

Robotics with ZumoBot

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Alexander Kirillov

ISLANDBOTS ROBOTIC CLUB

URL: <http://islandbots.org/>

Email address: shurik179@gmail.com



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This work is based in part on *Programming with Robots* by Albert W. Schueller, available from <http://carrot.whitman.edu/Robots/>.

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Introduction

These notes contain a short introduction to programming Zumo 32U4 robot, produced by Pololu, using Arduino IDE. It is intended for people with little to none programming experience.

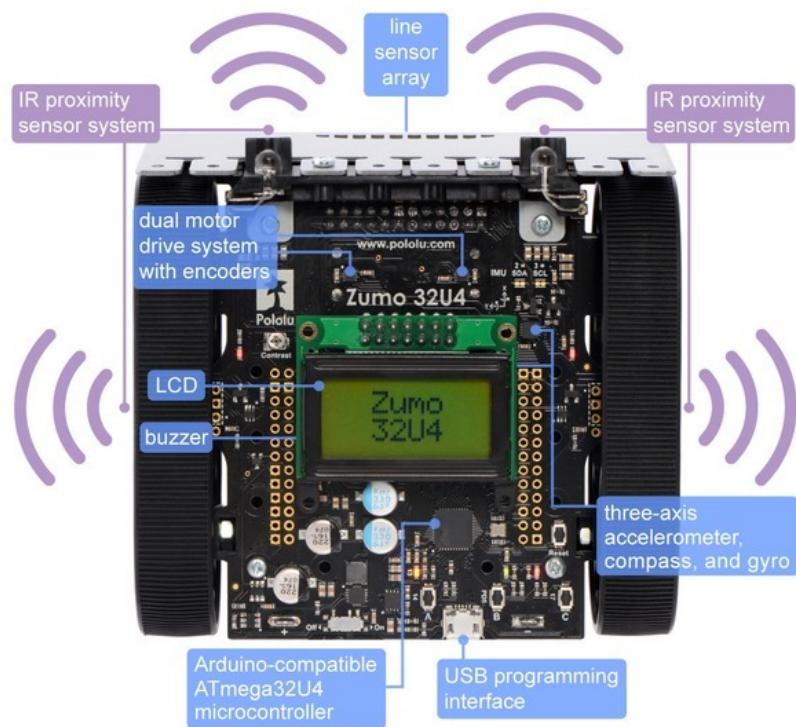
It was originally written for *SigmaCamp* (<http://sigmacamp.org>), a science summer camp where the author was teaching a course on robotics, and for members of *IslandBots* robotics club (<http://islandbots.org>), of which the author is the coach.

If you have any comments, suggestions, or corrections, please send them to shurik179@gmail.com.

Chapter 1

Introducing Zumo robot

Zumo 32U4 is a small tracked robot, manufactured and sold by Pololu: <https://www.pololu.com/product/3124>. At the heart of the robot is ATmega32U4 microcontroller, which can be programmed using a very popular Arduino IDE (integrated development environment), essentially a version of C++ programming language. The robot is equipped with two motors, a small LCD screen, and a variety of sensors.



The robot runs on 4 AA batteries; to program it, you need to connect it to a computer using a microUSB cable (the same cable used by Android cell phones). Detailed description of Zumo robot is given in the user guide on Pololu website: <https://www.pololu.com/docs/0J63>.

Chapter 2

Hello, world!

In this chapter, we run our first program for the Zumo Bot. Our instructions assume that you are using a recent version of Windows operating system (Windows 7 or above). You can also program Zumo on Mac or Linux; check Pololu website for instructions.

2.1. Installing the software

First, you need to install Arduino IDE. It is freely available on Arduino website: <http://arduino.cc>. The installation is straightforward; if you have any difficulties, check the instructions on the website. If you already have Arduino installed, make sure you have a recent version (at least 1.6.2).

Next, you need to install the custom library for Zumo, created by Pololu. To do that:

- In the Arduino IDE, open in the menu SKETCH→INCLUDE LIBRARY→MANAGE LIBRARIES....
- Search for “Zumo32U4”.
- Click the Zumo32U4 entry in the list.
- Click “Install”.

You will also need to install the custom drivers and board definitions for Zumo (not necessary but advised under Windows 10; required for previous versions of Windows). To do this:

- Download the zip file from Pololu website: https://www.pololu.com/file/download/a-star-2.0.0.zip?file_id=0J743
- Extract it to a temporary location
- Inside the extracted folder, find subfolder `drivers`. Right-click on the file `a-star.inf` and select “Install” from the pop-up menu. The installation normally only takes several seconds. In case of any errors, check Zumo User guide, Section 5.1, <https://www.pololu.com/docs/0J63/5.1>, for more details. If you do not get any error messages, it means that the installation was successful.
- Copy the `pololu` folder from the downloaded add-on folder into the `[sketchbook location]\hardware` folder, where `[sketchbook location]` is the directory where your arduino sketches are. Normally it would be `C:\Users\<username>\Documents\Arduino\hardware\pololu`
If the `Arduino` or `hardware` directories do not exist yet, you need to create them.

2.2. Uploading and running programs

You are now ready to upload your first program to Zumo. Start Arduino IDE; it opens an empty program (“sketch”). Ignore it and select in the menu FILE→EXAMPLES→ZUMO32U4→BLINKLEDs. This loads a simple example program, which blinks Zumo’s built-in LEDs. This program is part of Zumo 32U4 library. Read the program and comments to see how it works; even if you are not familiar with these commands, their meaning is easy to guess.

Connect Zumo to the computer using a micro USB cable (it is not necessary to turn Zumo on — USB cable provides the required power). Select in Arduino IDE menu TOOLS→BOARD→POLOLU A-STAR 32U4. After that, go to TOOLS→PORT and select the port which has “Pololu 32U4” next to it. (The board choice is remembered, so you only need to do it once; the port might change every time you reconnect Zumo.)

