



# Activity manual

## version 1.0 Lite

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Arduino is an open source project supported by many. The Team is composed of Massimo Banzi, David Cuartielles, Tom Igoe, Gianluca Martino, and David Mellis. Nicholas Zambetti has contributed since the beginning. Yaniv Steiner and Giorgio Olivero have been supporting the project and are working at using it with the Instant Soup platform. The Arduino platform used to include the avr-gcc tool chain, uisp, and the Procyon AVR-LIB by Pascal Stang. The Arduino language syntax is based on Wiring by Hernando Barragan. The Arduino environment is based on Processing by Ben Fry and Casey Reas. Thanks to all the people who are supporting arduino.

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# 1 : POP-BOT part list

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## 1.1 Part list of POP-BOT mobile robot kit

1. POP-168 The Arduino-mini compatible microcontroller module
  2. RBX-168 Robot controller board with 4-AA battery holder
  3. Switch module with JST cable (2 sets)
  4. Infrared Reflector board with JST cable (2 sets)
  5. Serial LCD 16 characters by 2 lines module with LED backlight and cable
  6. 48:1 ratio 4.5V DC motor gearbox with IDC cable (2 sets)
  7. Circle wheel and Threaded rubber wheel set with 2mm. tapped-screw. (2 sets)
  8. 80x60 cm. and 80x80 cm. Plastic Grid plate set (1 sets)
  9. Circle base with idle ball wheel
  10. Plastic joiner and Strip joiner set (60 pieces of 3-type mix colored plastic joiner, 4 pieces of each 3/5/12 holes of Strip joiner)
  11. Right angled metal shaft set (4 pieces of each 1x2, 2x2, 2x5 Right angled metal shaft)
  12. Nuts and Screws set
  13. Line tracking demo paper sheet
  14. CX-4 Serial cable for downloading and communication
  15. CD-ROM contains software tools, source code and documentation
- Optional :**
1. GP2D120 Infrared distance sensor with JST cable
  2. UCON-4 USB to serial converter cable for downloading and communication
  3. UCON-232S USB to serial converter for CX-4 cable to work with computer that without COM port and available only USB port.
  4. Standard servo motor (Operating voltage is 4.8 to 7.2Vdc)

## 1.2 Microcontroller components information

### 1.2.1 POP-168 microcontroller module

The Arduino POP-168 is a flexible board with no hidden components which allows full development of its features with AVR Standard tools like the like IAR C/C++ , MikroElektronika Mikro BASIC/ MikroPascal for AVR, and also the open-source tool WINAVR: AVRGCC for Windows ... etc.

**Arduino POP-168** use the ATmega168 of AVR microcontroller from Atmel ([www.atmel.com](http://www.atmel.com)). **Arduino POP-168 is similar** BASIC Stamp **module** ([www.parallax.com](http://www.parallax.com)). **It includes** RS-232 serial port communication circuit for downloading and data communication with computer. Arduino POP-168 module's hardware is compatible with Arduino-mini in Arduino project ([www.arduino.cc/en](http://www.arduino.cc/en))

The complete schematic diagram of Arduino POP-168 module is shown in figure 1-1. The summarize features of POP-168 module is as follows :

- ATmega168 on board with 10-bit ADC converter, 16KB flash program memory, 512-byte EEPROM, 1KB RAM, 16MHz clock
- Built-in RS-232 interface for Communication
- Immediate code upload with the built-in Bootloader
- Reset Button for reset capability
- Small Form Factor for compact size development
- ISP port for programming with the PX-400/PX-4000 device
- SMD Leds for indications
- Fully compatible with the Arduino Project
- 16 I/O pin assignment compatible i-Stamp/i-Stamp2P24 module
- Supply voltage range +3.3 to +5V 50mA

### 1.2.2 RBX-168 Robot controller board for Arduino POP-168

The RBX-168 Robot controller board is a complete, low-cost development platform designed for those interested in learning and using Arduino POP-168 module in robotic applications. Its compact size, convenient features, and low price make it an ideal tool for the student and educator. Figure 1-2 shows the layout of RBX-168 board and complete schematic diagram of its is shown in the figure 1-3. The summarized technical feature of the RBX-168 board is as follows :

