

Porthos

An-embedded-linux-robot

0.0.0-cmake

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Chapter 1

Porthos

This project tries to create an embedded linux robot system.

A high-level description of the system is given in the `system_description`. Some requirements have been created, but these are still very much open to discussion.

The compiled documentation can be read at <http://spoorcc.github.io/porthos/> And the PDF at <http://spoorcc.github.io/porthos/Porthos.pdf>

Compiling

```
mkdir bld
cd bld
cmake ..
make
```

Generating documentation

```
cd bld
make doc
```


Chapter 2

Licensing

This page describes the licencing for the Porthos system.

2.1 Licensing of documentation

Todo determine licensing

2.2 Licensing of source code

Todo determine licensing

Chapter 3

System Description

Describes the robot system on high-level

Chapter 4

Testing

This page describes the testing procedures for the Porthos project.

4.1 Unittests

This project uses check for testing the C-code In order to run the tests do the following

```
cd bld
cmake ..
make
make test
```

To have more output for analyzing failing tests use follwoing command instead of make test:

```
ctest --verbose
```


Chapter 5

Workflow

This page describes the workflow for the Porthos project.

5.1 Workflow

This project works following the git-flow branching model. Each feature is developed on a feature branch, branched off of develop. Check out <http://nvie.com/posts/a-successful-git-branching-model/> for more info.

The below workflow is based on <http://qq.is/tutorial/2011/10/23/git-flow-on-github.html>.

5.2 Setting up

First clone the repository

```
git clone https://github.com/spoorcc/porthos.git
```

Go into the repo

```
cd porthos
```

Setup the origin

```
git remote add upstream git@github.com:spoorcc@porthos
```

Setup git flow (first install git flow if you haven't got it)

```
git flow init
```

And accept all the defaults

5.3 Starting on your feature

Create a new branch for your awesome feature

```
git flow feature start <my_great_feature>
```

Push the branch remote.

```
git flow feature publish <my_great_feature>
```

Commit your changes regularly locally with descriptive messages.

Also push the changes back up to GitHub.

```
git push origin HEAD
```

5.4 Finish work

Create a pull request in the GitHub interface. In the pull request add useful info. Click the send pull request to confirm you think you're done.

When your awesome feature is reviewed, sometimes additional changes are needed. Make them locally, commit and push them up to your branch.

Make sure you're on your feature branch:

```
git checkout feature/<my_awesome_feature>
```

Do your development, commit and push the changes again. (see [Starting on your feature](#)).

5.5 Cleanup

When all your changes are agreed upon and merged by the project, your feature branch will be deleted. Locally you can finish your feature as well.

```
git flow feature finish
```


Chapter 6

Todo List

Page [Licensing](#)

determine licensing

determine licensing

Chapter 7

Class Index

7.1 Class List

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

position_t	17
--------------------------------------	----

Chapter 8

File Index

8.1 File List

Here is a list of all files with brief descriptions:

motion.c	19
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Chapter 9

Class Documentation

9.1 position_t Struct Reference

```
#include <motion.h>
```

Public Attributes

- double [x](#)
- double [y](#)

9.1.1 Detailed Description

Simple position struct

9.1.2 Member Data Documentation

9.1.2.1 x

```
double position_t::x
```

9.1.2.2 y

```
double position_t::y
```

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

- [motion.h](#)

Chapter 10

File Documentation

10.1 licensing.dox File Reference

10.2 motion.c File Reference

```
#include <stdio.h>
#include <math.h>
#include "motion.h"
```

Functions

- int `motion_init` ()
Initializes the motion library.
- int `motion_get_distance` (float *const distance)
- int `motion_get_direction` (float *const direction)
- int `motion_get_goal_direction` (float *const direction)
- int `motion_get_current_position` (`position_t` *const position)
Returns current position.
- int `motion_move_to` (`position_t` const *const position)
Sets goal position.
- int `motion_update` (void)
- int `motion_update_direction` (void)

10.2.1 Function Documentation

10.2.1.1 `motion_get_current_position()`

```
int motion_get_current_position (
    position_t *const position )
```

Returns current position.

10.2.1.2 `motion_get_direction()`

```
int motion_get_direction (
    float *const direction )
```

10.2.1.3 motion_get_distance()

```
int motion_get_distance (
    float *const distance )
```

10.2.1.4 motion_get_goal_direction()

```
int motion_get_goal_direction (
    float *const direction )
```

10.2.1.5 motion_init()

```
int motion_init ( )
```

Initializes the motion library.

The motion library is initialized and ready to use.

10.2.1.6 motion_move_to()

```
int motion_move_to (
    position_t const *const position )
```

Sets goal position.

10.2.1.7 motion_update()

```
int motion_update (
    void )
```

10.2.1.8 motion_update_direction()

```
int motion_update_direction (
    void )
```

10.3 motion.h File Reference

```
#include <stdio.h>
```

Classes

- struct [position_t](#)

Enumerations

- enum [MotionError](#) { [MOTION_OK](#) = 0, [MOTION_PARAMETER_ERROR](#) }

Functions

- int [motion_init](#) ()

Initializes the motion library.