Now, click on “Upload” icon (a circle with green arrow pointing to the right, immediately under FILE menu). If everything works as expected, some messages will scroll in the bottom area of the window. Wait until you see message “Upload complete” in the green strip between the main part with program code and the bottom part, where the messages were displayed. If you see it, you have successfully uploaded your first program — and it should immediately start working, blinking the LEDs. You now can disconnect Zumo from the computer; the program you uploaded is on it and it will automatically start working every time you turn Zumo on.

2.3. Help and troubleshooting

A description of the basics of Arduino programming is given in Chapter 8. You can also use Arduino IDE’s built-in help (under HELP menu item); in particular, HELP→REFERENCE describes many of the basic functions and structures of Arduino IDE.

Installation of Zumo 32U4 library for Arduino is covered in *Zumo User Guide* <https://www.pololu.com/docs/0J63/5.1>. The library itself is fully documented here: <http://pololu.github.io/zumo-32u4-arduino-library/index.html>.

Chapter 3

Robot motion

We are now ready to start programming the robot. To make it easier, we will be using a set of custom functions, written by Alexander Kirillov, which are slightly more user-friendly than the original Zumo32U4 library.

3.1. First example

Download and extract the zip file **ZumoBot-Shurik**. Navigate to the extracted folder; you will see there the files **ZumoShurik.cpp**, **ZumoShurik.h**, and **ZumoBot.ino**. The first two files contain the custom functions; the last file is an example of a program using these functions. Click on **ZumoBot.ino** to open it in Arduino IDE; it should look like this.

```
#include <Wire.h>
#include <Zumo32U4.h>
#include "ZumoShurik.h"
void setup() {
    // put your setup code here, to run once:
    printLcd("Press A", "to start");
    // wait until user presses button A
    buttonA.waitForButton();
}

void loop() {
    // put your main code here, to run repeatedly:
    // go forward for 400mm=40cm
    goForward(400);
    // turn right 90 degrees
    turn(90);
    beep(400); //produce a beep with frequency 400 hz
    delay(1000); //wait for 1000ms=1 sec
}
```

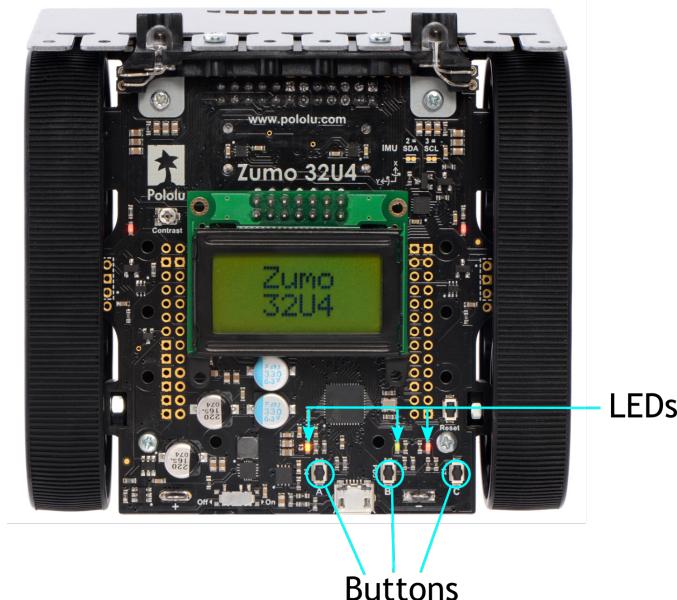
The first two lines load required libraries. Line `#include "ZumoShurik.h"` loads files **ZumoShurik.h** and **ZumoShurik.cpp**. Both of these files must be in the same directory as the Arduino sketch; if you are writing your own program, make sure to copy these files into the program directory. An

easy way to do it is to open the example program and then use FILE→SAVE AS; this will create a copy of the example file and of the files `ZumoShurik.h` and `ZumoShurik.cpp`.

You can upload the example file and run it to see how it works.

3.2. Buttons and LCD

Zumo provides several options for interacting with the user. It has a small 2-line LCD display (up to 8 symbols on each line), several LEDs, and three buttons labelled A, B, and C (the buttons are tiny). In addition, it has a built-in buzzer.



Below are the most useful commands for controlling these elements; all of these commands are available once you have included `Zumo32U4.h` and `ZumoShurik.h`. In this table, as in all the tables that follow, the first column shows the type of value returned by the function. If the function does not return any value, the first column shows `void`.

<code>void</code>	<code>printLcd(String s1, String s2)</code>	Prints the two strings to LCD, as line 1 and line 2. Note that each LCD line can only show 8 symbols.
<code>void</code>	<code>buttonA.waitForButton()</code>	Pause program execution until the button is pressed and released.
<code>void</code>	<code>buttonB.waitForButton()</code>	
<code>void</code>	<code>buttonC.waitForButton()</code>	
<code>void</code>	<code>ledGreen(bool on)</code>	Turns LED on/off. Use <code>on=true</code> or <code>1</code> to turn on, <code>false</code> or <code>0</code> to turn off.
<code>void</code>	<code>ledYellow(bool on)</code>	
<code>void</code>	<code>ledRed(bool on)</code>	
<code>void</code>	<code>beep(int frequency, int duration=500)</code>	produces a beep of specified frequency (in Hz) and duration (in milliseconds). Duration is optional; if omitted, defaults to 500 ms=0.5 sec. For frequency, good choice would be values of 400–2000.

For playing beeps, please note that the program does not wait for the sound to complete: program execution continues while the sound is playing.

3.3. Motor control

The robot has two motors, both equipped with encoders, or rotation counters. The encoders can be used to compute the distance travelled or stop the robot once we have travelled certain distance. To turn, we run the motors in opposite directions.

Below is the list of commands for controlling robot motion.

