021 #include "Initialization.cpp"
00022
00023 // #define UNLOADTEST
00024 // #define ARMTEST
00025 // #define NAVTEST
00026 // #define SWITCHTEST
00027 #define READTHINKDO
00028
00029 using namespace std;
00030
00031 int startstatus;
00032 int startroboth;
00033 int stoproboth;
00034 int track;
00035 int navigationbusy;
00036 int cleartnavigate;
00037 int cleartoload;
00038 int cleartounload;
00039 int robotismoving;
00040 int whereistherobot;
00041 int loadcounter;
00042 int unloadcounter;
00043 int loadtheblocks;
00044 int unloadtheblocks;
00045 int giveitasec;
00046 int startloadingthread;
00047
00051 int main() {
00052
00053     initialization();
00054     #ifdef READTHINKDO
00055     /*Track selection initialization will allow track select until start condition is true*/
00056     while(1){
00057         while(track == 1 && startroboth == 0){
00058             startstatus = digitalRead(0);
00059             track = digitalRead(1);
00060             cout<<endl<<"I am in left track mode";
00061             if(startstatus == 1){
00062                 startroboth = 1;
00063             }
00064
00065             /* RUN MODE FOR LEFT TRACK GAME START!*/
00066             while(startroboth == 1 && stoproboth == 0){
00067                 //READ for left track
00068
00069                 startstatus = digitalRead(0);
00070                 navigationbusy = digitalRead(2);
00071
00072                 //THINK for left track
00073
00074                 //clearance to do an action;
00075                 if(cleartoload == 1 || cleartounload == 1){
00076                     cleartnavigate = 0;
00077                 }
00078                 else if(cleartnavigate == 1 || cleartounload == 1){
00079                     cleartoload = 0;
00080                 }
00081                 else if(cleartnavigate == 1 || cleartoload == 1){
00082                     cleartounload = 0;
00083                 }
00084
00085

```

```

00086         // latch to figure out robot position in sequence
00087         if(navigationbusy == 1 && robotismoving == 0){
00088             robotismoving = 1;
00089             whereistherobot++;
00090         }else if(navigationbusy == 0 && robotismoving == 1){
00091             robotismoving = 0;
00092         }
00093
00094         //working actions
00095         if(whereistherobot > 0 && whereistherobot <=4 &&
navigationbusy == 0){
00096             cleartoload = 1;
00097         }else if(whereistherobot > 0 && whereistherobot <=4 &&
navigationbusy == 1){
00098             cleartoload = 0;
00099         }else if(whereistherobot == 5 && navigationbusy == 0){
00100             cleartounload = 1;
00101         }else if(whereistherobot == 5 && navigationbusy == 1){
00102             cleartounload = 0;
00103         }
00104
00105
00106         //controls load action timing
00107         if(cleartoload == 1 && loadcounter < 2000){
00108             loadtheblocks = 1;
00109             loadcounter ++;
00110             startloadingthread = 1;
00111
00112         }else if(loadcounter >= 2000){
00113             cleartoload = 0;
00114             loadcounter = 1;
00115         }
00116
00117         //controls the unload action timing
00118         if(cleartounload ==1 && unloadcounter < 150){
00119             unloadcounter++;
00120             unloadtheblocks = 1;
00121         }else if(loadcounter >= 150){
00122             cleartounload = 0;
00123             unloadcounter = 1;
00124             unloadtheblocks = 0;
00125         }
00126
00127         //DO for the left track
00128
00129         //Navigate to next position in sequence
00130         if(cleartounload == 0 && cleartoload == 0 &&
robotismoving == 0){
00131             digitalWrite(3,HIGH);
00132         }else if(robotismoving == 1){
00133             digitalWrite(3,LOW);
00134         }
00135
00136         //load blocks
00137         if(loadtheblocks ==1){
00138             pthread_t andrewthread;
00139             pthread_create(&andrewthread,NULL,grabCall,NULL);
00140
00141             loadtheblocks =0;
00142
00143         }
00144
00145         // unload the blocks
00146         if(unloadtheblocks ==1 && unloadcounter < 100){
00147             setServoPosition(Servo(10),90);
00148             setServoPosition(Servo(11),90);
00149             setServoPosition(Servo(12),90);
00150             setServoPosition(Servo(13),90);
00151         }else if(unloadtheblocks == 1 && unloadcounter >= 100 &&
unloadcounter <140){
00152             setServoPosition(Servo(10),0);
00153             setServoPosition(Servo(11),0);
00154             setServoPosition(Servo(12),0);
00155             setServoPosition(Servo(13),0);
00156         }else if(unloadtheblocks == 1 && unloadcounter >= 140){
00157             setServoPosition(Servo(10),-1);
00158             setServoPosition(Servo(11),-1);
00159             setServoPosition(Servo(12),-1);
00160             setServoPosition(Servo(13),-1);
00161         }
00162
00163         cout<<endl<<"I am in run mode of left track";
00164
00165         /* stops Robot if ever hit on a RTD loop*/
00166         if(startstatus == 0){
00167             digitalWrite(3,LOW);
00168             cout<<endl<<"Halting all function stop engaged after a start";

```

```

00169         giveitasec++;
00170         if(giveitasec >= 50){
00171             stoproboth = 1;
00172             giveitasec = 0;
00173         }
00174     }
00175     cout<<endl<<"The current position of robot is:"<<whereistherobot<<endl;
00176
00177     // delay for 20 milliseconds per loop
00178     usleep(20000);
00179
00180 }
00181 }
00182 }
00183 /*Track selection initialization will allow track select until start condition is true*/
00184 while(track == 0 && startroboth ==0){
00185     startstatus = digitalRead(0);
00186     track = digitalRead(1);
00187     if(startstatus == 1){
00188         startroboth = 1;
00189     }
00190     cout<<endl<<"I am in right track mode.";
00191     cout<<"Not yet implemented. Danger. Danger. Danger.";
00192 }
00193 }
00194 #endif
00195 #ifndef SWITCHTEST
00196     int cat;
00197     int dog;
00198     wiringPiSetup();
00199     while(1){
00200
00201         //test each pin if needed for setup and checking
00202         /*
00203         cout<<endl;
00204         cout<<"Input a pin to check:"<<endl;
00205         cin>>dog;
00206         cat =digitalRead(dog);
00207         cout<<"I am reading:"<<cat<<endl;
00208         */
00209
00210         if(digitalRead(0)==1){
00211             cout<<"Heavy is in stop or idle mode."<<endl;
00212
00213         }else if(digitalRead(0)==0){
00214             cout<<"Heavy is in run mode!"<<endl;
00215         }
00216         if(digitalRead(1)==1){
00217             cout<<"Heavy is set for left track."<<endl;
00218         }else if(digitalRead(1)==0){
00219             cout<<"Heavy is set for right track."<<endl;
00220         }
00221
00222         cout<<endl<<"Press enter to continue";
00223         cin.ignore();
00224     }
00225 #endif
00226
00227 #ifndef ARMTEST
00228
00229     Servo whichservo;
00230     int tmpServo = -1;
00231     int position;
00232     setup();
00233     while(1){
00234         cout<<endl;
00235         cout<<"Pick a servo to use: BASE_TURN = 0, BASE_TILT = 1, ELBOW = 2, WRIST_TILT = 3,";
00236         cout<<endl<<"WRIST_PAN = 4, GRIP_LEFT = 5, GRIP_RIGHT = 6";
00237         cout<<endl;
00238         cin>>tmpServo;
00239         if(tmpServo > 6 || tmpServo < 0){
00240             cout<<"Please choose again:"<<endl;
00241             continue;
00242         }
00243         whichservo = (Servo)tmpServo;
00244         cout<<endl;
00245         cout<<"Pick a position (set position to -1 to disengage servo and set pwm to 0).";
00246         cin>>position;
00247         cout<<endl;
00248         setServoPosition(whichservo,position);
00249     }
00250 }
00251 #endif
00252
00253 #ifndef NAVTEST
00254
00255     int cat = 0;

```

```

00256     pinMode(2, INPUT);
00257     while(1){
00258         cout<<"High or Low?:"<<endl;
00259         cin>>cat;
00260         digitalWrite(3, cat);
00261         cout<<endl;
00262         if(digitalRead(2)==1){
00263             cout<<"I am getting a high from Micah"<<endl;
00264
00265         }else if(digitalRead(2)==0){
00266             cout<<"I am getting a low from Micah"<<endl;
00267         }
00268     }
00269     cin.ignore();
00270
00271
00272
00273 #endif
00274
00275 #ifndef UNLOADTEST
00276
00277     Servo whichservo;
00278     int tmpServo = -1;
00279     int position;
00280
00281     setup();
00282     while(1){
00283         /*
00284         cout<<endl;
00285         cout<<"Pick a servo to use: ";
00286         cout<<endl<<"UNLOAD_1= 10, UNLOAD_2 = 11, UNLOAD_3 = 12, UNLOAD_4 = 13";
00287         cout<<endl;
00288         cin>>tmpServo;
00289         if(tmpServo < 10 || tmpServo > 14){
00290             cout<<"Please choose again:"<<endl;
00291             continue;
00292         }
00293         whichservo = (Servo)tmpServo;
00294         */
00295         cout<<endl;
00296         cout<<"Pick a position (set position to -1 to disengage servo and set pwm to 0):";
00297         cin>>position;
00298         cout<<endl;
00299         //setServoPosition((Servo)tmpServo, position);
00300         setServoPosition((Servo)10, position);
00301         setServoPosition((Servo)11, position);
00302         setServoPosition((Servo)12, position);
00303         setServoPosition((Servo)13, position);
00304
00305     }
00306
00307 #endif
00308     return 0;
00309 }

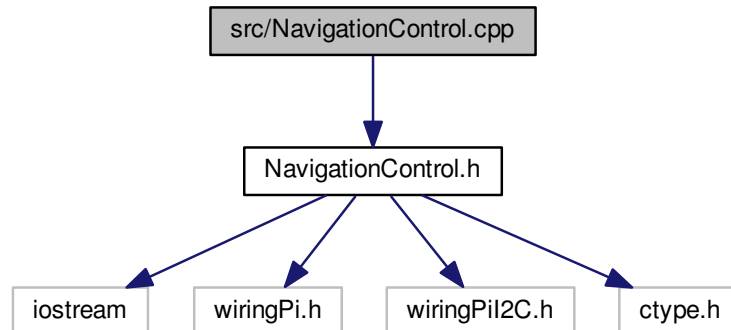
```

6.37 src/NavigationControl.cpp File Reference

Contains the navigation control function definitions.

