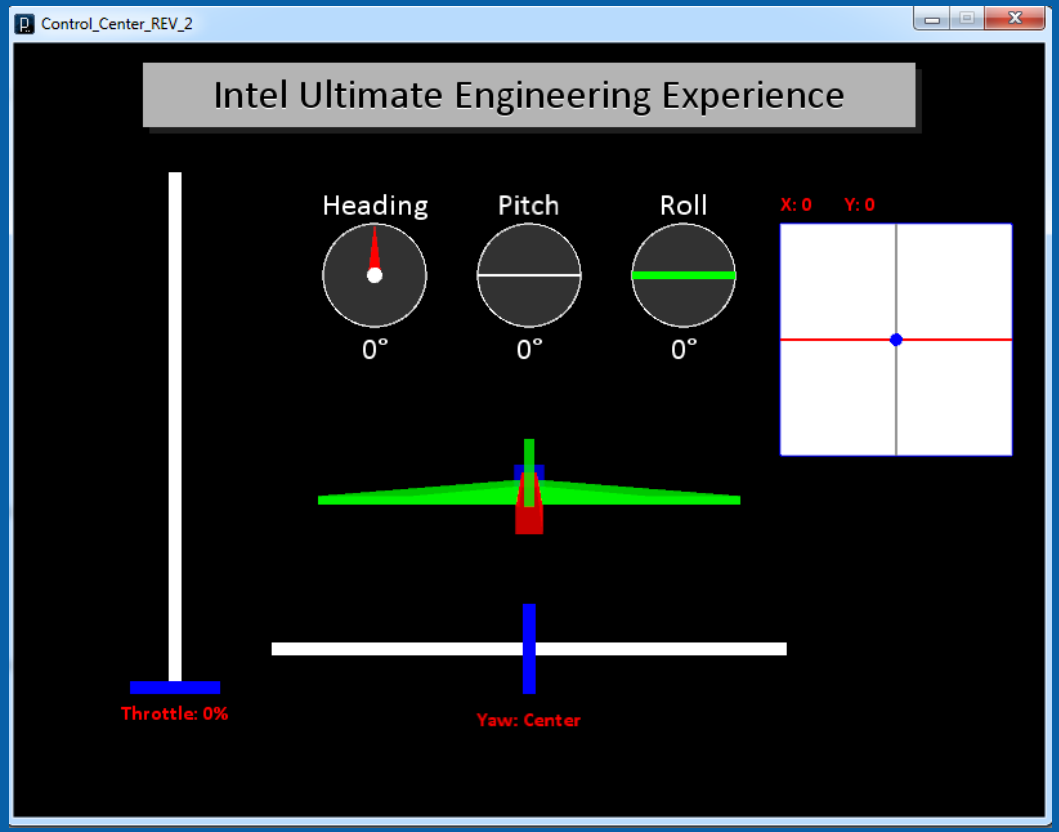


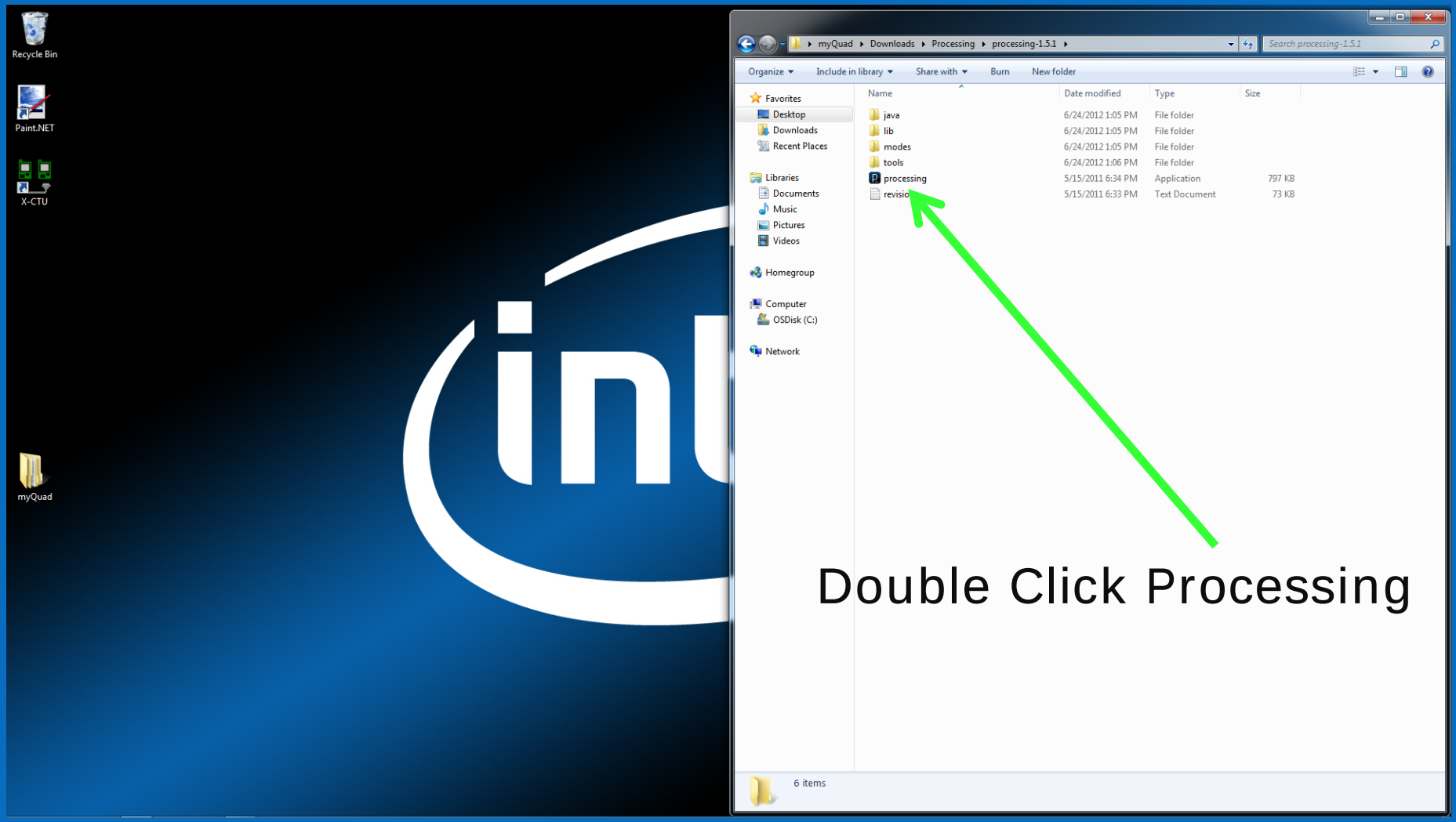