<code>void goForward(long distance, int speed=70)</code>	Go forward/backward for specified distance, in mm. Distance must always be positive. Optional parameter <code>speed</code> determines speed (must be between 0-100); if it is omitted, default value of 70 is used.
<code>void goBackward(long distance, int speed=70)</code>	
<code>void turn(int angle, int speed=70)</code>	Turn by specified angle (in degrees). Positive angle gives clockwise rotation, negative gives counterclockwise rotation. Optional parameter <code>speed</code> determines speed (must be between 0-100).
<code>void setMotors(int left, int right)</code>	Set the speed of both motors. Speed of each must be between -100 and 100.
<code>void stopMotors()</code>	Self-explanatory
<code>void resetEncoders()</code>	Resets the encoders (rotation counters) on both motors. Note that encoders are also reset when you use <code>goForward()</code> , <code>goBackward()</code> .
<code>int distanceTraveled()</code>	Returns distance travelled since the last encoder reset, in mm. Distance is computed by using the average of both motor encoders. Negative distance corresponds to motion backward.
<code>int angleTurned()</code>	Returns the angle by which the robot has turned since the last encoder reset, in degrees (positive values for clockwise). Angle is computed using the difference of motor encoders and is not very precise.

Parameter `speed` used by `goForward` and `goBackward` is expected to be between 0-100. Values larger than 100 are allowed, but give the same result as the value of 100. Similarly, for `setMotors`, each of the speeds can be lower than -100 or higher than 100, but it gives the same result as value of -100 or 100 respectively.

Chapter 4

Using sensors

In this section, we describe how one uses the sensors provided by Zumo.

4.1. Front sensor array

Zumo contains an array of five infrared reflected light sensors, which are attached at the front of the robot pointing down (see Figure 4.1). They are named DN1 through DN5, with DN1 being the leftmost.

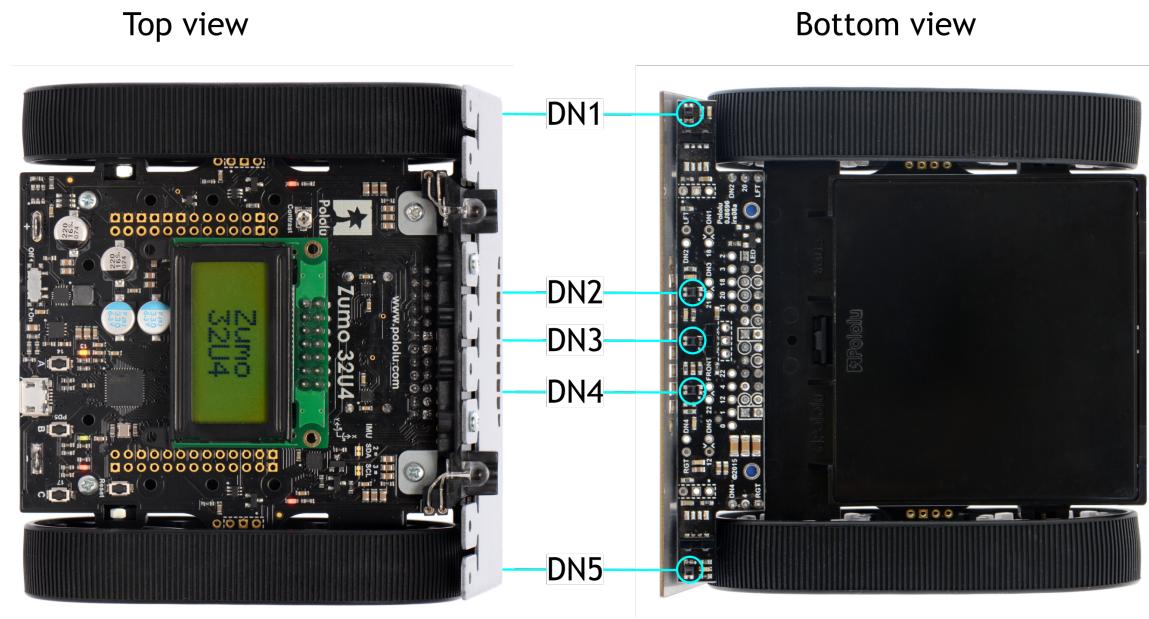


Figure 4.1. Front sensor array

Each sensor combines an infrared LED aimed down, and a photosensitive element, which is used to measure the intensity of reflected light. This allows one to determine how dark the floor is. We will only be using it in the situation when the floor is white, with some black markings, or vice versa (which is a common setup for robotics: black line on white surface could be used as a line to be followed, or as border of the field, or as walls of a maze).

Zumo can be configured in two different ways:

- All five front sensors are active (but then some of the proximity sensors, described in the next section, will be disabled)
- Only three front sensors are active (DN1, DN3, DN5), and all proximity sensors are active.

To switch from one configuration to another, you need to physically move jumpers on the front sensor array; see Section 3.5 in *Zumo User Guide* for details.

Before using sensors, one needs to activate and calibrate them. To do that, use function `calibrateSensors(mode)`, provided by `ZumoShurik` package. This should be done in the `setup` function of the sketch. Allowed values for argument `mode` are `LINEARRAY` (if using the configuration when all five sensors of the front array are active) or `PROXIMITY` (if only three sensors of the front array are active). These values should be entered without quotes — these are predefined constants, not strings.

For calibration, the robot will turn 360 degrees in place, all the time recording the sensor readings. The lowest reading will be interpreted as black level, and the highest as the white level. Thus, before running this function, a robot must be placed so that when rotating, it would see both white and black (e.g., on top of a white line). It is also advised that you put `buttonA.waitForButton()` before and after the calibration function, to make it easier to place the robot in the required starting position.