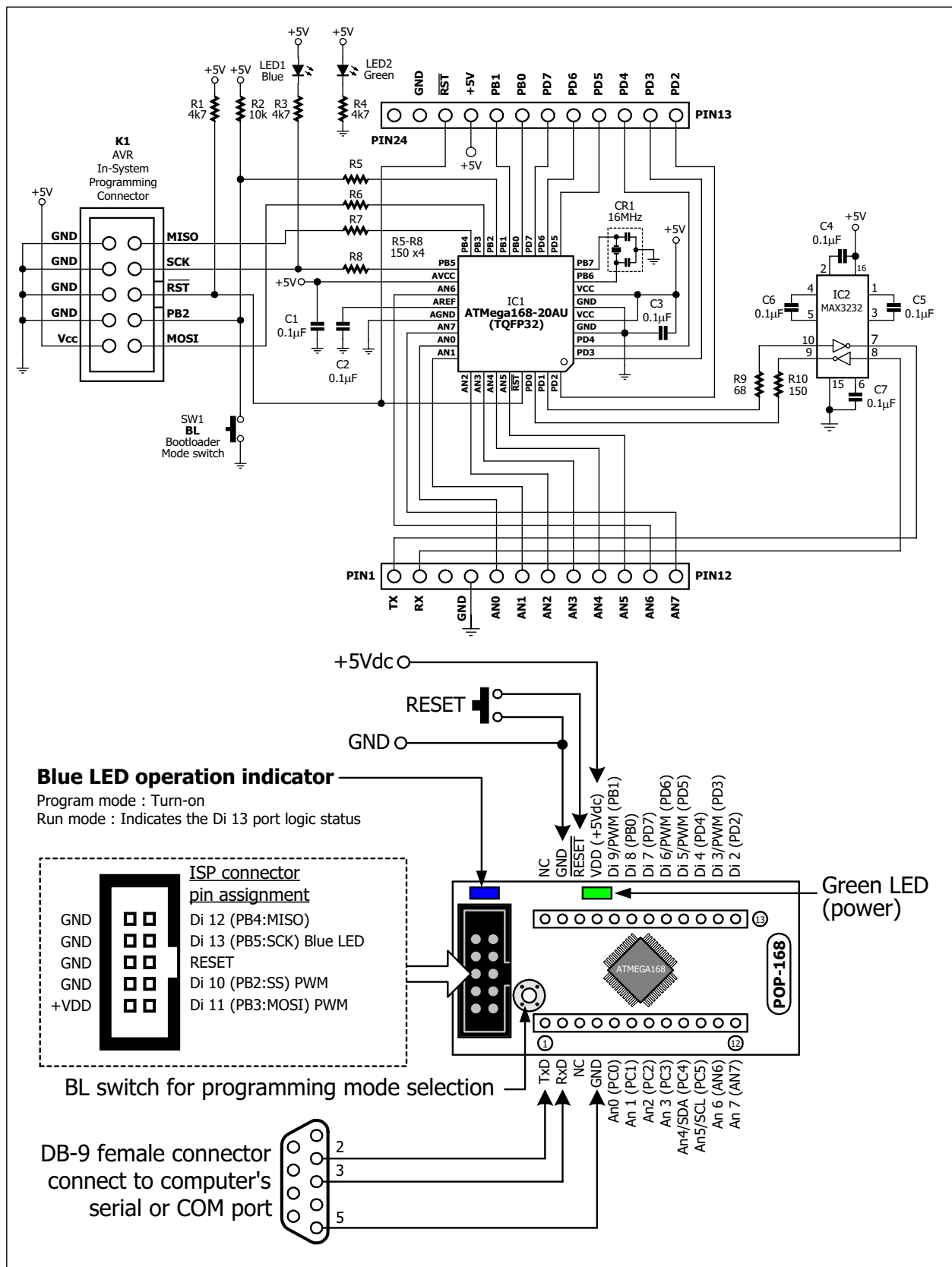


Figure 1-1 Schematic diagram, Pin assignment and simple connection of POP-168 microcontroller module