```
#include "NavigationControl.h"
```

Include dependency graph for NavigationControl.cpp:



Functions

- void [navigationSetup](#) (uint8_t navigation_add)
- void [commandNavigation](#) (uint8_t navigationcommand)

Variables

- [uint8_t navigationcmd](#)
- [uint8_t nav_fd](#)

6.37.1 Detailed Description

Contains the navigation control function definitions.

Author

Nickolas Neely

Definition in file [NavigationControl.cpp](#).

6.37.2 Function Documentation

6.37.2.1 void [commandNavigation](#) (uint8_t *navigationcommand*)

Definition at line 19 of file [NavigationControl.cpp](#).

```

00019                                     {
00020     uint8_t data = navigationcommand;
00021     wiringPiI2CWrite(nav_fd, data);
00022 }
```

6.37.2.2 void navigationSetup (uint8_t navigation_add)

Definition at line 14 of file [NavigationControl.cpp](#).

```
00014
00015     nav_fd=wiringPiI2CSetup(navigation_add);
00016
00017 }
```

6.37.3 Variable Documentation**6.37.3.1 uint8_t nav_fd**

Definition at line 11 of file [NavigationControl.cpp](#).

6.37.3.2 uint8_t navigationcmd

Definition at line 10 of file [NavigationControl.cpp](#).

6.38 NavigationControl.cpp

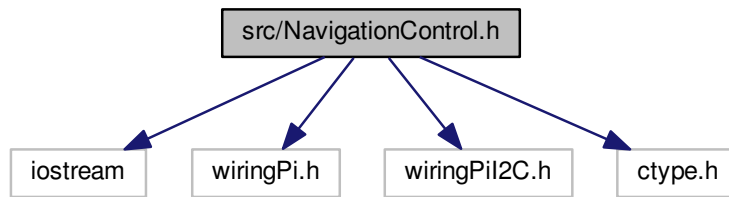
```
00001
00007 #include "NavigationControl.h"
00008
00009 //uint8_t navigation_address = 10u;
00010 uint8_t navigationcmd;
00011 uint8_t nav_fd;
00012
00013
00014 void navigationSetup(uint8_t navigation_add){
00015     nav_fd=wiringPiI2CSetup(navigation_add);
00016
00017 }
00018
00019 void commandNavigation(uint8_t navigationcommand){
00020     uint8_t data = navigationcommand;
00021     wiringPiI2CWrite(nav_fd, data);
00022 }
```

6.39 src/NavigationControl.h File Reference

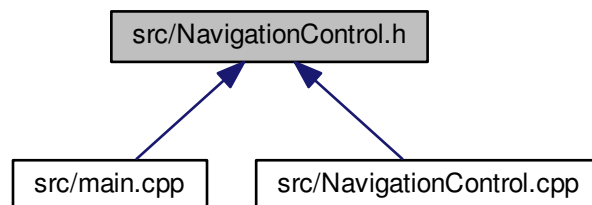
Contains the function definitions for navigation control.

```
#include <iostream>
#include <wiringPi.h>
#include <wiringPiI2C.h>
#include <ctype.h>
```

Include dependency graph for NavigationControl.h:



This graph shows which files directly or indirectly include this file:



Macros

- #define [uint8_t](#) unsigned char

Functions

- void [navigationSetup](#) ([uint8_t](#) navigation_add)
- void [commandNavigation](#) ([uint8_t](#) navigationcommand)

6.39.1 Detailed Description

Contains the function definitions for navigation control.

Author

Nickolas Neely

Date

22. February 2016, 12:00 PM

Definition in file [NavigationControl.h](#).

6.39.2 Macro Definition Documentation

6.39.2.1 #define uint8_t unsigned char

Definition at line 24 of file [NavigationControl.h](#).

6.39.3 Function Documentation

6.39.3.1 void commandNavigation (uint8_t navigationcommand)

Definition at line 19 of file [NavigationControl.cpp](#).

```
00019                                     {
00020     uint8_t data = navigationcommand;
00021     wiringPiI2CWrite(nav_fd, data);
00022 }
```

6.39.3.2 void navigationSetup (uint8_t navigation_add)

Definition at line 14 of file [NavigationControl.cpp](#).

```
00014                                     {
00015     nav_fd=wiringPiI2CSetup(navigation_add);
00016
00017 }
```

6.40 NavigationControl.h

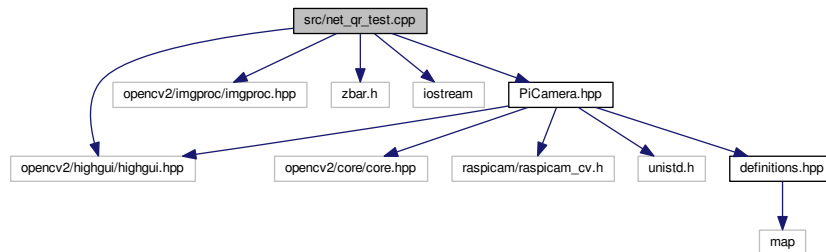
```
00001
00008 /*
00009  * File:   NavigationControl.h
00010  * Author: Nick
00011  *
00012  * Created on February 22, 2016, 12:00 PM
00013  */
00014
00015
00016 #ifndef NAVIGATIONCONTROL_H
00017 #define NAVIGATIONCONTROL_H
00018 #include <iostream>
00019 #include <wiringPi.h>
00020 #include <wiringPiI2C.h>
00021 #include <ctype.h>
00022
00023 #ifndef uint8_t
00024 #define uint8_t unsigned char
00025 #endif
00026
00027 #ifdef __cplusplus
00028 extern "C"{
00029 #endif
00030
00031
00032 void navigationSetup(uint8_t navigation_add);
00033
00034 void commandNavigation(uint8_t navigationcommand);
00035
00036 #ifdef __cplusplus
00037 }
00038 #endif
00039
00040 #endif /*NAVIGATIONCONTROL_H*/
00041
```

6.41 src/net_qr_test.cpp File Reference

Contains test program for reading QR codes.

```
#include <opencv2/highgui/highgui.hpp>
#include <opencv2/imgproc/imgproc.hpp>
#include <zbar.h>
#include <iostream>
#include "PiCamera.hpp"
```

Include dependency graph for net_qr_test.cpp:



Functions

- `int main (int argc, char *argv[])`

6.41.1 Detailed Description

Contains test program for reading QR codes.

Author

Michael Young
 Samuel Andrew Wisner, awisner94@gmail.com

Definition in file [net_qr_test.cpp](#).

6.41.2 Function Documentation

6.41.2.1 `int main (int argc, char * argv[])`

This is a (modified) test program written by Michael Young (<https://github.com/ayoungprogrammer/←WebcamCodeScanner>). It was modified to work with the Raspicam.

Definition at line 25 of file [net_qr_test.cpp](#).

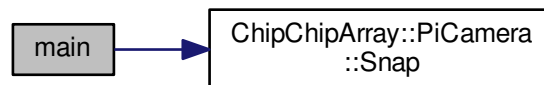
```
00026 {
00027     PiCamera cam; // open the video camera no. 0
00028     ImageScanner scanner;
00029     scanner.set_config(ZBAR_NONE, ZBAR_CFG_ENABLE, 1);
00030
00031     namedWindow("MyVideo", CV_WINDOW_AUTOSIZE); //create a window called "MyVideo"
00032
00033     while (1)
00034     {
00035         Mat frame = cam.Snap();
00036         Mat grey;
00037         cvtColor(frame, grey, CV_BGR2GRAY);
00038
00039         int width = frame.cols;
00040         int height = frame.rows;
00041         uchar *raw = (uchar *)grey.data;
00042         // wrap image data
00043         zbar::Image image(width, height, "Y800", raw, width * height);
```

```

00044         // scan the image for barcodes
00045         int n = scanner.scan(image);
00046         // extract results
00047         for(Image::SymbolIterator symbol = image.symbol_begin();
00048             symbol != image.symbol_end();
00049             ++symbol) {
00050             vector<Point> vp;
00051             // do something useful with results
00052             cout << "decoded " << symbol->get_type_name() << " symbol \" << symbol->get_data() << '\"' << "
" << endl;
00053             int n = symbol->get_location_size();
00054             for(int i=0;i<n;i++){
00055                 vp.push_back(Point(symbol->get_location_x(i),symbol->get_location_y(i)));
00056             }
00057             RotatedRect r = minAreaRect(vp);
00058             Point2f pts[4];
00059             r.points(pts);
00060             for(int i=0;i<4;i++){
00061                 line(frame,pts[i],pts[(i+1)%4],Scalar(255,0,0),3);
00062             }
00063         }
00064
00065         imshow("MyVideo", frame); //show the frame in "MyVideo" window
00066
00067         if (waitKey(30) == 27) //wait for 'esc' key press for 30ms. If 'esc' key is pressed, break loop
00068         {
00069             cout << "esc key is pressed by user" << endl;
00070             break;
00071         }
00072     }
00073     return 0;
00074 }
00075 }

```

Here is the call graph for this function:



6.42 net_qr_test.cpp

```

00001
00008 #include <opencv2/highgui/highgui.hpp>
00009 #include <opencv2/imgproc/imgproc.hpp>
00010 #include <zbar.h>
00011 #include <iostream>
00012
00013 #include "PiCamera.hpp"
00014
00015 using namespace cv;
00016 using namespace std;
00017 using namespace zbar;
00018 using namespace ChipChipArray;
00019
00025 int main(int argc, char* argv[])
00026 {
00027     PiCamera cam; // open the video camera no. 0
00028     ImageScanner scanner;
00029     scanner.set_config(ZBAR_NONE, ZBAR_CFG_ENABLE, 1);
00030
00031     namedWindow("MyVideo",CV_WINDOW_AUTOSIZE); //create a window called "MyVideo"
00032
00033     while (1)
00034     {
00035         Mat frame = cam.Snap();
00036         Mat grey;
00037         cvtColor(frame, grey, CV_BGR2GRAY);
00038

```