After the calibration, you can read the sensor values using the functions below.

void	<code>calibrateSensors(mode)</code>	Calibrates line and proximity sensors, by having the robot rotate 360 degrees and determining the highest and lowest value. Allowed values for <code>mode</code> are <code>LINEARRAY</code> and <code>PROXIMITY</code> .
void	<code>readLineSensors()</code>	Reads the values of line sensors (they are saved in an internal variable, which you rarely need to use directly.)
boolean	<code>sensorOnWhite(sensorNum)</code>	Checks whether given front sensor is on white/black. Allowed values of <code>sensorNum</code> are DN1 through DN5. See warning below.
boolean	<code>sensorOnBlack(sensorNum)</code>	
boolean	<code>allOnWhite()</code>	Are all sensors on white? (See warning below.)
boolean	<code>allOnBlack()</code>	Are all sensors on black? (See warning below.)
int	<code>linePosition()</code>	Checks the values of all five sensors and returns the position of the white line under the robot. Returns number between -100 (line all the way to the left of the robot) and 100 (line all the way to the right). Value 0 shows that the robot is centered on the line.



Warning. For performance reasons, getting the values of the sensors is a two-step process: first you call function `readLineSensors()`, which reads all the sensor values at once and saves them. After this, you can use functions `sensorOnWhite()`, etc, which use the sensor values obtained at last reading. Thus, to get accurate results, function `readLineSensors()` must be called shortly before calling functions `sensorOnBlack()` and other functions in the list above. It is a good idea to put `readLineSensors()` function in the beginning of each `loop()`.

Notes:

- (1) The cutoff value used to distinguish between black and white is set in file `ZumoShurik.cpp`. In most cases the default value should work fine, but if you need to change it, search this file for `LIGHT_THRESHOLD` and change the value as required.
- (2) Functions `allOnBlack()`, `allOnWhite()` work in both configurations; in the configuration where only three front sensors are active, they only check the values of these three.
- (3) Function `linePosition()` assumes the white line on black background. It only works in five sensor configuration, and to work reliably, the white line should be at least 3/4 inch wide (standard masking tape, which is 0.94" wide, works well).

Below is a sample program using sensors. This program would have the robot moving forward until at least one of the sensors sees white.

```
#include <Wire.h>
#include <Zumo32U4.h>
#include "ZumoShurik.h"
void setup() {
    printLcd("Press □A", "to start");
    buttonA.waitForButton();
    //calibrate the sensors, in 5 sensor mode
    calibrateSensors(LINEARRAY);
    printLcd("Done", "Press □B");
    buttonB.waitForButton();
}

void loop() {
    readLineSensors();
    if (allOnBlack()) {
        //start going forward, at 70% speed
        setMotors(70,70);
    } else {
        //stop
        stopMotors();
        beep(400);
    }
}
```

4.2. Proximity sensors

Zumo provides several proximity sensors. These sensors combine an infrared LED, which sends pulses of IR light, and IR photosensitive elements, which react to the reflected light. To prevent photosensitive elements from reacting to IR light from other sources, Zumo uses modulated IR light: the receivers only react to the IR light at certain frequency.

These sensors are short-range; exact range depends on the object being detected, its size, and reflectivity (in IR light). Typical range is about 15-20 cm.

Due to technical constraints, these sensors do not give the distance to the object; the return value is determined in a more complicated way. However, the basic rule stays the same: the higher the return value, the stronger the reflected light, and thus, the closer is the object.

Zumo has four IR LEDs used for proximity sensors (left, right, front left, front right) and three IR receivers: the front IR receiver (hidden behind the blade) is used to detect the reflected light from front left and front right IR LEDs. For more technical details, check *Zumo User Guide*.

In the LINEARRAY configuration, when all five sensors of the front line array are active, only the left front and right front IR LEDs (together with the front receiver) are active. In the PROXIMITY configuration, when only 3 sensors of the front line array are active, all proximity LEDs and receivers are active.

To access the readings of proximity sensors, use the functions below.

void	<code>calibrateSensors(mode)</code>	Calibrates line and proximity sensors. Allowed values for <code>mode</code> are LINEARRAY and PROXIMITY .
void	<code>readProxSensors()</code>	Reads the values of proximity sensors (they are saved in an internal variable, which you rarely need to use directly.)
int	<code>proxSensorLevel(sensorNum)</code>	Returns the reading of a given proximity sensor. Allowed values of <code>sensorNum</code> are PROX_L (left), PROX_LF (left front), PROX_RF (right front), PROX_R (right). Returned values can be 0–6; the higher the value, the stronger the reflected light. See warning below.



Warning. For performance reasons, getting the values of the sensors is a two-step process: first you call the function `readLProxSensors()`, which reads all the sensor values at once and saves them. Note that this function takes significant time (about 15ms). After this, you can use functions `proxSensorLevel()`, which use the sensor values obtained at last reading. Thus, to get accurate results, function `readProxSensors()` must be called frequently enough. It is a good idea to put this function in the beginning of each `loop()`.

Chapter 5

Project 1: line follower

In this chapter, we do our first project: a robot that follows a line on the floor. We will make a line by putting 1-inch wide white masking tape on a black surface (a sheet of plywood painted black). You can make your own field; just make sure the line is at least one inch wide and doesn't have sharp turns.

Before we start writing code, we need to describe the algorithm the robot will be using — first in human language, then translate it to C++.

The obvious algorithm is “start on the line; go forward until you get off the line; turn to get back on the line; repeat”.

However, this algorithm will result in very jerky movement: the robot will only start correcting its course when it gets completely off the line. Since we have a whole array of front line sensors, we can use them to detect even small deviation from the right course — when the robot is still on the line, but the line is not exactly under the center of the robot — and start correcting before we get off the line. To correct, we would be going forward but steering more to the left or right as needed: if the line is to the left of the robot center, we must be steering left; if the line is to the right, we must be steering right.