- Screw terminal block for battery connections. It supports +4.8 to +12Vdc and has an on-board power switch.
- +5Vdc switching regulator power supply circuit. Its regulates the supply voltage for POP-168 module and all sensor ports.
- 2-push button switch are connected with the digital port 2 (Di2) and 4 (Di4). Also connected with LED for indicator the operation.
- 5-Universal port support Analog input function and Digital input/output function; An1 (Di15) to An5 (Di19)
- 2-Analog input port ; An6 and An7. Both port pin are analog input only.
- I<sup>2</sup>C bus port; An4 (SDA) and An5 (SCL)
- RS-232 serial port interfacing.
- 2-ch. DC motor driver with indicators. Support motor voltage 2.5 to 13.5Vdc.
- 2-Servo motor output; connect with the digital port 7 (Di7) and 8 (Di8).
- Piezo speaker connections (do not show in the figure 1-2; it is fixed at bottom circuit board of RBX-1689 board. It is connected with POP-168 An0/Di14 pin.

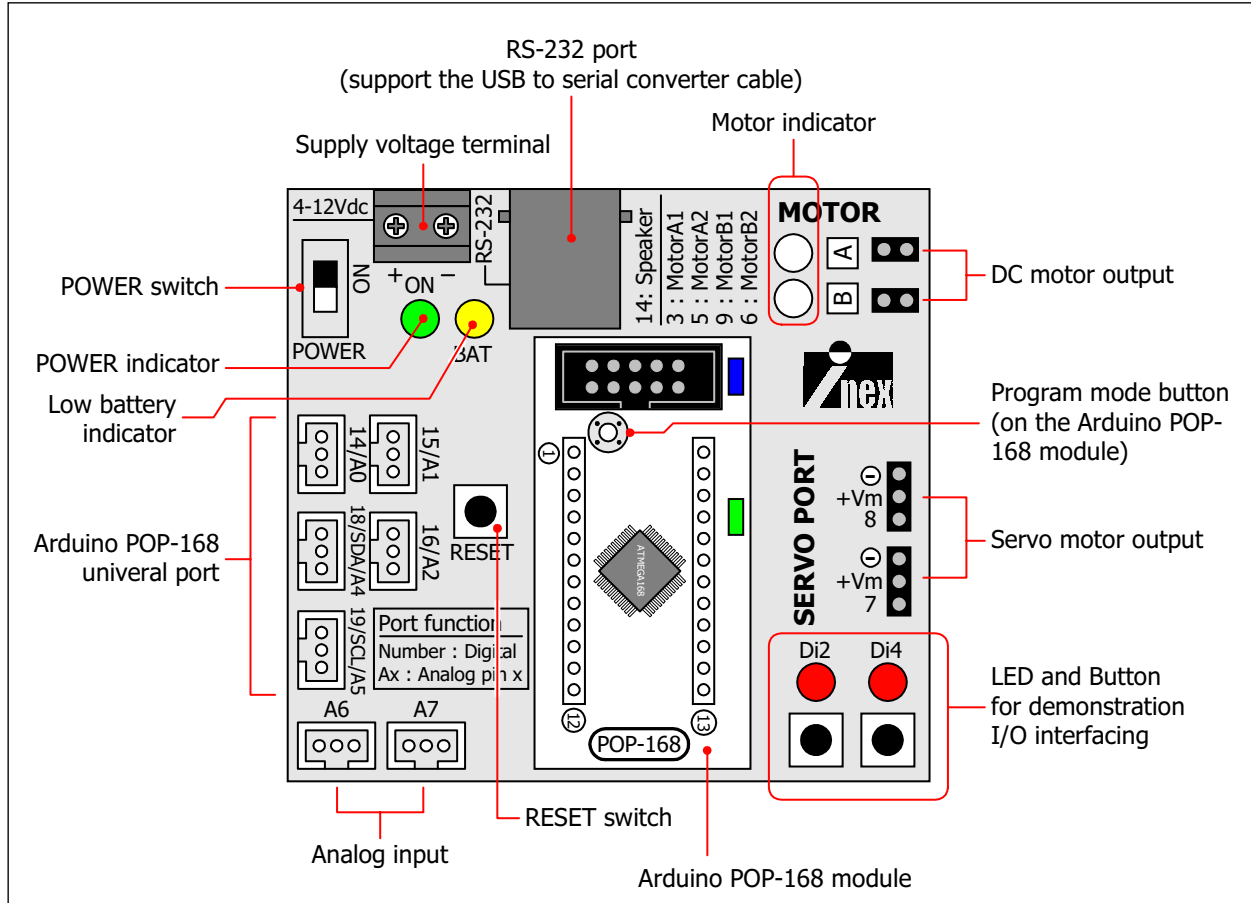