Session Three

Getting Started With Processing

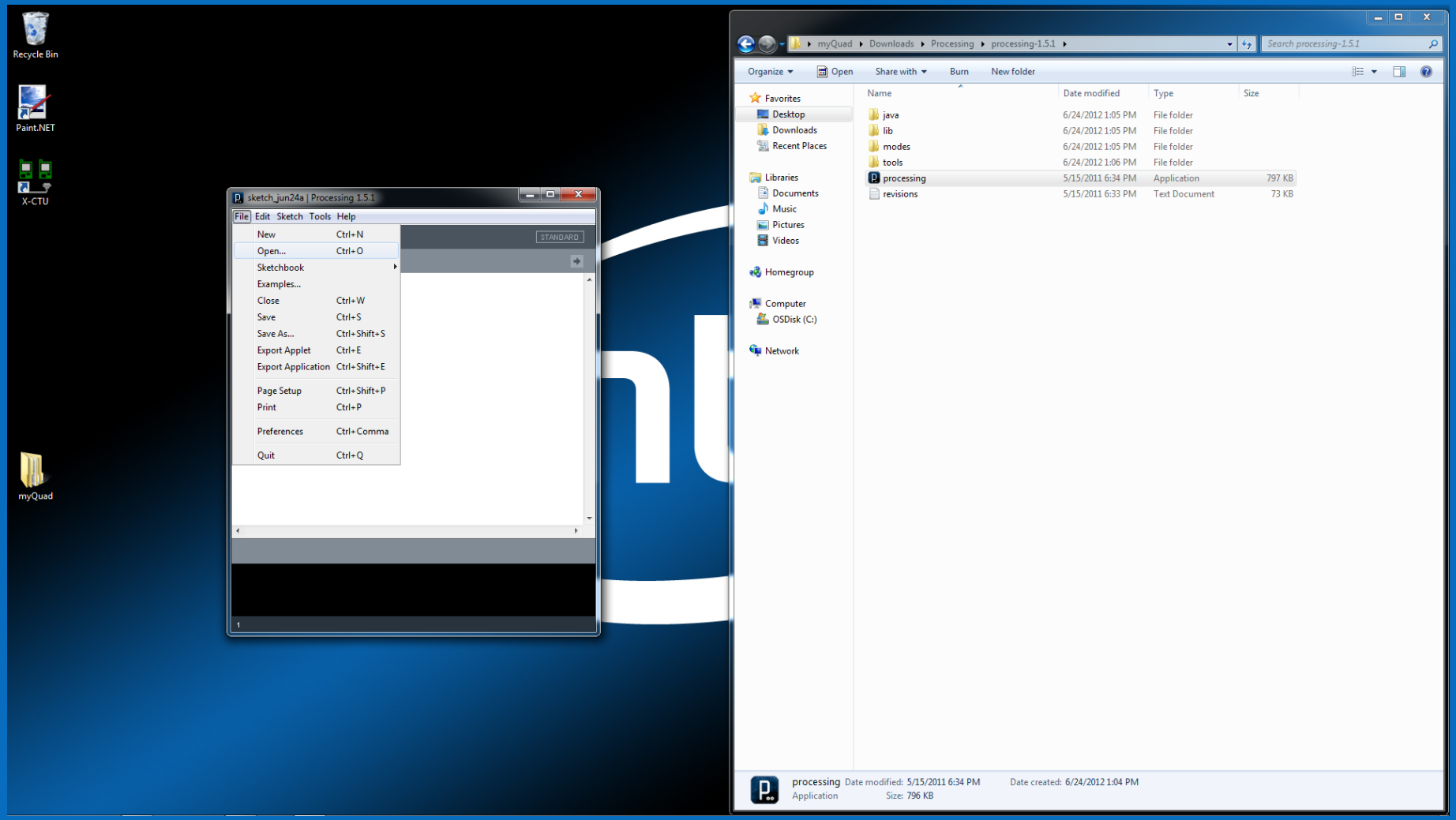