```

00039         int width = frame.cols;
00040         int height = frame.rows;
00041         uchar *raw = (uchar *)grey.data;
00042         // wrap image data
00043         zbar::Image image(width, height, "Y800", raw, width * height);
00044         // scan the image for barcodes
00045         int n = scanner.scan(image);
00046         // extract results
00047         for(Image::SymbolIterator symbol = image.symbol_begin();
00048             symbol != image.symbol_end();
00049             ++symbol) {
00050             vector<Point> vp;
00051             // do something useful with results
00052             cout << "decoded " << symbol->get_type_name() << " symbol \"" << symbol->get_data() << "\" <<
" << endl;
00053             int n = symbol->get_location_size();
00054             for(int i=0;i<n;i++){
00055                 vp.push_back(Point(symbol->get_location_x(i),symbol->get_location_y(i)));
00056             }
00057             RotatedRect r = minAreaRect(vp);
00058             Point2f pts[4];
00059             r.points(pts);
00060             for(int i=0;i<4;i++){
00061                 line(frame,pts[i],pts[(i+1)%4],Scalar(255,0,0),3);
00062             }
00063         }
00064
00065         imshow("MyVideo", frame); //show the frame in "MyVideo" window
00066
00067         if (waitKey(30) == 27) //wait for 'esc' key press for 30ms. If 'esc' key is pressed, break loop
00068         {
00069             cout << "esc key is pressed by user" << endl;
00070             break;
00071         }
00072     }
00073     return 0;
00074
00075 }

```

6.43 src/old_cv_test.cpp File Reference

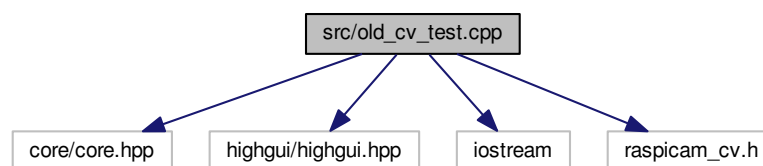
Contains old test program for the RaspiCam_Cv class.

```

#include <core/core.hpp>
#include <highgui/highgui.hpp>
#include <iostream>
#include "raspicam_cv.h"

```

Include dependency graph for old_cv_test.cpp:



Functions

- int [main](#) ()

6.43.1 Detailed Description

Contains old test program for the RaspiCam_Cv class.

Author

Samuel Andrew Wisner, awisner94@gmail.com

Definition in file [old_cv_test.cpp](#).

6.43.2 Function Documentation**6.43.2.1 int main ()**

This program was used to test the raspicam wrapper for OpenCV before implementing it in a more projet-friendly form as the PiCamera class.

Definition at line 17 of file [old_cv_test.cpp](#).

```

00017     {
00018         cv::namedWindow("Test", CV_WINDOW_AUTOSIZE);
00019
00020         raspicam::RaspiCam_Cv cam;
00021         cv::Mat image;
00022
00023         bool s = cam.set(CV_CAP_PROP_FORMAT, CV_16UC3);
00024         bool o = cam.open();
00025
00026         while(true) {
00027             cam.grab();
00028             cam.retrieve(image);
00029             cv::imshow("Test", image);
00030             cv::waitKey(1000);
00031         }
00032     }
00033
00034     cam.release();
00035 }
```

6.44 old_cv_test.cpp

```

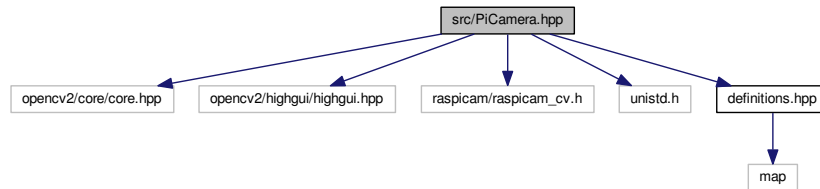
00001
00007 #include <core/core.hpp>
00008 #include <highgui/highgui.hpp>
00009 #include <iostream>
00010
00011 #include "raspicam_cv.h"
00012
00017 int main() {
00018     cv::namedWindow("Test", CV_WINDOW_AUTOSIZE);
00019
00020     raspicam::RaspiCam_Cv cam;
00021     cv::Mat image;
00022
00023     bool s = cam.set(CV_CAP_PROP_FORMAT, CV_16UC3);
00024     bool o = cam.open();
00025
00026     while(true) {
00027         cam.grab();
00028         cam.retrieve(image);
00029         cv::imshow("Test", image);
00030         cv::waitKey(1000);
00031     }
00032
00033     cam.release();
00034
00035 }
```

6.45 src/PiCamera.hpp File Reference

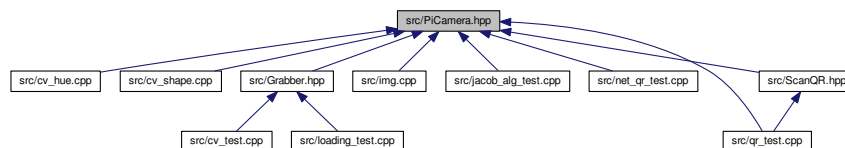
Contains PiCamera class.

```
#include <opencv2/core/core.hpp>
#include <opencv2/highgui/highgui.hpp>
#include <raspicam/raspicam_cv.h>
#include <unistd.h>
#include "definitions.hpp"
```

Include dependency graph for PiCamera.hpp:



This graph shows which files directly or indirectly include this file:



Classes

- class [ChipChipArray::PiCamera](#)

Namespaces

- [ChipChipArray](#)

6.45.1 Detailed Description

Contains PiCamera class.

Author

Samuel Andrew Wisner, awisner94@gmail.com

Definition in file [PiCamera.hpp](#).

6.46 PiCamera.hpp

```
00001
00007 #ifndef PiCamera_H
00008 #define PiCamera_H
00009
00010 #include <opencv2/core/core.hpp>
00011 #include <opencv2/highgui/highgui.hpp>
00012 #include <raspicam/raspicam_cv.h>
```

```

00013 #include <unistd.h>
00014
00015 #include "definitions.hpp"
00016
00017 namespace ChipChipArray {
00018
00019     class PiCamera {
00020     public:
00021         PiCamera() : PiCamera(true) {};
00022
00023         PiCamera(bool useColor);
00024
00025         void Close();
00026
00027         cv::Mat Snap();
00028
00029     private:
00030         raspicam::RaspiCam_Cv cam;
00031     };
00032
00033     PiCamera::PiCamera(bool useColor) {
00034         cam.set(CV_CAP_PROP_FORMAT, (useColor ? CV_16UC3 : CV_16UC1));
00035         cam.open();
00036         usleep(500000); // required to allow camera time to adjust!
00037     }
00038
00039     void PiCamera::Close() {
00040         cam.release();
00041     }
00042
00043     cv::Mat PiCamera::Snap() {
00044         if(!cam.isOpened()) throw std::runtime_error("Camera "
00045             "is not open!");
00046
00047         cv::Mat image;
00048         cam.grab();
00049         cam.retrieve(image);
00050         return image;
00051     }
00052 }
00053 #endif

```

6.47 src/qr_test.cpp File Reference

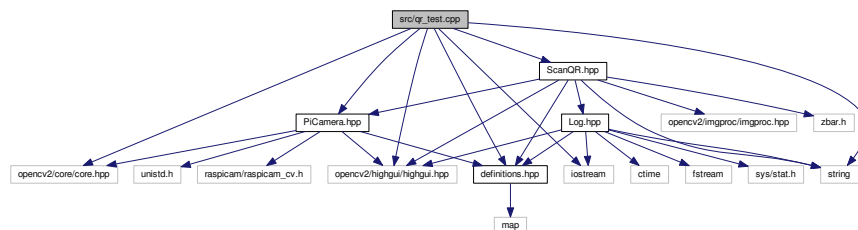
Contains test program for [ScanQR\(\)](#) function.

```

#include <iostream>
#include <opencv2/core/core.hpp>
#include <opencv2/highgui/highgui.hpp>
#include <string>
#include "definitions.hpp"
#include "PiCamera.hpp"
#include "ScanQR.hpp"

```

Include dependency graph for qr_test.cpp:



Functions

- int [main](#) ()

6.47.1 Detailed Description

Contains test program for [ScanQR\(\)](#) function.

Author

Samuel Andrew Wisner, awisner94@gmail.com

Definition in file [qr_test.cpp](#).

6.47.2 Function Documentation

6.47.2.1 int main ()

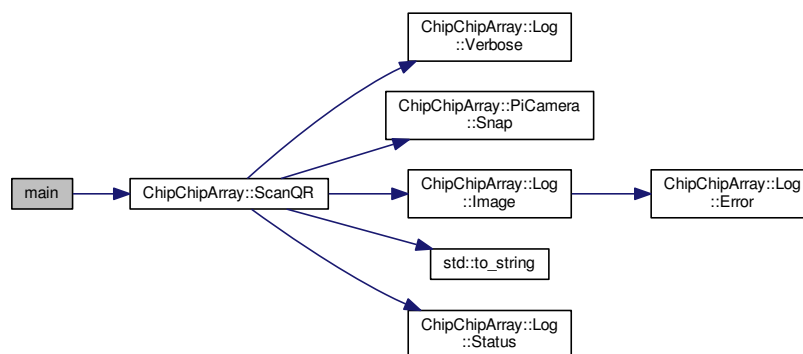
This program tests the [ScanQR\(\)](#) function in terms of reading QR codes (not moving the arm).

Definition at line 22 of file [qr_test.cpp](#).