Figure 1-2 The layout of RBX-168 controller board



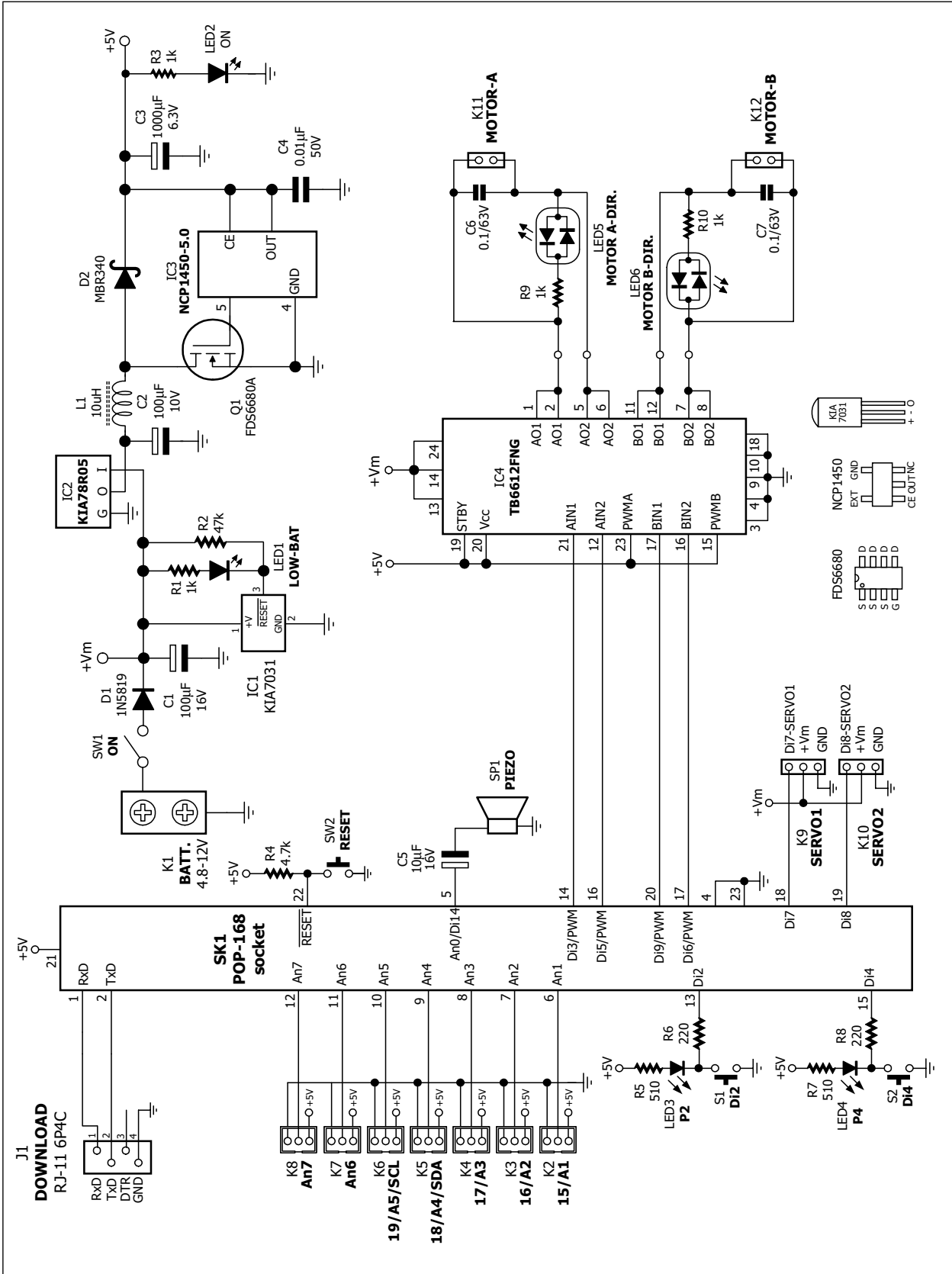


Figure 1-3 The completely schematic diagram of RBX-168 controller board

## 1.3 Output device features

### 1.3.1 DC motor gearbox

This robot kit provides 48:1 ratio DC motor gearbox; model BO-2 with IDC connector cable. This is features :



- Operating voltage is +3 to +9Vdc
- Current consumption 130mA @ +6Vdc and no load)
- Average speed 170 to 250 round per minute (RPM) @ +6V and no load
- Weight is 30 grams
- Minimum torque is 0.5 kg.cm.
- Attached with the plastic mounting with 5 of insert nuts
- 42 x 45 x 22.7 mm. (WxLxH) dimension

### 1.3.2 Standard RC servo motor (Optional - not include in Life cersion)

The standard servo is ideal for robotics and basic movement projects. These servos will allow a movement range of 0 to 180 degrees. The servo output gear shaft is a standard Futaba configuration. Technical Specifications :



- Operating voltage is 6Vdc max.
- Speed 0 deg to 180 deg in 1.5 seconds on average.