This leads to the following algorithm

```
loop(){
    get the line position
    go forward steering left or right as needed to correct the position
}
```

Note that here we are continuously correcting our steering using the sensor feedback. To translate this algorithm to an actual program, we need to explain how one steers left or right. This is easy: to have the robot steer to the right, we need left motor to have more power than the right. Thus, the command would be `setMotors(70+correction, 70-correction)`. It makes sense to have the parameter `correction` proportional to the difference between the actual line position and the desired one: the farther off we are, the more we need to turn.

This gives the following program

```
float Kp=1.5;
loop(){
    readLineSensors();
    int error=linePosition();
```

```
    setMotors(70+Kp*error, 70-Kp*error);  
}
```

Double-check the sign: if `error` is negative (line to the left), we need to be steering left, so the left motor should have less power than the right; if `error` is positive, we will be steering right.

The value of the coefficient $K_p=1.5$ was chosen so that when the line is all the way to one side ($error=100$), the motors will be given power $70 + 150 = 220$, $70 - 150 = -80$. Since the motor power can't be more than a 100, the actual values would be $100, -80$, so the robot will be essentially turning in place.

You can test what happens if 1.5 is replaced by another value. If the value is too large, the robot will turn very quickly even for small errors, which can lead to the robot spending most time turning left and right, with very little headway. If the value is too small, the robot will be turning very little, which can cause it to miss a sharp turn. You can experiment to find the best value.

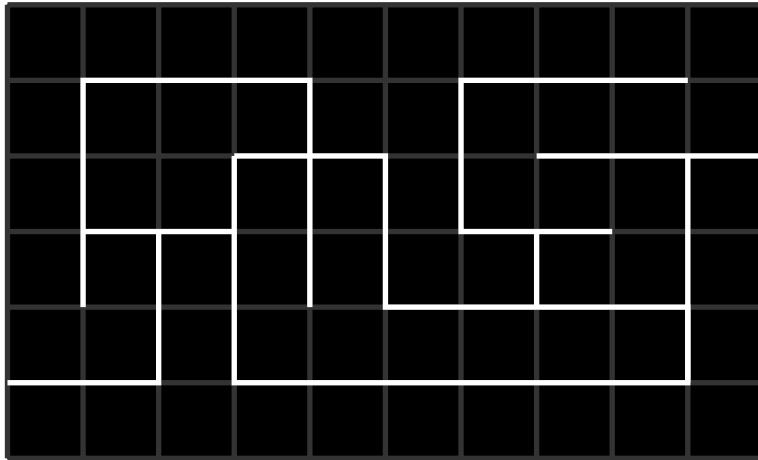
The same idea of correcting the course using sensor feedback, with the correction proportional to the error, can be used in many other situations. Instead of following the line, we could use it to turn to face an obstacle (using front proximity sensors), or face up on an inclined surface, or many other similar situations.

Chapter 6

Project 2: Maze Solver

6.1. Description of the challenge.

The maze is made of approx. 3×5 ft sheet of plywood, painted black. White masking tape (0.94 in wide) is used to mark passages forming the maze; these lines follow rectangular grid with 0.5 ft squares.



The goal is programming a robot to find its way out of the maze, using one of the algorithms described below.

6.2. Wall following algorithm: simplified version

The simplest algorithm for solving the maze is the wall following algorithm:

Start following passages, and whenever you reach a junction always follow the leftmost open passage. This is equivalent to a human walking in the a maze by putting his hand on the left wall and keeping it on the wall as he walks through.

This method is guaranteed to find an exit if we start at the entrance to the maze; then this method allows us to explore a section of the maze and find our way out. However, it is not guaranteed to find an exit if we start in the middle of the maze: the robot could be going in circles around an “island” inside the maze.

The first draft of the program looks as follows (not including `void setup()` function):

```

boolean passageLeft;
int speed;
void loop () {
    goToIntersection();
    checkIntersection();
    if there is a passage to the left, turn left; otherwise do nothing
}

```

Function `goToIntersection()` should follow the line until we reach an intersection.

Function `checkIntersection()` should do two things:

- Move forward so that the center (not front!) of the robot is above the intersection.
- While doing this, check whether there is a passage to the left and set variable `passageLeft`

We can now fill in the details:

```

void goToIntersection(){
    boolean atIntersection=false;
    float Kp=1.5;

    while (!atIntersection) {
        readLineSensors();
        setMotors(speed+Kp*linePosition(),
                  speed-Kp*linePosition());
        atIntersection=sensorOnWhite(DM1) || sensorOnWhite(DM5);
    } //end of while loop
    stopMotors();
}

```

For function `checkIntersection()`, we will be going forward until we have travelled 5 cm; while doing this, we will be checking the line sensors. If the leftmost line sensor (DM1) sees white, we set variable `passageLeft` true. (Also, we should remember to set it to `false` initially):

```

void goToIntersection(){
    passageLeft=false;
    resetEncoders();
    setMotors(speed,speed);
    while (distanceTraveled()<50) {
        readLineSensors();
        if (sensorOnWhite(DM1)) {
            passageLeft=true;
        }
    }
    stopMotors();
}

```

Now, all that remains to do is write the piece of code implementing instruction
`if there is a passage to the left, turn left; otherwise do nothing`,
which is straightforward.

6.3. Wall following: the full version

The algorithm described in the previous section has obvious deficiencies. First, it only checks for open passage to the left. Correct algorithm should check for open passages to left, right, and front, and turn accordingly.

Second, the function `goToIntersection` detects the intersection by using two light sensors, leftmost and rightmost. Thus, it would be unable to detect a dead end.

To fix the first issue, we introduce two more boolean global variables, `passageRight` and `passageForward`, and modify the function `checkIntersection` accordingly. The proper way to detect existence of forward passage should be by checking whether one of the three sensors DM2, DM3, DM4 sees white after we move forward by 5 cm (not during move!).