Robotics Week Instructor

Joy Shetler, PhD

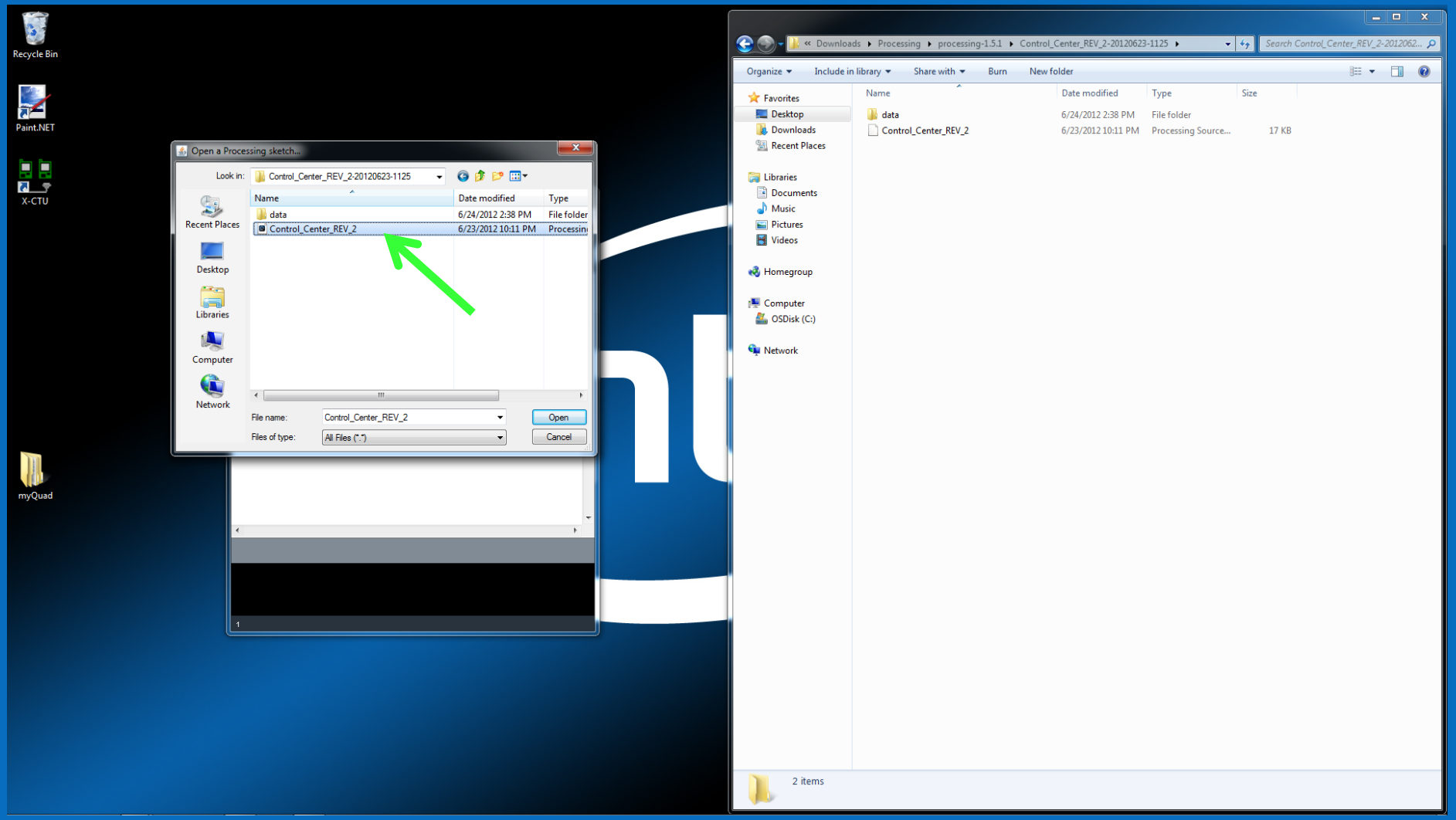
Navigate to: C:\Users\Intel\Desktop\myQuad\Downloads\Processing\processing-1.5.1