```

00022     {
00023     while(true) {
00024         Color color = ScanQR();
00025         std::string colstr;
00026
00027         switch(color) {
00028             case Color::Red:
00029                 colstr = "RED";
00030                 break;
00031
00032             case Color::Yellow:
00033                 colstr = "YELLOW";
00034                 break;
00035
00036             case Color::Green:
00037                 colstr = "GREEN";
00038                 break;
00039
00040             case Color::Blue:
00041                 colstr = "BLUE";
00042                 break;
00043         }
00044     }
00045
00046     std::cout << colstr << std::endl;
00047 }
00048 }
```

Here is the call graph for this function:



6.48 qr_test.cpp

```

00001
00007 #include <iostream>
00008 #include <opencv2/core/core.hpp>
00009 #include <opencv2/highgui/highgui.hpp>
00010 #include <string>
00011
00012 #include "definitions.hpp"
00013 #include "PiCamera.hpp"
00014 #include "ScanQR.hpp"
00015
00016 using namespace ChipChipArray;
00017
00022 int main() {
00023     while(true) {
00024         Color color = ScanQR();
00025         std::string colstr;
00026
00027         switch(color) {
00028             case Color::Red:
00029                 colstr = "RED";
00030                 break;
00031
00032             case Color::Yellow:
00033                 colstr = "YELLOW";
00034                 break;
00035
00036             case Color::Green:
00037                 colstr = "GREEN";
00038                 break;
00039
00040             case Color::Blue:
00041                 colstr = "BLUE";
00042                 break;
00043         }
00044
00045         std::cout << colstr << std::endl;
00046     }
00047 }
00048 }

```

6.49 src/ScanQR.hpp File Reference

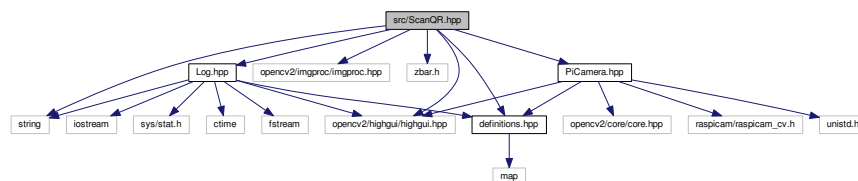
Contains [ScanQR\(\)](#) function.

```

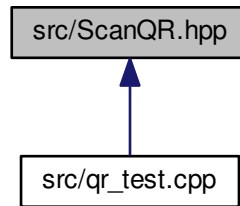
#include <string>
#include <opencv2/highgui/highgui.hpp>
#include <opencv2/imgproc/imgproc.hpp>
#include <zbar.h>
#include "definitions.hpp"
#include "Log.hpp"
#include "PiCamera.hpp"

```

Include dependency graph for ScanQR.hpp:



This graph shows which files directly or indirectly include this file:



Namespaces

- [ChipChipArray](#)

Functions

- [Color ChipChipArray::ScanQR \(\)](#)

Variables

- [uint8 ChipChipArray::qrInvokeCount = 0](#)
- [Log ChipChipArray::scanQrLog \("logs/ScanQR", LogMode::Multi\)](#)

6.49.1 Detailed Description

Contains [ScanQR\(\)](#) function.

Author

Samuel Andrew Wisner, awisner94@gmail.com

Definition in file [ScanQR.hpp](#).

6.50 ScanQR.hpp

```

00001
00007 #ifndef ScanQR_H
00008 #define ScanQR_H
00009
00010 #include <string>
00011 #include <opencv2/highgui/highgui.hpp>
00012 #include <opencv2/imgproc/imgproc.hpp>
00013 #include <zbar.h>
00014
00015 #include "definitions.hpp"
00016 #include "Log.hpp"
00017 #include "PiCamera.hpp"
00018
00019 namespace ChipChipArray {
00020
00024     uint8 qrInvokeCount = 0;
00025

```

```

00029     Log scanQrLog("logs/ScanQR", LogMode::Multi);
00030
00041     Color ScanQR() {
00042         // 0. Initialize variables
00043         Color color;
00044         PiCamera cam(false);
00045
00046         // 1. Position arm
00047         scanQrLog.Verbose("Positioning arm");
00048
00049         // 2. Scan images from camera
00050         scanQrLog.Verbose("Scanning for QR code");
00051
00052         // Nick's supposed to make sure this isn't an endless loop
00053         while(true) {
00054             // get image
00055             cv::Mat frame = cam.Snap();
00056             cv::Mat canvas;
00057             cv::cvtColor(frame, canvas, CV_BGR2GRAY);
00058             scanQrLog.Image(canvas, std::to_string(++qrInvokeCount)
00059                             + ".bmp");
00060
00061             uint32 width = canvas.cols;
00062             uint32 height = canvas.rows;
00063             zbar::Image image(width, height, "Y800",
00064                               (uchar*)canvas.data, width * height);
00065
00066             zbar::ImageScanner scanner;
00067             scanner.set_config(zbar::ZBAR_NONE, zbar::ZBAR_CFG_ENABLE, 1);
00068             scanner.scan(image);
00069             zbar::Image::SymbolIterator symbol = image.symbol_begin();
00070
00071             if(symbol != image.symbol_end()) {
00072                 switch(symbol->get_data()[0]) {
00073                     case 'r':
00074                         color = Color::Red;
00075                         break;
00076
00077                     case 'y':
00078                         color = Color::Yellow;
00079                         break;
00080
00081                     case 'g':
00082                         color = Color::Green;
00083                         break;
00084
00085                     case 'b':
00086                         color = Color::Blue;
00087                         break;
00088                 }
00089
00090                 scanQrLog.Status("Detected " + std::to_string(color)
00091                                 + " train car");
00092                 break;
00093             }
00094         }
00095
00096         // 3. Retract arm
00097         scanQrLog.Verbose("Retracting arm");
00098         return color;
00099     }
00100 }
00101
00102 #endif

```

6.51 src/Servo_Position_Shell.cpp File Reference

Contains the function definitions for the servo position shell.

```

#include <wiringPi.h>
#include "Adafruit_PWMServoDriver.cpp"
#include <iostream>
#include "Servo_Position_Shell.h"

```


- [uint8_t servo_num](#)

6.51.1 Detailed Description

Contains the function definitions for the servo position shell.

Author

Nickolas Neely

Date

8. February 2016, 12:05 PM

Definition in file [Servo_Position_Shell.cpp](#).

6.51.2 Macro Definition Documentation

6.51.2.1 #define SERVOMAX 600

Definition at line 31 of file [Servo_Position_Shell.cpp](#).

6.51.2.2 #define SERVOMIN 150

Definition at line 30 of file [Servo_Position_Shell.cpp](#).

6.51.3 Function Documentation

6.51.3.1 void setServoPosition (Servo *whichservo*, int *position*)

Desc: This function sets which servo to use using *whichservo* and what position out of 180 degrees for each servo (with limits).

Parameters

<i>whichservo</i>	which servo would you like to use on the board
<i>position</i>	what position do you want to set the servo selected at

Definition at line 71 of file [Servo_Position_Shell.cpp](#).

```

00071                                     {
00072     // works for servo 0, 3, 4
00073     double dividedconstant = 180.0;
00074     double highservo = 2.4;
00075     double lowservo = 0.6;
00076     // To fix the magical digital servo on LIFT 1
00077     double highservoweird = 1.9;
00078     double lowservoweird = 0.6;
00079     // To compensate for the bent servo spline on LIFT 2
00080     double highservospline = 2.25;
00081     double lowservospline = 0.6;
00082     // works for servo 1, 2
00083     double digitalservohigh = 2.45;
00084     double digitalservolow = 0.9;
00085     // left gripper servo 5
00086     double gripleftopen = 2.2;
00087     double gripleftclose = 1.3;
00088     // right gripper servo 6
00089     double griprightopen = 2.2;
00090     double griprightclose = 1.3;
00091     double pulse;
00092
00093     switch (whichservo) {

```

```

00094
00095 // BASE TURN
00096 case 0:
00097 {
00098     if (position == -1) {
00099         pulse = 0.0;
00100     } else if (position < 0) {
00101         position = 20;
00102         pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo;
00103     } else if (position > 179) {
00104         position = 179;
00105         pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo;
00106     } else {
00107         pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo;
00108     }
00109 }
00110 }
00111
00112 break;
00113
00114 // BASE TILT
00115 case 1:
00116 {
00117
00118
00119     if (position == -1) {
00120         pulse = 0.0;
00121     } else if (position < 90) {
00122         position = 90;
00123         pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo;
00124     } else if (position > 172) {
00125         position = 172;
00126         pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo;
00127     } else {
00128         pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo;
00129     }
00130 }
00131 break;
00132
00133 // ELBOW
00134 case 2:
00135 {
00136     if (position == -1) {
00137         pulse = 0.0;
00138     } else if (position < 43) {
00139         position = 43;
00140         pulse = (((digitalservohigh - digitalservolow) / dividedconstant)*((double) position)) +
digitalservolow;
00141     } else if (position > 179) {
00142         position = 179;
00143         pulse = (((digitalservohigh - digitalservolow) / dividedconstant)*((double) position)) +
digitalservolow;
00144     } else {
00145         pulse = (((digitalservohigh - digitalservolow) / dividedconstant)*((double) position)) +
digitalservolow;
00146     }
00147 }
00148 break;
00149
00150 // WRIST TURN
00151 case 3:
00152 {
00153     if (position == -1) {
00154         pulse = 0.0;
00155     } else {
00156         pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo;
00157     }
00158 }
00159 break;
00160
00161 // WRIST PAN
00162 case 4:
00163 {
00164     if (position == -1) {
00165         pulse = 0.0;
00166     } else if (position < 0) {
00167         position = 0;
00168         pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo;
00169     } else if (position > 180) {
00170         position = 180;
00171         pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo;
00172     } else {
00173         pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo;
00174     }
00175 }
00176 break;
00177

```

```

00178         // GRIP LEFT
00179     case 5:
00180     {
00181         if (position == -1) {
00182             pulse = 0.0;
00183         } else if (position < 0) {
00184             position = 0;
00185             pulse = (((griprightopen - griprightclose) / dividedconstant)*((double) position)) +
griprightclose);
00186         } else if (position > 90) {
00187             position = 90;
00188             pulse = (((griprightopen - griprightclose) / dividedconstant)*((double) position)) +
griprightclose);
00189         } else {
00190             pulse = (((gripleftopen - gripleftclose) / dividedconstant)*((double) position)) +
gripleftclose);
00191         }
00192     }
00193     break;
00194
00195     // GRIP RIGHT
00196     case 6:
00197     {
00198         if (position == -1) {
00199             pulse = 0.0;
00200         } else if (position < 90) {
00201             position = 90;
00202             pulse = (((griprightopen - griprightclose) / dividedconstant)*((double) position)) +
griprightclose);
00203         } else if (position > 180) {
00204             position = 180;
00205             pulse = (((griprightopen - griprightclose) / dividedconstant)*((double) position)) +
griprightclose);
00206         } else {
00207             pulse = (((griprightopen - griprightclose) / dividedconstant)*((double) position)) +
griprightclose);
00208         }
00209     }
00210     break;
00211
00212     // Michael Yellow Gate
00213     case 7:
00214     {
00215         if (position == -1) {
00216             pulse = 0.0;
00217         } else if (position < 0) {
00218             position = 0;
00219             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00220         } else if (position > 90) {
00221             position = 90;
00222             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00223         } else {
00224             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00225         }
00226     }
00227     break;
00228
00229     // Michael Green Gate
00230     case 8:
00231     {
00232         if (position == -1) {
00233             pulse = 0.0;
00234         } else if (position < 0) {
00235             position = 0;
00236             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00237         } else if (position > 90) {
00238             position = 90;
00239             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00240         } else {
00241             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00242         }
00243     }
00244     break;
00245
00246     // Michael Blue Gate
00247     case 9:
00248     {
00249         if (position == -1) {
00250             pulse = 0.0;
00251         } else if (position < 0) {
00252             position = 0;
00253             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00254         } else if (position > 90) {
00255             position = 90;
00256             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00257         } else {
00258             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);

```