The second issue is fixed by replacing line

```
atIntersection=sensorOnWhite(DM1) || sensorOnWhite(DM5);  
with  
atIntersection=sensorOnWhite(DM1) || sensorOnWhite(DM5) || allOnBlack();
```

Finally, the logic determining where to turn should be different. Namely, it should be

```
if (passageLeft) {  
    turn(-90);  
} else if (passageForward) {  
    //do nothing  
} else if (passageRight) {  
    turn(90);  
} else {  
    // no open passages left, front, or right  
    turn(180);  
}
```

We leave it to the reader to write the full program.

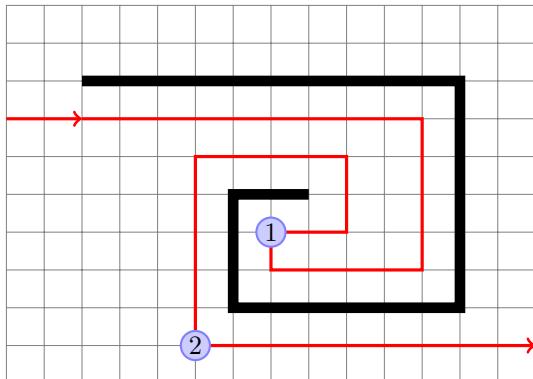
6.4. Pledge algorithm

This is a modified version of wall following that's able to jump between islands, to solve mazes wall following can't. It's a guaranteed way to reach an exit on the outer edge of any 2D maze from any point in the middle. However, it is not guaranteed to visit every passage inside the maze, so this algorithm will not help you if you are looking for a hidden treasure inside the maze.

Start by picking a direction, and always move in that direction when possible. When you hit a wall, start wall following, using the left hand rule. When wall following, count the number of turns you make, e.g. a left turn is -1 and a right turn is 1. Continue wall following until your chosen direction is available again **and** the total number of turns you've made is 0; then stop following wall and go in the chosen direction until you hit a wall. Repeat until you find an exit.

Note: if your chosen direction is available but the total number of turns is not zero (i.e. if you've turned around 360 degrees or more), keep wall following until you untwist yourself. Note that Pledge algorithm may make you visit a passage or the start more than once, although subsequent times will always be with different turn totals.

The figure below illustrates this method:



Thick black lines show the walls of the maze; the red line shows the path of the robot. At point 1, robot turns to so that it is again heading the same direction as in the beginning; however, the number of turns at this point is not zero, so the robot continues following the wall. At point 2, the robot is again heading in the original direction, and the number of turns is zero, so it stops following the wall. Had the robot left the wall at point 1, it would be running in circles.

6.5. Coding Pledge algorithm

To program Pledge algorithm, we need to keep track of robot direction and number of turns. In fact, just the number of turns is sufficient: if we know the number of turns, we can determine the direction. Thus, we introduce a global variable `numTurns`. Every time we turn 90 clockwise, `numTurns` is increased by 1; every time we turn 90 degrees counterclockwise, we decrease `numTurns` by 1.

Thus, the draft of the program would be

```
int numTurns=0;
void loop(){
    goToWall();
    followWall();
}
```

where

- Function `goToWall()` goes forward along the line, through intersections, until the robot hits a wall
- Function `followWall()` follows the wall using left hand rule until we are again facing the same direction as before, with `numTurns=0`.

For each of these functions, we need to describe carefully what conditions the function expects at the start and in what condition it leaves the robot at the end (which way is it facing? is it at intersection?)

For `goToWall()`:

- Initial condition: robot is on the line (i.e., the line is under the center of the front sensor array; robot could be at intersection), `numTurns=0`
- Final state: robot is at an intersection, there is a wall ahead (i.e., no passage forward), and `numTurns=0`

For `followWall()`:

- Initial condition: robot is at an intersection, there is a wall ahead (i.e., no passage forward), and `numTurns=0`
- Final state: robot is on the line (i.e., the line is under the sensor of the front sensor array; robot could be at intersection), `numTurns=0`

When we think about implementing the algorithm, we see that in the very beginning of `followWall()`, the robot needs to turn so that the wall is on its left. Normally it would be just a 90 degree right turn; however, if we are at a dead end, we need to turn 180 degrees. Thus, we need to know whether there is a passage to the right. Therefore, we add one more condition to the final state of `goToWall()`:

- Final state: robot is at the intersection, there is a wall ahead (i.e., no passage forward), `numTurns=0`, and global variable `passageRight` contains information about whether there is a passage to the right.

To implement these two functions, we will make use of the functions `goToIntersection()`, `checkIntersection()` which we used for wall-following algorithm. Implementing `goToWall()` is trivial; for `followWall()`, in the beginning we must put

```
if (passageRight){  
    turn(90); numTurns=numTurns+1;  
} else {  
    //no passage to the right - need to turn 180  
    turn(180); numTurns=numTurns+2;  
}
```

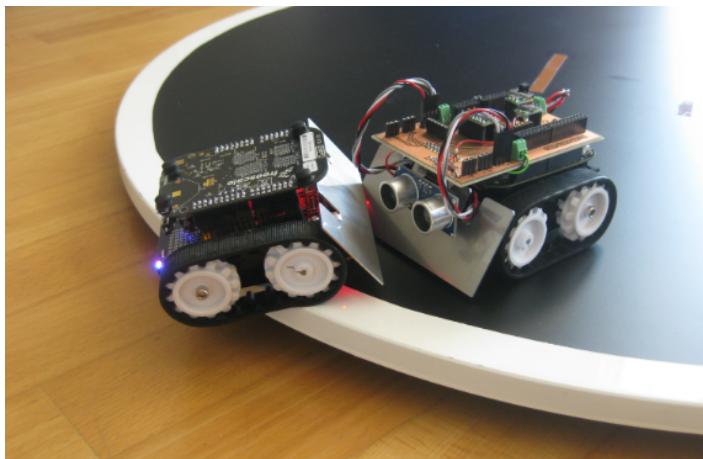
After this, we do the regular line following algorithm: go to intersection, check intersection, turn as needed, except that we should exit the function if, after a “turn as needed”, we have `numTurns=0`.