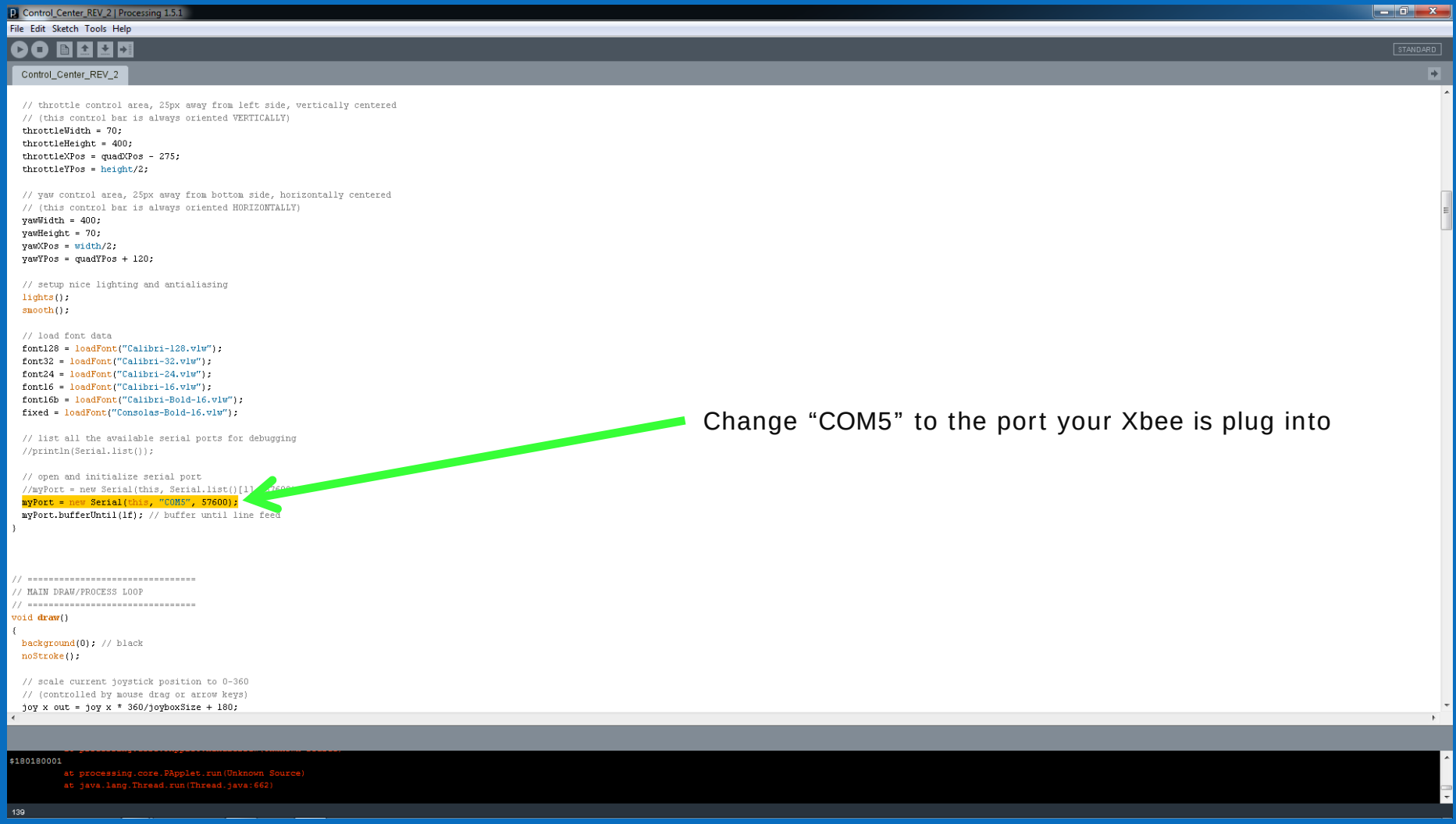
Click File – Open



Open: C:\Users\Intel\Desktop\myQuad\Downloads\Processing\processing-1.5.1\Control_Center_REV_2-20120623-1125\Control_Center