```

00259         }
00260     }
00261     break;
00262
00263     // Michael Lift 1
00264     case 10:
00265     {
00266         if (position == -1) {
00267             pulse = 0.0;
00268         } else if (position < 0) {
00269             position = 0;
00270             pulse = (((highservoweird - lowservoweird) / dividedconstant)*((double) position)) +
lowservoweird);
00271         } else if (position > 105) {
00272             position = 105;
00273             pulse = (((highservoweird - lowservoweird) / dividedconstant)*((double) position)) +
lowservoweird);
00274         } else {
00275             pulse = (((highservoweird - lowservoweird) / dividedconstant)*((double) position)) +
lowservoweird);
00276         }
00277     }
00278     break;
00279
00280     //Michael Lift 2
00281     case 11:
00282     {
00283         if (position == -1) {
00284             pulse = 0.0;
00285         } else if (position < 0) {
00286             position = 0;
00287             pulse = (((highservospline - lowservospline) / dividedconstant)*((double) position)) +
lowservospline);
00288         } else if (position > 105) {
00289             position = 105;
00290             pulse = (((highservospline - lowservospline) / dividedconstant)*((double) position)) +
lowservospline);
00291         } else {
00292             pulse = (((highservospline - lowservospline) / dividedconstant)*((double) position)) +
lowservospline);
00293         }
00294     }
00295     break;
00296
00297     //Michael lift 3
00298     case 12:
00299     {
00300         if (position == -1) {
00301             pulse = 0.0;
00302         } else if (position < 0) {
00303             position = 0;
00304             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00305         } else if (position > 105) {
00306             position = 105;
00307             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00308         } else {
00309             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00310         }
00311     }
00312     break;
00313
00314     // Michael lift 4
00315     case 13:
00316     {
00317         if (position == -1) {
00318             pulse = 0.0;
00319         } else if (position < 0) {
00320             position = 0;
00321             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00322         } else if (position > 105) {
00323             position = 105;
00324             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00325         } else {
00326             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00327         }
00328     }
00329     break;
00330
00331     // Michael RED GATE
00332     case 14:
00333     {
00334         if (position == -1) {
00335             pulse = 0.0;
00336         } else if (position < 0) {
00337             position = 0;
00338             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00339         } else if (position > 105) {

```

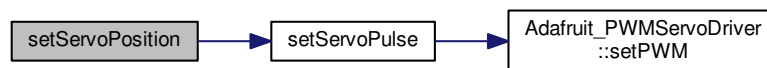


```

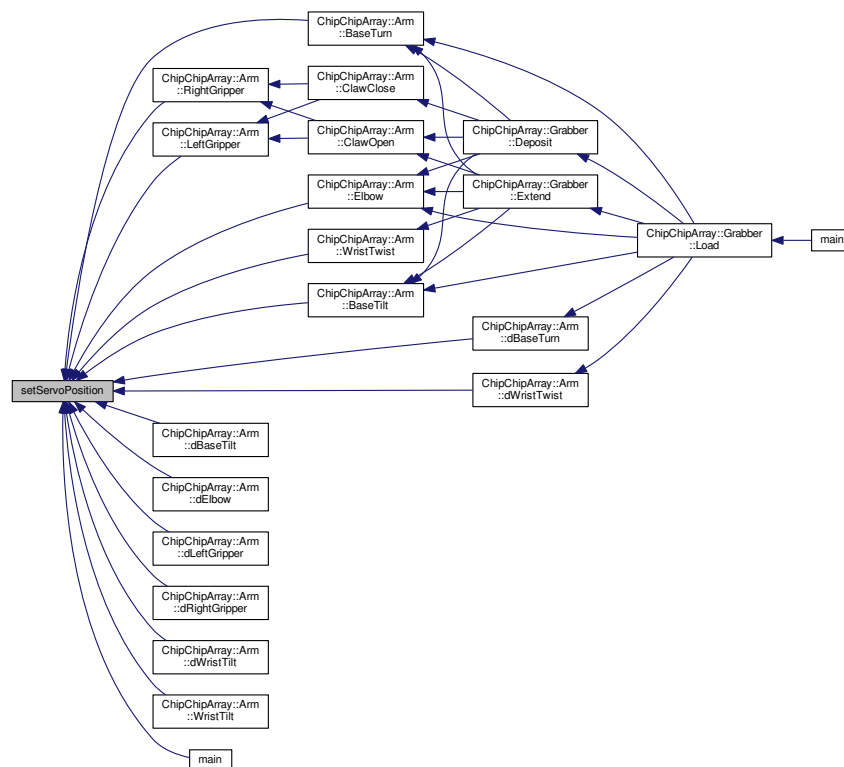
00340         position = 105;
00341         pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00342     } else {
00343         pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00344     }
00345 }
00346     break;
00347 }
00348     setServoPulse(whichservo, pulse);
00349 }
00350 }

```

Here is the call graph for this function:



Here is the caller graph for this function:



6.51.3.2 void setServoPulse (uint8_t n, double pulse)

Desc: This function sets which servo to use and what pulse to set that servos pwm to.

Parameters

<i>n</i>	which servo on the breakout board am I calling. Starting with 0.
<i>pulse</i>	what is the pulse length (in micro seconds) the pwm of the servo is set to.

Definition at line 50 of file [Servo_Position_Shell.cpp](#).

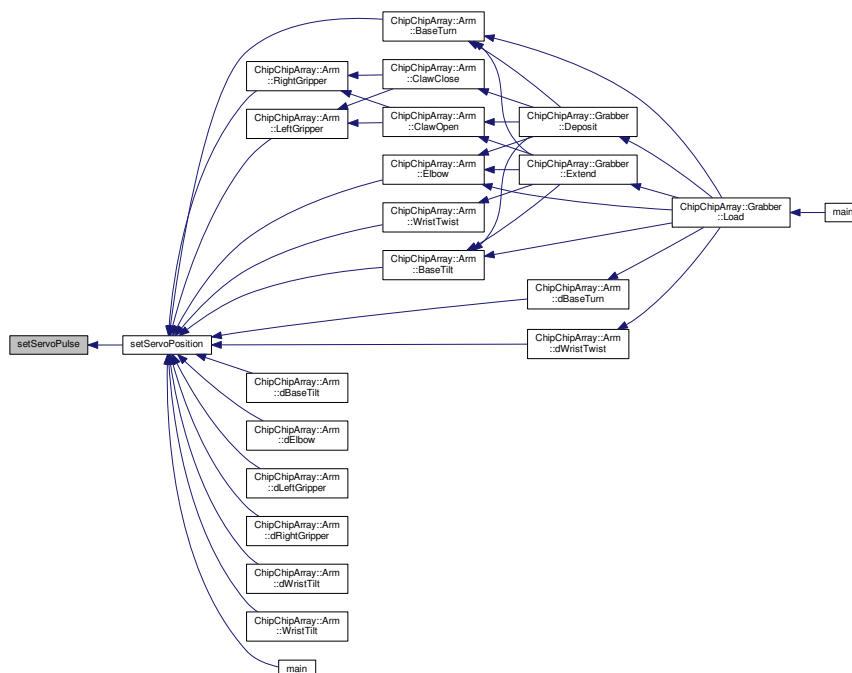
```

00050                                     {
00051     double pulselength;
00052
00053     pulselength = 1000000; // 1,000,000 us per second
00054     pulselength /= 60; // 60 Hz
00055     //cout << pulselength << " us per period" << endl;
00056     pulselength /= 4096; // 12 bits of resolution
00057     //cout << pulselength << "us per bit" << endl;
00058     pulse *= 1000;
00059     pulse /= pulselength;
00060     //cout << (uint16_t) pulse << endl;
00061     pwm.setPWM(servo_num, 0, (uint16_t) pulse);
00062     //cout << endl;
00063 }
```

Here is the call graph for this function:



Here is the caller graph for this function:



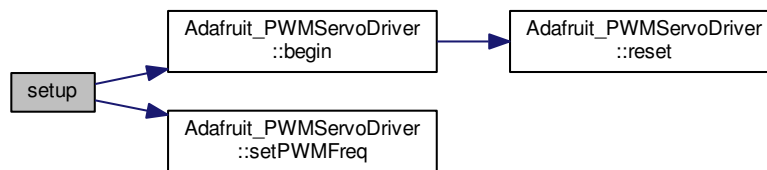
6.51.3.3 void setup ()

Desc: This function sets up the breakout board communication with I2C using Adafruit_PWMServoDriver.cpp and to set the frequency of the servos to 60Hz.

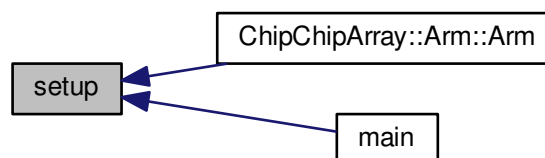
Definition at line 41 of file [Servo_Position_Shell.cpp](#).