We leave it to the reader to complete the assignment.

Chapter 7

Project 3: Sumo Bot

In this chapter, we program Zumo for robotic Sumo competition, where the robot is competing against another robot. The goal is to push the opponent out of the field. The field is a circle made out of plywood and painted black. Along the boundary of the field, there is a white strip, so that the robots can detect approach to the field boundary. Official field has diameter of 77 cm and the white border of 2.5 cm (see <http://robogames.net/rules/all-sumo.php>); the field we will be using has diameter of 4 feet and border of 2 inches.



7.1. Initial algorithm

The simplest algorithm for a sumo robot is just randomly driving on the field, turning whenever we approach the field boundary:

```
void loop(){
    readLineSensors();
    if (allOnBlack()){
        setMotors(70,70); //drive forward
    } else {
        //one of the sensors sees white
        goBackward(50); //back up 5 cm
        if (sensorOnWhite(DN1)) {
            //left sensor saw white
            turnLeft(10);
        }
    }
}
```

```
        turn(120); //turn 120 degrees right
    } else {
        //must have been the right sensor
        turn(-120);
    }
}
}
```

Note that the sensor values used in `if(sensorOnWhite(DN1))` line are the values obtained at last `readLineSensors()`, which is before we back up.

7.2. Using proximity sensors

A better algorithm, instead of blindly driving forward, would try to use front proximity sensors to detect the opponent. If we do see the opponent, we should go forward at full speed. If the opponent is not directly ahead but to a side, then we need to steer left or right as needed.

To make the program more readable, we use functions:

```
void loop(){
    readLineSensors();
    if (allOnBlack()){
        lookForOpponent();
    } else {
        //one of the sensors sees white
        backFromEdge();
    }
}
```

Function `backFromEdge()` would be backing up from the edge and turning left/right as needed, using exactly the same code as before. Function `lookForOpponent()` should use the proximity sensors to check for opponent:

```
void lookForOpponent(){
    int left, right, correction;
    readProxSensors();
    left=proxSensorLevel(PROX_LF);
    right=proxSensorLevel(PROX_RF);
    if (left+right<3) {
        //very low signal -- no opponent nearby
        //let us just go forward
        setMotors(70,70);
    } else {
        //we see opponent!
        correction = 30.0*(left-right)/(left+right);
        setMotors(100-correction, 100+correction);
    }
}
```

One thing worth commenting is how we determine the correction to the course. The general idea is similar to the one used in the line following algorithm: we use sensor feedback for correction. In

this case, if left signal is stronger (thus, `correction>0`), then we need to be turning left, i.e. left motor should get less power.

We use the ratio $(l - r)/(l + r)$ as it is a better measure of difference of relative signal strengths. This expression ranges from -1 (if $l = 0$, i.e. the signal only come from the right sensor) to 1 (if the signal only comes from the left sensor). As before, you can experiment what happens if the coefficient of proportionality 30.0 is replaced by a different value.

7.3. Advanced algorithm: using states

The previous algorithm can be improved in several ways. For example, we could also use the side proximitye sensors: if one of them sees the opponent, we need to turn to face it. Also, it seems a good idea that if we have been driving for some time without seeing the opponent, we should stop driving and just turn in place, looking for the opponent.

Trying to write such an agrorithm using the same ideas as before (basically as a series of `if` statements) is not easy and will result in a program which is very difficult to read — and thus, easy to make a mistake. A better (and more common) apporach is to introduce the idea of robot state: at each moment, the robot can be in one of several states, or modes, such as “driving forward”, “sweeping for opponent”, “at edge”, etc. The behavior of the robot would not only depend on the current sensor readings, but also on its state.

Thus, the outline of such a program would be

```
int state;
void loop(){
    set new state
    move depending on the state and current sensors
}
```

A suggested list of states is as follows:

- **Driving:** we do not see an opponent and are just driving forward blindly. This is the default state.
- **At edge:** the robot is at the edge of the field
- **Opponent ahead:** we see an opponent ahead
- **Sweeping right:** robot is sweeping for opponent, by rotating clockwise
- **Sweeping left:** robot is sweeping for opponent, by rotating counterclockwise

For describing the state in the program, we could encode each state by an integer number (say, `Driving =0`) and use these numbers in all our constructions: `if (state==0)....`. A better way is to use `#define` construction:

```
#define DRIVING 0
#define AT_EDGE 1
...
int state;
...
if (state==DRIVING) {
...
}
```

Line `#define DRIVING 0` directs the computer to replace everywhere in the program word `DRIVING` by 0; essentially it defines an alias for the value 0. (Note that there is no equality sign in this construction, and no semicolon.) The benefit of this is that condition `if (state==DRIVING)` is much easier to understand than `if (state==0)`.

We now need to formulate the rules for state change: how the new state of the robot is determined? Generally, the new state will depend on the previous state and current values of sensors. A reasonable choice of rules is as follows:

- If one of line sensors sees white, the state should be set to `AT_EDGE` (regardless of the previous state)
- Otherwise, if the front proximity sensors see opponent, the state should be set to `OPPONENT_AHEAD` (regardless of previous state)
- Otherwise, if the left/right proximity sensor sees opponent, the state should be set to `SWEET_LEFT` or `SWEET_RIGHT`

These rules deal with immediate reaction to sensors. What about when the sensors do not see anything?

- If the current state is `DRIVING` and we have been in this state long enough, set new state to `SWEET_LEFT` (i.e., start looking for an opponent)
- If the current state is `SWEET_LEFT/SWEET_RIGHT`, and we have been in this state long enough, set the new state to `DRIVING`; otherwise keep sweeping.
- If none of the above rules apply, set the state to `DRIVING`

The last rule is a general catch-all: it should deal, for example, with the situation when we were seeing the opponent ahead, and then it suddenly disappeared, or when we just backed up from the edge.

