

# Aria Homework 2

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# Code

asn2.cpp

```
1 #include "Aria.h"
2 #include <stdio.h>
3
4 /**
5  * @brief control func for asn2
6  *
7  * call this function in main
8  *
9  * @return void
10 *
11 */
12 void asn2(ArRobot* robot)
13 {
14     if (!robot)
15         return;
16
17     double range, angle;
18
19     ArUtil::sleep(1000);
20
21     while(1)
22     {
23         /** get sonar range in front of robot */
24         range = robot->checkRangeDevicesCurrentPolar(-90,90,&angle);
25
26         ArLog::log(ArLog::Normal,"range: %f _ angle: %f",range,angle);
27         ArUtil::sleep(100);
28     }
29 }
```