- Weight 45.0 grams/1.59oz
- Torque 3.40 kg-cm/47oz-in
- Size mm (L x W x H) 40.5x20.0x38.0

### 1.3.2 SLCD16x2 : 16 characters 2 lines Serial LCD module

The 16x2 Serial LCD module provides a simple way to display data from micro-controller. The module requires only one I/O pin, +5 V and ground to function. Simple serial data out commands can be used in the Arduino POP-168 module to communicate with the module at 2400 and 9600 baud.

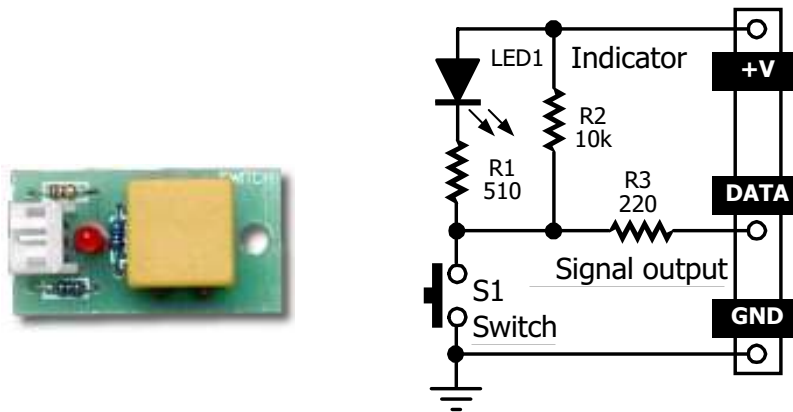


Features of the 16x2 Serial LCD Module:

- Serial Input with Invert/Non-invert TTL logic level.
- 1/8 or 1/16 Duty can be selected by jumper.
- Scott Edwards's LCD Serial Backpack™ command compatible addition with Extended Command that make LCD control easier.
- Operation with +5 Vdc supply
- SLCD16x2 provides a brightness adjustment with variable resistor at **BRIGHTNESS** position.
- Interfacing connector has 3 pins : +5V Supply voltage (**+**), Serial data input (**S**) and Ground (**G**).