```
00041     {
00042     //cout << "Testing Servos" << endl;
00043     pwm.begin();
00044     pwm.setPWMFreq(60.0); // Analog servos run at ~60 Hz updates
00045 }
```

Here is the call graph for this function:



Here is the caller graph for this function:



6.51.4 Variable Documentation

6.51.4.1 Adafruit_PWMServoDriver pwm = Adafruit_PWMServoDriver()

Definition at line 22 of file [Servo_Position_Shell.cpp](#).

6.51.4.2 uint8_t servo_num

Definition at line 34 of file [Servo_Position_Shell.cpp](#).

6.52 Servo_Position_Shell.cpp

```
00001
00008 /*
```

```

00009  * File:    Servo_Position_Shell.cpp
00010  * Author:  Nickolas Neely
00011  *
00012  * Created on February 8, 2016, 12:05 PM
00013  */
00014
00015 #include <wiringPi.h>
00016 #include "Adafruit_PWMServoDriver.cpp"
00017 #include <iostream>
00018 #include "Servo_Position_Shell.h"
00019
00020
00021 // called this way, it uses the default address 0x40
00022 Adafruit_PWMServoDriver pwm = Adafruit_PWMServoDriver();
00023 // you can also call it with a different address you want
00024 //Adafruit_PWMServoDriver pwm = Adafruit_PWMServoDriver(0x41);
00025
00026 // Depending on your servo make, the pulse width min and max may vary, you
00027 // want these to be as small/large as possible without hitting the hard stop
00028 // for max range. You'll have to tweak them as necessary to match the servos you
00029 // have!
00030 #define SERVOMIN 150 // this is the 'minimum' pulse length count (out of 4096)
00031 #define SERVOMAX 600 // this is the 'maximum' pulse length count (out of 4096)
00032
00033 // our servo # counter
00034 uint8_t servo_num;
00035
00041 void setup() {
00042     //cout << "Testing Servos" << endl;
00043     pwm.begin();
00044     pwm.setPWMFreq(60.0); // Analog servos run at ~60 Hz updates
00045 }
00046
00047 // you can use this function if you'd like to set the pulse length in seconds
00048 // e.g. setServoPulse(0, 0.001) is a ~1 millisecond pulse width. its not precise!
00049
00050 void setServoPulse(uint8_t servo_num, double pulse) {
00051     double pulselength;
00052
00053     pulselength = 1000000; // 1,000,000 us per second
00054     pulselength /= 60; // 60 Hz
00055     //cout << pulselength << " us per period" << endl;
00056     pulselength /= 4096; // 12 bits of resolution
00057     //cout << pulselength << "us per bit" << endl;
00058     pulse *= 1000;
00059     pulse /= pulselength;
00060     //cout << (uint16_t) pulse << endl;
00061     pwm.setPWM(servo_num, 0, (uint16_t) pulse);
00062     //cout << endl;
00063 }
00064
00071 void setServoPosition(Servo whichservo, int position) {
00072     // works for servo 0, 3, 4
00073     double dividedconstant = 180.0;
00074     double highservo = 2.4;
00075     double lowservo = 0.6;
00076     // To fix the magical digital servo on LIFT 1
00077     double highservoweird = 1.9;
00078     double lowservoweird = 0.6;
00079     // To compensate for the bent servo spline on LIFT 2
00080     double highservospline = 2.25;
00081     double lowservospline = 0.6;
00082     // works for servo 1, 2
00083     double digitalservohigh = 2.45;
00084     double digitalservolow = 0.9;
00085     // left gripper servo 5
00086     double gripleftopen = 2.2;
00087     double gripleftclose = 1.3;
00088     // right gripper servo 6
00089     double griprihtopen = 2.2;
00090     double griprihtclose = 1.3;
00091     double pulse;
00092
00093     switch (whichservo) {
00094         // BASE TURN
00095         case 0:
00096         {
00097             if (position == -1) {
00098                 pulse = 0.0;
00099             }else if (position < 0){
00100                 position = 20;
00101                 pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo;
00102             }else if (position > 179){
00103                 position = 179;
00104                 pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo;
00105             }else{
00106

```

```

00107         pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00108     }
00109
00110 }
00111
00112     break;
00113
00114     // BASE TILT
00115     case 1:
00116     {
00117
00118
00119         if (position == -1) {
00120             pulse = 0.0;
00121         } else if (position < 90){
00122             position = 90;
00123             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00124         } else if (position > 172){
00125             position = 172;
00126             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00127         } else {
00128             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00129         }
00130     }
00131
00132     break;
00133
00134     // ELBOW
00135     case 2:
00136     {
00137         if (position == -1) {
00138             pulse = 0.0;
00139         } else if (position < 43){
00140             position = 43;
00141             pulse = (((digitalservohigh - digitalservolow) / dividedconstant)*((double) position)) +
00142             digitalservolow);
00143         } else if (position > 179){
00144             position = 179;
00145             pulse = (((digitalservohigh - digitalservolow) / dividedconstant)*((double) position)) +
00146             digitalservolow);
00147         } else {
00148             pulse = (((digitalservohigh - digitalservolow) / dividedconstant)*((double) position)) +
00149             digitalservolow);
00150         }
00151     }
00152
00153     break;
00154
00155     // WRIST TURN
00156     case 3:
00157     {
00158         if (position == -1) {
00159             pulse = 0.0;
00160         } else {
00161             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00162         }
00163     }
00164
00165     break;
00166
00167     // WRIST PAN
00168     case 4:
00169     {
00170         if (position == -1) {
00171             pulse = 0.0;
00172         } else if (position < 0){
00173             position = 0;
00174             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00175         } else if (position > 180){
00176             position = 180;
00177             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00178         } else {
00179             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00180         }
00181     }
00182
00183     break;
00184
00185     // GRIP LEFT
00186     case 5:
00187     {
00188         if (position == -1) {
00189             pulse = 0.0;
00190         } else if (position < 0){
00191             position = 0;
00192             pulse = (((griprightopen - griprightclose) / dividedconstant)*((double) position)) +
00193             griprightclose);
00194         } else if (position > 90){
00195             position = 90;
00196             pulse = (((griprightopen - griprightclose) / dividedconstant)*((double) position)) +
00197             griprightclose);

```

```

00189         } else {
00190             pulse = (((gripleftopen - gripleftclose) / dividedconstant)*((double) position)) +
gripleftclose);
00191         }
00192     }
00193     break;
00194     // GRIP RIGHT
00195     case 6:
00196     {
00197         if (position == -1) {
00198             pulse = 0.0;
00199         } else if(position < 90){
00200             position = 90;
00201             pulse = (((griprightopen - griprightclose) / dividedconstant)*((double) position)) +
griprightclose);
00202         } else if(position > 180){
00203             position = 180;
00204             pulse = (((griprightopen - griprightclose) / dividedconstant)*((double) position)) +
griprightclose);
00205         } else{
00206             pulse = (((griprightopen - griprightclose) / dividedconstant)*((double) position)) +
griprightclose);
00207         }
00208     }
00209     }
00210     break;
00211     // Michael Yellow Gate
00212     case 7:
00213     {
00214         if (position == -1) {
00215             pulse = 0.0;
00216         } else if(position < 0){
00217             position = 0;
00218             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00219         } else if(position > 90){
00220             position = 90;
00221             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00222         } else {
00223             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00224         }
00225     }
00226     }
00227     break;
00228     // Michael Green Gate
00229     case 8:
00230     {
00231         if (position == -1) {
00232             pulse = 0.0;
00233         } else if(position < 0){
00234             position = 0;
00235             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00236         } else if(position > 90){
00237             position = 90;
00238             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00239         } else {
00240             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00241         }
00242     }
00243     }
00244     break;
00245     // Michael Blue Gate
00246     case 9:
00247     {
00248         if (position == -1) {
00249             pulse = 0.0;
00250         } else if(position < 0){
00251             position = 0;
00252             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00253         } else if(position > 90){
00254             position = 90;
00255             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00256         } else {
00257             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00258         }
00259     }
00260     }
00261     break;
00262     // Michael Lift 1
00263     case 10:
00264     {
00265         if (position == -1) {
00266             pulse = 0.0;
00267         } else if(position < 0){
00268             position = 0;
00269             pulse = (((highservoweird - lowservoweird) / dividedconstant)*((double) position)) +
lowservoweird);
00270         }

```

```

00271         } else if(position > 105){
00272             position = 105;
00273             pulse = (((highservoweird - lowservoweird) / dividedconstant)*((double) position)) +
lowservoweird);
00274         } else {
00275             pulse = (((highservoweird - lowservoweird) / dividedconstant)*((double) position)) +
lowservoweird);
00276         }
00277     }
00278     break;
00279
00280     //Michael Lift 2
00281     case 11:
00282     {
00283         if (position == -1) {
00284             pulse = 0.0;
00285         } else if(position < 0){
00286             position = 0;
00287             pulse = (((highservospline - lowservospline) / dividedconstant)*((double) position)) +
lowservospline);
00288         } else if(position > 105){
00289             position = 105;
00290             pulse = (((highservospline - lowservospline) / dividedconstant)*((double) position)) +
lowservospline);
00291         } else {
00292             pulse = (((highservospline - lowservospline) / dividedconstant)*((double) position)) +
lowservospline);
00293         }
00294     }
00295     break;
00296
00297     //Michael lift 3
00298     case 12:
00299     {
00300         if (position == -1) {
00301             pulse = 0.0;
00302         } else if(position < 0){
00303             position = 0;
00304             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00305         } else if(position > 105){
00306             position = 105;
00307             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00308         } else {
00309             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00310         }
00311     }
00312     break;
00313
00314     // Michael lift 4
00315     case 13:
00316     {
00317         if (position == -1) {
00318             pulse = 0.0;
00319         } else if(position < 0){
00320             position = 0;
00321             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00322         } else if(position > 105){
00323             position = 105;
00324             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00325         } else {
00326             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00327         }
00328     }
00329     break;
00330
00331     // Michael RED GATE
00332     case 14:
00333     {
00334         if (position == -1) {
00335             pulse = 0.0;
00336         } else if(position < 0){
00337             position = 0;
00338             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00339         } else if(position > 105){
00340             position = 105;
00341             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00342         } else {
00343             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00344         }
00345     }
00346     break;
00347 }
00348 setServoPulse(whichservo, pulse);
00349
00350 }