To make precise “long enough” used in the rules above, we could use motor encoders. For example, for driving, we could reset the encoders when we begin driving, and then use condition `distanceTraveled()>2000` instead of “long enough” (2000 mm=2 m).

Similarly, for sweeping left/right, we could also reset the encoders once the sweep begins, and use `abs(angleTurned())>360` as the condition.

Now that we have all these rules, we can program them. We will make a separate function `setState()` that does this.

```
#define DRIVING 0
#define AT_EDGE 1
#define SWEET_RIGHT 2
#define SWEET_LEFT 3
#define OPPONENT_AHEAD 4
int state;
void setState(){
    readLineSensors();
    if (sensorOnWhite(DM1)||sensorOnWhite(DM5)) {
        state=AT_EDGE;
        return;
    }
    readProxSensors();
    if (proxSensorLevels(PROX_LF)+proxSensorLevels(PROX_RF)>3) {
```

```

        state=OPPONENT_AHEAD;
        return;
    }
    if (proxSensorLevels(PROX_L)>1) {
        resetEncoders();
        state=SWEET_LEFT;
        return;
    }
    if (proxSensorLevels(PROX_R)>1) {
        resetEncoders();
        state=SWEET_RIGHT;
        return;
    }
    if (proxSensorLevels(PROX_LF)+proxSensorLevels(PROX_RF)>3) {
        state=OPPONENT_AHEAD;
        return;
    }
    if (state==DRIVING) {
        if (distanceTraveled()>2000) {
            state=SWEET_LEFT;
            resetEncoders();
        }
        //otherwise, do nothing - continue driving
        return;
    }
    if (state==SWEET_LEFT || state==SWEET_RIGHT){
        if (abs(angleTurned())>360) {
            state=DRIVING;
            resetEncoders();
        }
        //otherwise, do nothing - continue sweeping
        return;
    }
    //and finally, catch-all rule
    state=DRIVING;
    resetEncoders();
}

```

The main program would now look like this:

```

void loop(){
    setState();
    switch (state) {
        case DRIVING:
            setMotors(70,70);
            break;
        case AT_EDGE:
            ...
            break;
    }
}

```

```
    case SWEEP_LEFT:  
        ...  
        break;  
    case SWEEP_RIGHT:  
        ...  
        break;  
    case OPPONENT_AHEAD:  
        ...  
        break;  
  
    }  
}
```

The code for setting robot motion in OPPONENT_AHEAD state should be steering left/right, using the values of two front proximity sensors for feedback, as was done in the previous section.

Chapter 8

Appendix A: Arduino basics

8.1. Basic program structure

```
void setup() {  
    // put your setup code here, to run once:  
}  
  
void loop() {  
    // put your main code here, to run repeatedly:  
}
```

Comments. Single-line comment: everything from `//` to end of line.

Multi-line comment: everything between `/*` and `*/`:

```
x=x+1; //this is a single line comment  
/* and this is a  
multi-line comment */
```

Control structures.

```
// if statements  
if (condition) {  
    ...  
} else {  
    ...  
}  
//while loops  
while(condition){  
    ...  
}
```

Logical operators. Used to construct conditions:

Comparison: == (e.g., if (x==5) {...}).

AND: &&

OR: ||

NOT: !

```
while (time<1000 && !sensorOnWhite()){
  ...
}
```



Warning. When comparing two values, make sure you use == rather than =. A common beginners mistake is writing something like if (x=5). Instead of checking whether x is equal to 5, this will **assign** to x value 5 (and will give true logical value).

8.2. Variables and constants

Variable declaration:

```
int n=10;
```

Usually these declarations are placed in the beginnign of the file, before void setup().

Basic variable types: int, long (long integer, gives larger range), float, boolean, String (note uppercase!).

Constant declarations:

```
constant int CUTOFF=40;
```

Pre-defined boolean constants: true, false.

Strings. Defining a string: String s="Hello\World!";

(note the double quotes).

Turning numbers into strings:

```
float x=5.17
String s=String(x);
```

Concatenating (putting together) strings:

```
String s="x="+String(x);
```

8.3. Functions

Some standard functions.

<code>int</code>	<code>abs(int x)</code>	Absolute value. Instead of <code>int</code> , can also use <code>float</code>
<code>int</code>	<code>max(int x, int y)</code>	Maximum of two numbers. Instead of <code>int</code> , can also use <code>float</code>
<code>long</code>	<code>millis()</code>	Number of milliseconds since the program started
<code>void</code>	<code>delay(unsigned long ms)</code>	Pause program executions for specified number of milliseconds

Defining your own functions. To define your own function, you need to declare it as shown below:

```
int myFunction(int a, int b){
    body of the function
}
```

This declaration can be placed in any place in the file (but not inside other functions); usually it is placed after the end of `loop()`.

The first word (in this case `int`) is the type of the value returned by the function. If your function does not return any values, use `void`.

`myFunction` is the name of the function; it must satisfy the usual properties (can only contain letters, digits, and underscore, and can not coincide with existing variable and function names).

After function name, you put in parentheses the arguments, or inputs to the function. In this case, there are two arguments, both of type `int`. If your function does not have any arguments, put nothing between the parentheses: `myFunction()`.

Inside the body of the function, you can put any code. You can also use global variables (those defined in the beginning of the program, outside of any functions) and arguments (such as `a`, `b` in the example above). You can also introduce new variables, called local variables; these variables will only be accessible inside the function, and their values are not saved once the function execution completes: if the same function is called again, the values of local variables are initialized again.

To finish the function and return a value, use `return(value);`.

Below is an example of a function, which computes the factorial of a number: $n! = 1 \cdot 2 \cdots \cdot n$.

```
int factorial(int n){
    int f=1;
    int i=1;
    if (n<0) { //invalid input!
        return(0);
    }
    while (i<=n) {
        f=f*i;
        i=i+1;
    }
    return(f);
}
```