## 1.4 Sensor module features

### 1.4.1 Switch module/Touch sensor

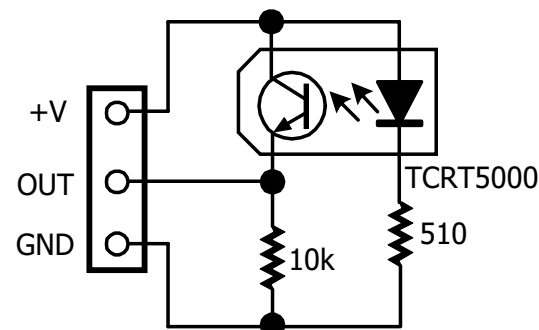
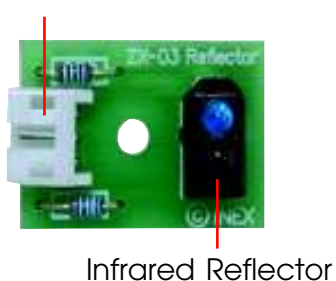


The switch input is used to detect collision at logic  $\bar{0}$ . Two sets along with the connecting cable are provided.

### 1.4.1 ZX-03 : Infrared reflector sensor

The heart of this sensor is TCRT5000 reflective object sensor. It is designed for close proximity infrared (IR) detection. There is an infrared diode behind its transparent blue window and an infrared transistor behind its black window. When the infrared emitted by the diode reflects off a surface and returns to the black window, it strikes the infrared transistor's base, causing it to conduct current. The more infrared incident on the transistor's base, the more current it conducts. When used as an analog sensor, the ZX-03 can detect shades of gray on paper and distances over a short range if the light in the room remains constant.

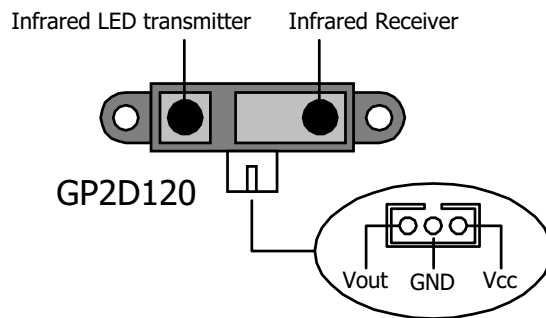
Signal connector



The suitable distance from sensor to line or floor is during 3 to 8 mm. The output voltage is during 0.1 to 4.8V and digital value from 10-bit A/D converter is 20 to 1,000. Thus, ZX-03 will suitable to apply to line tracking sensor.

### 1.4.3 GP2D120 Infrared distance sensor (optional - not include in POP-BOT Lite version)

One of the special sensors in robotics is the GP2D120. It is an Infrared Distance sensor. Some people call it the IR Ranger. With the GP2D120 module, it adds the distance measuring and Obstacle detection using infrared light feature to your robot. Your MicroCamp robot can avoid obstacles without having to make any physical contact.



#### Features of the GP2D120 module

- Uses Infrared light reflection to measure range
- Can measure a range from 4 to 30 cm.
- 4.5 to 5 V power supply and 33mA electric current
- The output voltage range is 0.4 to 2.4V when supplied by +5V

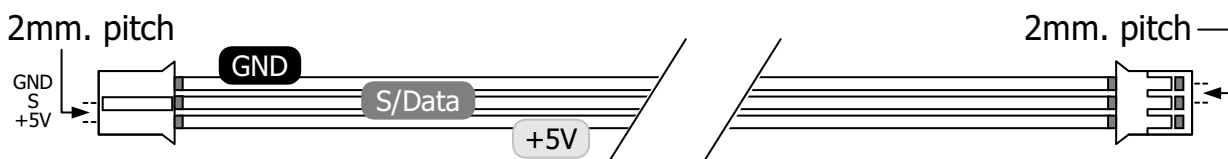
GP2D120 Infrared Ranger module has 3 terminals: Power input (Vcc), Ground (GND) and Voltage output (Vout). To read the voltage values from the GP2D120, you must wait till after the acknowledgement period which is around 32 to 52.9 ms.