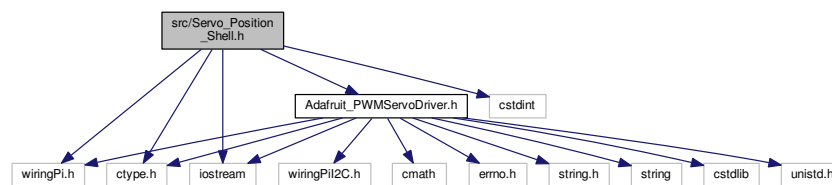
```

6.53 src/Servo_Position_Shell.h File Reference

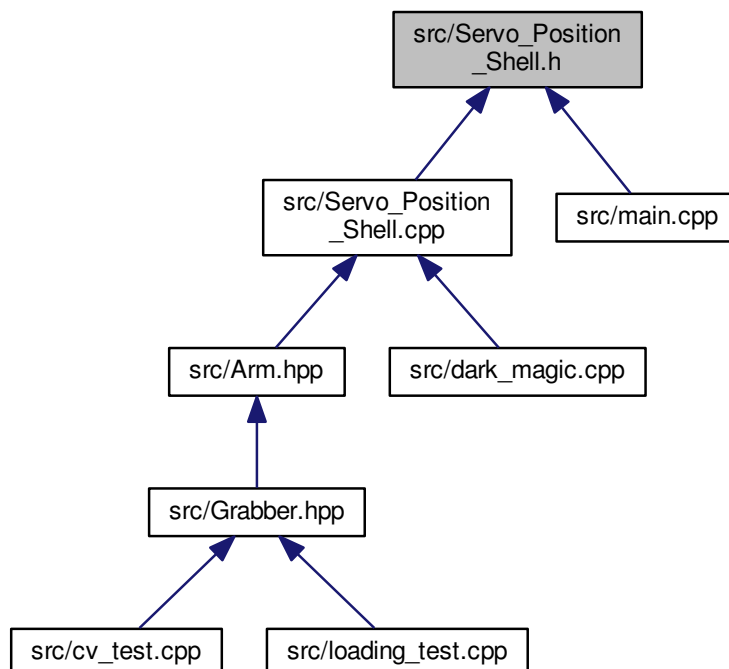
Contains the function prototypes for the servo position shell.

```
#include <wiringPi.h>
#include "Adafruit_PWMServoDriver.h"
#include <iostream>
#include <ctype.h>
#include <cstdint>
```

Include dependency graph for Servo_Position_Shell.h:



This graph shows which files directly or indirectly include this file:



Enumerations

- enum [Servo](#) {
 [BASE_TURN](#) = 0, [BASE_TILT](#) = 1, [ELBOW](#) = 2, [WRIST_TILT](#) = 3,
 [WRIST_PAN](#) = 4, [GRIP_RIGHT](#) = 5, [GRIP_LEFT](#) = 6, [GATE_1](#) = 7,
 [GATE_2](#) = 8, [GATE_3](#) = 9, [LIFT_1](#) = 10, [LIFT_2](#) = 11,
 [LIFT_3](#) = 12, [LIFT_4](#) = 13, [GATE_4](#) = 14 }

Functions

- void [setServoPulse](#) (uint8_t n, double pulse)
- void [setup](#) ()
- void [setServoPosition](#) ([Servo](#) whichservo, int position)

6.53.1 Detailed Description

Contains the function prototypes for the servo position shell.

Author

Nickolas Neely

Date

8. February 2016, 12:05 PM

Definition in file [Servo_Position_Shell.h](#).

6.53.2 Enumeration Type Documentation

6.53.2.1 enum [Servo](#)

Defines each of the servos on the robot.

Enumerator

[BASE_TURN](#)
[BASE_TILT](#)
[ELBOW](#)
[WRIST_TILT](#)
[WRIST_PAN](#)
[GRIP_RIGHT](#)
[GRIP_LEFT](#)
[GATE_1](#)
[GATE_2](#)
[GATE_3](#)
[LIFT_1](#)
[LIFT_2](#)
[LIFT_3](#)
[LIFT_4](#)
[GATE_4](#)

Definition at line 28 of file [Servo_Position_Shell.h](#).

```

00028     {
00029         BASE_TURN = 0,
00030         BASE_TILT = 1,
00031         ELBOW = 2,
00032         WRIST_TILT = 3,
00033         WRIST_PAN = 4,
00034         GRIP_RIGHT = 5,
00035         GRIP_LEFT = 6,
00036         GATE_1 = 7,
00037         GATE_2 = 8,
00038         GATE_3 = 9,
00039         LIFT_1 = 10,
00040         LIFT_2 = 11,
00041         LIFT_3 = 12,
00042         LIFT_4 = 13,
00043         GATE_4 = 14
00044     };

```

6.53.3 Function Documentation

6.53.3.1 void setServoPosition (Servo *whichservo*, int *position*)

Desc: This function sets which servo to use using *whichservo* and what position out of 180 degrees for each servo (with limits).

Parameters

<i>whichservo</i>	which servo would you like to use on the board
<i>position</i>	what position do you want to set the servo selected at

Definition at line 71 of file [Servo_Position_Shell.cpp](#).

```

00071                                     {
00072         // works for servo 0, 3, 4
00073         double dividedconstant = 180.0;
00074         double highservo = 2.4;
00075         double lowservo = 0.6;
00076         // To fix the magical digital servo on LIFT 1
00077         double highservoweird = 1.9;
00078         double lowservoweird = 0.6;
00079         // To compensate for the bent servo spline on LIFT 2
00080         double highservospline = 2.25;
00081         double lowservospline = 0.6;
00082         // works for servo 1, 2
00083         double digitalservohigh = 2.45;
00084         double digitalservolow = 0.9;
00085         // left gripper servo 5
00086         double gripleftopen = 2.2;
00087         double gripleftclose = 1.3;
00088         // right gripper servo 6
00089         double griprightopen = 2.2;
00090         double griprightclose = 1.3;
00091         double pulse;
00092
00093         switch (whichservo) {
00094
00095             // BASE TURN
00096             case 0:
00097             {
00098                 if (position == -1) {
00099                     pulse = 0.0;
00100                 }else if (position < 0){
00101                     position = 20;
00102                     pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo;
00103                 }else if (position > 179){
00104                     position = 179;
00105                     pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo;
00106                 }else{
00107                     pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo;
00108                 }
00109             }
00110
00111             break;
00112
00113             // BASE TILT
00114             case 1:

```

```

00116     {
00117
00118
00119         if (position == -1) {
00120             pulse = 0.0;
00121         } else if (position < 90){
00122             position = 90;
00123             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00124         } else if (position > 172){
00125             position = 172;
00126             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00127         } else {
00128             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00129         }
00130     }
00131     break;
00132
00133     // ELBOW
00134     case 2:
00135     {
00136         if (position == -1) {
00137             pulse = 0.0;
00138         } else if (position < 43){
00139             position = 43;
00140             pulse = (((digitalservohigh - digitalservolow) / dividedconstant)*((double) position)) +
digitalservolow);
00141         } else if (position > 179){
00142             position = 179;
00143             pulse = (((digitalservohigh - digitalservolow) / dividedconstant)*((double) position)) +
digitalservolow);
00144         } else {
00145             pulse = (((digitalservohigh - digitalservolow) / dividedconstant)*((double) position)) +
digitalservolow);
00146         }
00147     }
00148     break;
00149
00150     // WRIST TURN
00151     case 3:
00152     {
00153         if (position == -1) {
00154             pulse = 0.0;
00155         } else {
00156             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00157         }
00158     }
00159     break;
00160
00161     // WRIST PAN
00162     case 4:
00163     {
00164         if (position == -1) {
00165             pulse = 0.0;
00166         } else if (position < 0){
00167             position = 0;
00168             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00169         } else if (position > 180){
00170             position = 180;
00171             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00172         } else {
00173             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00174         }
00175     }
00176     break;
00177
00178     // GRIP LEFT
00179     case 5:
00180     {
00181         if (position == -1) {
00182             pulse = 0.0;
00183         } else if (position < 0){
00184             position = 0;
00185             pulse = (((griprightopen - griprightclose) / dividedconstant)*((double) position)) +
griprightclose);
00186         } else if (position > 90){
00187             position = 90;
00188             pulse = (((griprightopen - griprightclose) / dividedconstant)*((double) position)) +
griprightclose);
00189         } else {
00190             pulse = (((gripleftopen - gripleftclose) / dividedconstant)*((double) position)) +
gripleftclose);
00191         }
00192     }
00193     break;
00194
00195     // GRIP RIGHT
00196     case 6:

```

```

00197     {
00198         if (position == -1) {
00199             pulse = 0.0;
00200         } else if(position < 90){
00201             position = 90;
00202             pulse = (((griprightopen - griprightclose) / dividedconstant)*((double) position)) +
griprightclose);
00203         } else if(position > 180){
00204             position = 180;
00205             pulse = (((griprightopen - griprightclose) / dividedconstant)*((double) position)) +
griprightclose);
00206         }else{
00207             pulse = (((griprightopen - griprightclose) / dividedconstant)*((double) position)) +
griprightclose);
00208         }
00209     }
00210     break;
00211
00212     // Michael Yellow Gate
00213     case 7:
00214     {
00215         if (position == -1) {
00216             pulse = 0.0;
00217         } else if(position < 0){
00218             position = 0;
00219             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00220         } else if(position > 90){
00221             position = 90;
00222             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00223         } else {
00224             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00225         }
00226     }
00227     break;
00228
00229     // Michael Green Gate
00230     case 8:
00231     {
00232         if (position == -1) {
00233             pulse = 0.0;
00234         } else if(position < 0){
00235             position = 0;
00236             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00237         } else if(position > 90){
00238             position = 90;
00239             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00240         } else {
00241             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00242         }
00243     }
00244     break;
00245
00246     // Michael Blue Gate
00247     case 9:
00248     {
00249         if (position == -1) {
00250             pulse = 0.0;
00251         } else if(position < 0){
00252             position = 0;
00253             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00254         } else if(position > 90){
00255             position = 90;
00256             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00257         } else {
00258             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00259         }
00260     }
00261     break;
00262
00263     // Michael Lift 1
00264     case 10:
00265     {
00266         if (position == -1) {
00267             pulse = 0.0;
00268         } else if(position < 0){
00269             position = 0;
00270             pulse = (((highservoweird - lowservoweird) / dividedconstant)*((double) position)) +
lowservoweird);
00271         } else if(position > 105){
00272             position = 105;
00273             pulse = (((highservoweird - lowservoweird) / dividedconstant)*((double) position)) +
lowservoweird);
00274         } else {
00275             pulse = (((highservoweird - lowservoweird) / dividedconstant)*((double) position)) +
lowservoweird);
00276         }
00277     }