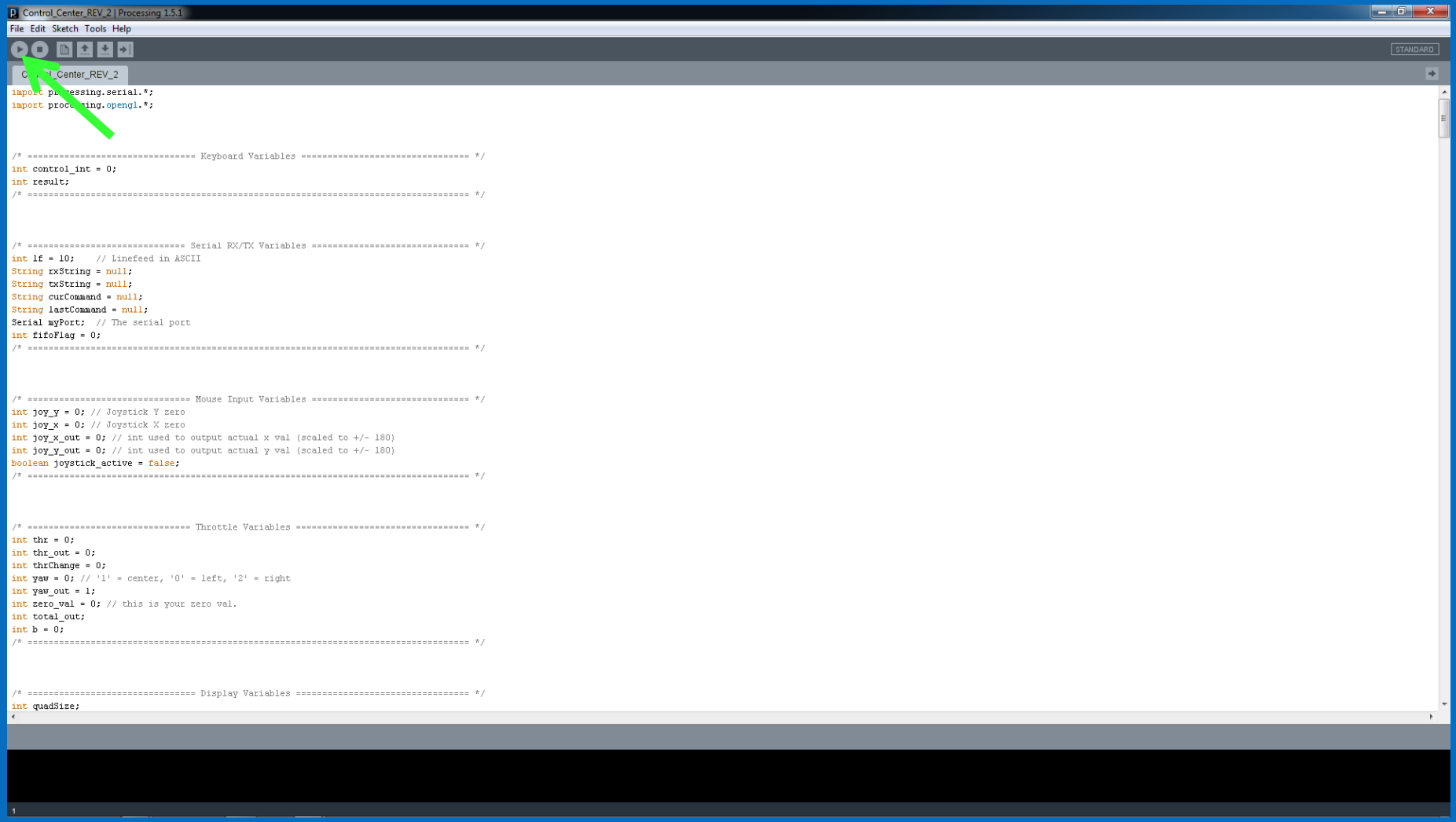


Change to Proper Port

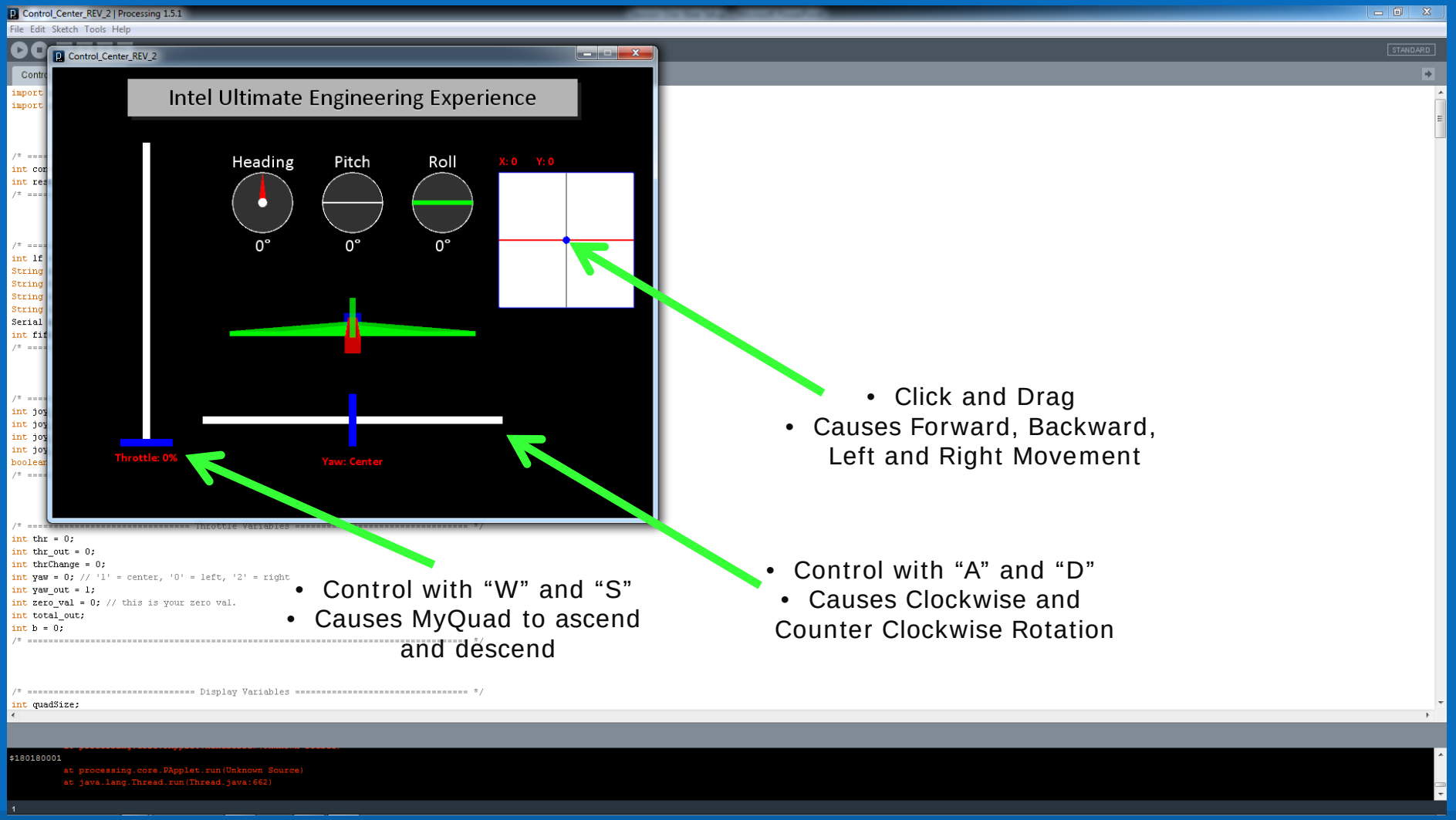


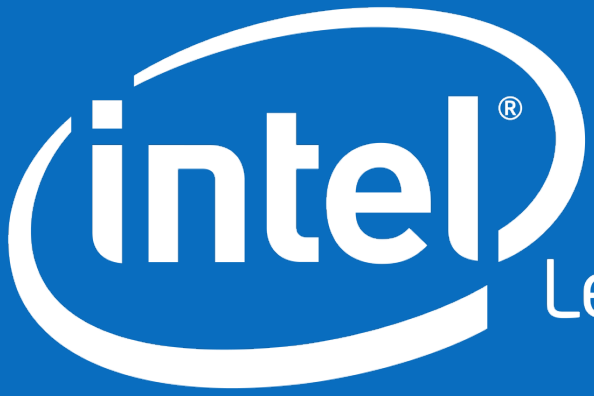
Change “COM5” to the port your Xbee is plug into

Click Play


Control_Center_REV_2 | Processing 1.5.1
File Edit Sketch Tools Help
STANDARD
Control_Center_REV_2
import processing.serial.*;
import processing.opengl.*;
/* ================================ Keyboard Variables ================================ */
int control_int = 0;
int result;
/* == */
/* ================================ Serial RX/TX Variables ================================ */
int lf = 10;   // Linefeed in ASCII
String rxString = null;
String txString = null;
String curCommand = null;
String lastCommand = null;
Serial myPort; // The serial port
int fifoFlag = 0;
/* == */
/* ================================ Mouse Input Variables ================================ */
int joy_y = 0; // Joystick Y zero
int joy_x = 0; // Joystick X zero
int joy_x_out = 0; // int used to output actual x val (scaled to +/- 180)
int joy_y_out = 0; // int used to output actual y val (scaled to +/- 180)
boolean joystick_active = false;
/* == */
/* ================================ Throttle Variables ================================ */
int thr = 0;
int thr_out = 0;
int thrChange = 0;
int yaw = 0; // '1' = center, '0' = left, '2' = right
int yaw_out = 1;
int zero_val = 0; // this is your zero val.
int total_out;
int b = 0;
/* == */
/* ================================ Display Variables ================================ */
int quadSize;

Click Modem Configuration Tab





Leap ahead™

Backup