The output voltage of GP2D120 at a range of 30 cm and +5V power supply is between 0.25 to 0.55V, with the mean being 0.4V. At the range of 4 cm., the output voltage will change at  $2.25V \pm 0.3V$ .

## 1.5 POP-BOT cable information

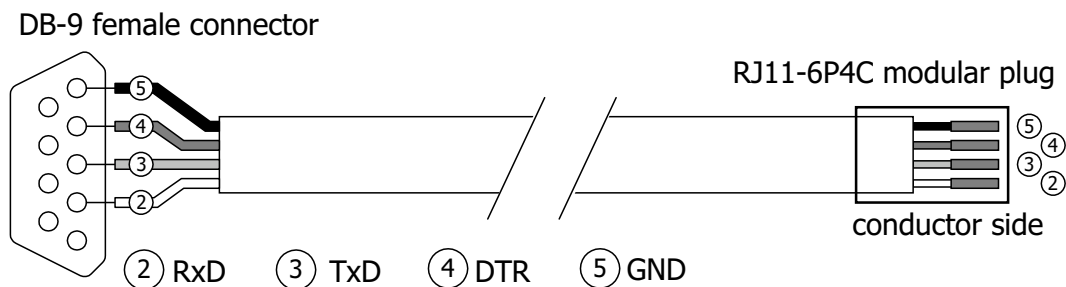
### 1.5.1 JST3AA-8 cable

This is an INEX standard cable, 3-wires combined with 2mm. The JST connector is at each end. 8 inches (20cm.) in length. Used for connecting between microcontroller board and all the sensor modules in the POP-BOT robot kit. The wire assignment is shown in the diagram below.



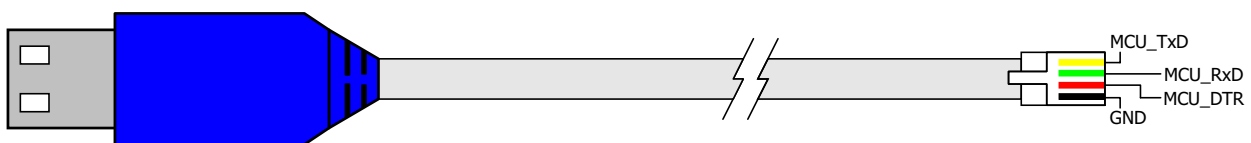
### 1.5.2 CX-4 serial port cable

This is used to connect between the computer's RS-232 serial port and the POP-BOT controller board. The connector's end uses a DB-9 female connector, and the other end uses a Modular plug RJ-11 6P4C (6-pins form and 4-contacts). Its Length is 1.5 meters. In the kit, this cable is used to connect between RS-232 serial port and POP-BOT controller board. The wire assignment is shown in the diagram below.



### 1.5.3 UCON-4 USB to Serial port converter cable (optional)

This is used to connect between the computer's USB port and the POP-BOT controller board. The cable's end uses a Modular plug RJ-11 6P4C (6-pins form and 4-contacts). Its Length is 1.5 meters approximation. The cable assignment is shown in the diagram below.