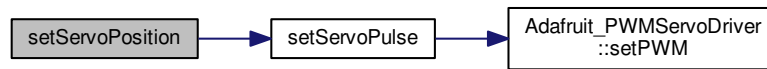
```

```

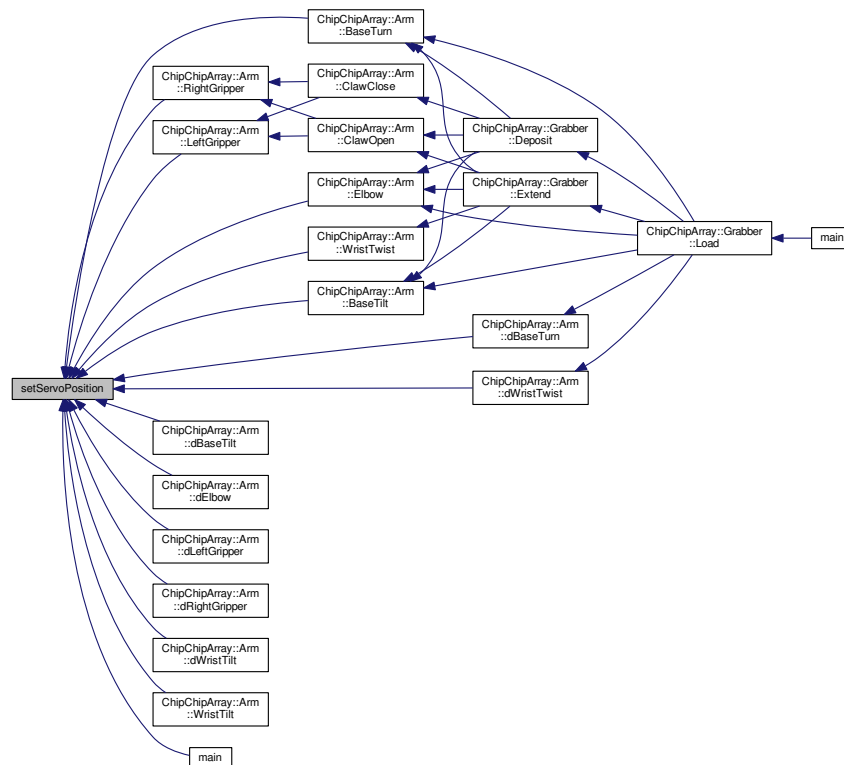
00278         break;
00279
00280         //Michael Lift 2
00281     case 11:
00282     {
00283         if (position == -1) {
00284             pulse = 0.0;
00285         } else if(position < 0){
00286             position = 0;
00287             pulse = (((highservospline - lowservospline) / dividedconstant)*((double) position)) +
00288             lowservospline);
00289         } else if(position > 105){
00290             position = 105;
00291             pulse = (((highservospline - lowservospline) / dividedconstant)*((double) position)) +
00292             lowservospline);
00293         } else {
00294             pulse = (((highservospline - lowservospline) / dividedconstant)*((double) position)) +
00295             lowservospline);
00296         }
00297         break;
00298
00299         //Michael lift 3
00300     case 12:
00301     {
00302         if (position == -1) {
00303             pulse = 0.0;
00304         } else if(position < 0){
00305             position = 0;
00306             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00307         } else if(position > 105){
00308             position = 105;
00309             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00310         } else {
00311             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00312         }
00313         break;
00314
00315         // Michael lift 4
00316     case 13:
00317     {
00318         if (position == -1) {
00319             pulse = 0.0;
00320         } else if(position < 0){
00321             position = 0;
00322             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00323         } else if(position > 105){
00324             position = 105;
00325             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00326         } else {
00327             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00328         }
00329         break;
00330
00331         // Michael RED GATE
00332     case 14:
00333     {
00334         if (position == -1) {
00335             pulse = 0.0;
00336         } else if(position < 0){
00337             position = 0;
00338             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00339         } else if(position > 105){
00340             position = 105;
00341             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00342         } else {
00343             pulse = (((highservo - lowservo) / dividedconstant)*((double) position)) + lowservo);
00344         }
00345         break;
00346     }
00347 }
00348 setServoPulse(whichservo, pulse);
00349
00350 }

```

Here is the call graph for this function:



Here is the caller graph for this function:



6.53.3.2 void setServoPulse (uint8_t n, double pulse)

Desc: This function sets which servo to use and what pulse to set that servos pwm to.

Parameters

<i>n</i>	which servo on the breakout board am I calling. Starting with 0.
<i>pulse</i>	what is the pulse length (in micro seconds) the pwm of the servo is set to.

Definition at line 50 of file [Servo_Position_Shell.cpp](#).

```

00050                                     {
00051     double pulselength;
00052
00053     pulselength = 1000000; // 1,000,000 us per second
00054     pulselength /= 60; // 60 Hz
00055     //cout << pulselength << " us per period" << endl;
00056     pulselength /= 4096; // 12 bits of resolution
  
```

```

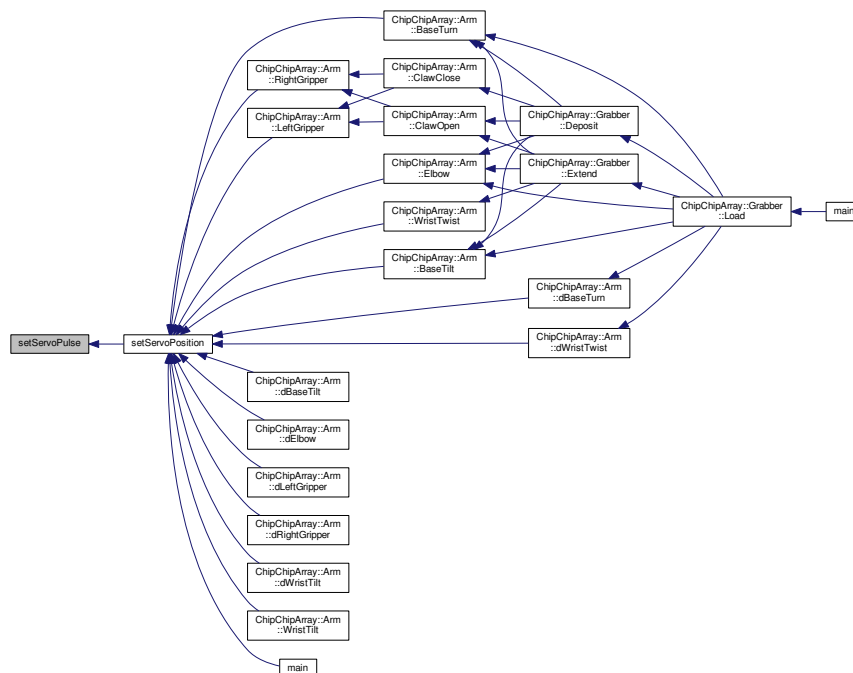
00057     //cout << pulselength << "us per bit" << endl;
00058     pulse *= 1000;
00059     pulse /= pulselength;
00060     //cout << (uint16_t) pulse << endl;
00061     pwm.setPWM(servo_num, 0, (uint16_t) pulse);
00062     //cout << endl;
00063 }

```

Here is the call graph for this function:



Here is the caller graph for this function:



6.53.3.3 void setup ()

Desc: This function sets up the breakout board communication with I2C using Adafruit's `PWMServoDriver.cpp` and to set the frequency of the servos to 60Hz.

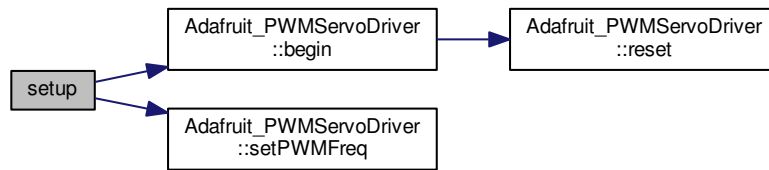
Definition at line 41 of file [Servo_Position_Shell.cpp](#).

```

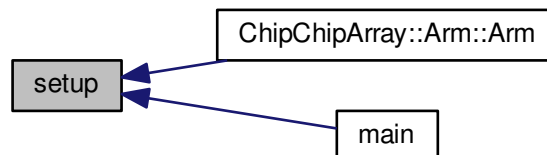
00041     {
00042     //cout << "Testing Servos" << endl;
00043     pwm.begin();
00044     pwm.setPWMPFreq(60.0); // Analog servos run at ~60 Hz updates
00045 }

```

Here is the call graph for this function:



Here is the caller graph for this function:



6.54 Servo_Position_Shell.h

```

00001
00008 /*
00009  * File: Servo_Position_Shell.h
00010  * Author: Nickolas Neely
00011  *
00012  * Created on February 8, 2016, 12:05 PM
00013  */
00014
00015 #ifndef SERVO_POSITION_SHELL_H
00016 #define SERVO_POSITION_SHELL_H
00017
00018
00019
00020 #include <wiringPi.h>
00021 #include "Adafruit_PWMServoDriver.h"
00022 #include <iostream>
00023 #include <ctype.h>
00024 #include <cstdint>
00025
00028 enum Servo{
00029     BASE_TURN = 0,
00030     BASE_TILT = 1,
00031     ELBOW = 2,
00032     WRIST_TILT = 3,
00033     WRIST_PAN = 4,
00034     GRIP_RIGHT = 5,
00035     GRIP_LEFT = 6,
00036     GATE_1 = 7,
00037     GATE_2 = 8,
00038     GATE_3 = 9,
00039     LIFT_1 = 10,
00040     LIFT_2 = 11,
00041     LIFT_3 = 12,
00042     LIFT_4 = 13,
00043     GATE_4 = 14
00044 };
00045
  
```



```
00046 #ifdef __cplusplus
00047 extern "C"{
00048 #endif
00049
00057 void setServoPulse(uint8_t n, double pulse);
00063 void setup();
00070 void setServoPosition(Servo whichservo, int position);
00071
00072 #ifdef __cplusplus
00073 }
00074 #endif
00075
00076 #endif /* SERVO_POSITION_SHELL_H */
00077
```

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