- int `motion_get_current_position` (`position_t` *const position)

Returns current position.

- int `motion_get_distance` (float *const distance)
- int `motion_get_direction` (float *const degrees)
- int `motion_get_goal_direction` (float *const degrees)
- int `motion_move_to` (`position_t` const *const position)

Sets goal position.

- int `motion_update` (void)
- int `motion_update_direction` (void)

10.3.1 Enumeration Type Documentation

10.3.1.1 MotionError

enum `MotionError`

error code for library

Enumerator

<code>MOTION_OK</code>	Everything went OK
<code>MOTION_PARAMETER_ERROR</code>	Wrong parameter was provided

10.3.2 Function Documentation

10.3.2.1 `motion_get_current_position()`

```
int motion_get_current_position (
    position_t *const position )
```

Returns current position.

10.3.2.2 `motion_get_direction()`

```
int motion_get_direction (
    float *const degrees )
```

10.3.2.3 `motion_get_distance()`

```
int motion_get_distance (
    float *const distance )
```

10.3.2.4 `motion_get_goal_direction()`

```
int motion_get_goal_direction (
    float *const degrees )
```

10.3.2.5 `motion_init()`

```
int motion_init ( )
```

Initializes the motion library.

The motion library is initialized and ready to use.

10.3.2.6 `motion_move_to()`

```
int motion_move_to (
    position_t const *const position )
```

Sets goal position.

10.3.2.7 `motion_update()`

```
int motion_update (
    void )
```

10.3.2.8 `motion_update_direction()`

```
int motion_update_direction (
    void )
```

10.4 README.md File Reference

10.5 system_description.dox File Reference

10.6 test_libmotion.c File Reference

```
#include <check.h>
#include <stdio.h>
#include "motion.h"
```

Macros

- `#define NR_GET_DEG_TESTS` (6)
Test getting goal direction.

Functions

- void `test_init` (void)
Test initialization.
- void `test_get_current_position_GW001` (void)
Test getting position.
- void `test_get_current_position_BW001` (void)
Test getting position - NULL parameter.
- void `test_move_to_GW001` (void)
Test setting position.
- void `test_move_to_BW001` (void)
Test setting position - NUL parameter.
- void `test_get_distance_GW001` (void)

Test getting distance.

- void [test_get_distance_BW001](#) (void)

Test getting distance.

- void [test_get_direction_GW001](#) (void)

Test getting direction.

- void [test_get_direction_BW001](#) (void)

Test getting distance.

- void [test_get_goal_direction_GW001](#) (void)
- void [test_get_goal_direction_BW001](#) (void)

Test getting goal direction.

- void [test_update_direction_GW001](#) (void)

Test updating direction.

- void [test_update_direction_GW002](#) (void)

Test updating direction.

- Suite * [motion](#) (void)
- int [main](#) (int argc, char *argv[])

10.6.1 Macro Definition Documentation

10.6.1.1 NR_GET_DEG_TESTS

```
#define NR_GET_DEG_TESTS (6)
```

Test getting goal direction.

10.6.2 Function Documentation

10.6.2.1 main()

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

10.6.2.2 motion()

```
Suite* motion (
    void )
```

10.6.2.3 test_get_current_position_BW001()

```
void test_get_current_position_BW001 (
    void )
```

Test getting position - NULL parameter.

10.6.2.4 test_get_current_position_GW001()

```
void test_get_current_position_GW001 (
    void )
```

Test getting position.

10.6.2.5 test_get_direction_BW001()

```
void test_get_direction_BW001 (  
    void )
```

Test getting distance.

10.6.2.6 test_get_direction_GW001()

```
void test_get_direction_GW001 (  
    void )
```

Test getting direction.

10.6.2.7 test_get_distance_BW001()

```
void test_get_distance_BW001 (  
    void )
```

Test getting distance.

10.6.2.8 test_get_distance_GW001()

```
void test_get_distance_GW001 (  
    void )
```

Test getting distance.

10.6.2.9 test_get_goal_direction_BW001()

```
void test_get_goal_direction_BW001 (  
    void )
```

Test getting goal direction.

10.6.2.10 test_get_goal_direction_GW001()

```
void test_get_goal_direction_GW001 (  
    void )
```

10.6.2.11 test_init()

```
void test_init (  
    void )
```

Test initialization.

Test initialization of Motion library

10.6.2.12 test_move_to_BW001()

```
void test_move_to_BW001 (  
    void )
```

Test setting position - NUL parameter.

10.6.2.13 test_move_to_GW001()

```
void test_move_to_GW001 (  
    void )
```

Test setting position.

10.6.2.14 test_update_direction_GW001()

```
void test_update_direction_GW001 (  
    void )
```

Test updating direction.

10.6.2.15 test_update_direction_GW002()

```
void test_update_direction_GW002 (  
    void )
```

Test updating direction.

10.7 testing.dox File Reference**10.8 workflow.dox File Reference**

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