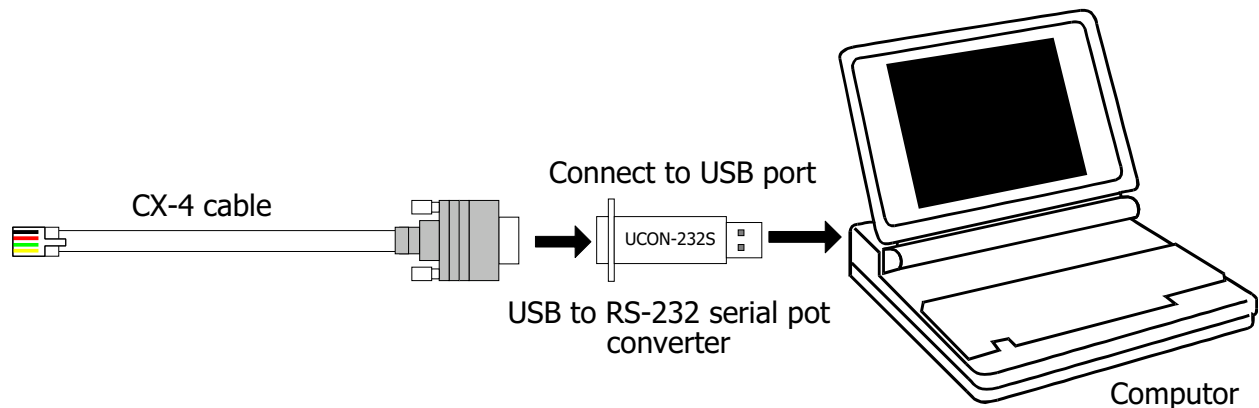
This cable requires +5V from USB port and support USB 1.0/2.0. User can set the baudrate up to 115,200 bit per second. Requires the driver installation before using.

## 1.5.4 UCON-232S USB to Serial port converter (optional)



This is a compact size RS232 Serial to USB Converter. Its fully compatible with all our robotic kits and microcontroller for Laptop or Desktop users whose computers do not have a RS232 Serial Port.

The mainly function of this converter is making the Virtual COM port compatible with true RS-232 serial port. The figure below shows UCON-232S connection with CX-4 and computer for using in POP-BOT kit.



The UCON-232S is used FT232RL from FTDI. It is USB-UART converter chip. FTDI support the driver for computer to know this device. You can see more information and download the latest driver at [www.ftdichip.com](http://www.ftdichip.com) or [www.parallax.com](http://www.parallax.com).

## 1.6 Mechanical prt features

### 1.6.1 Circle wheel and Tire set

Includes 2 pairs of the suitable circle wheel for BO-2 DC motor gearbox and tread rubber tire. Fix the wheel with gearbox shaft by 2mm. self-tapping screws



### 1.6.2 Plastic grid plate set

Includes each of the universal plastic grid palte 2 sizes; 80x60mm. and 80x80mm. Each plate provides 3mm. diameter holes with 5mm. pitch.



### 1.6.3 Circle base

This base is injected from high quality ABS plastic. Diameter is .....mm. It has 2 free ball wheels at both side. This base has many 3mm. holes for fixing the controller board, sensors and more mechanical parts.





### 1.6.4 Plastic joiners

60 pieces of varied color joiners made from PVC plastic. They can be connected together or by using screws and 3 mm nuts in installation. There are 4 types; Right angle, Obtuse, Straight joiner and Hole straight joiner.



### 1.6.5 Strip joiners

They are made from plastic. Each joiner has 3mm. hole 5mm. pitch. Each joiner can connect for length expansion. They are 4 pieces of 3 sizes; 3, 5 and 12 holes type. Total 12 pieces.



### 1.6.6 Box holder

It is injected plastic box for supporting the RBX-168 controller board. It has some of 3mm. hole for fixing with any platform.



### 1.6.7 Right-angle metal shaft

It is 7.5mm. width right-angle metal shaft. Each shaft has 3mm. hole for inserting the screw to fix with another structures. The set includes 4 pieces of 1x2, 2x2 and 2x5 holes metal shaft.



### 1.6.8 Screw and Nut set

Includes 2 of 2mm. self-tapping screws, 4 of 3x8mm. M3 screws, 30 of 3x10mm. M3 screws, 4 of 3x15 mm. M3 screws, 4 of 3x40mm.M3 screws, 10 of 3x8mm. flat-head screws and 30 of 3mm. M3 nuts.



### 1.6.9 Metal spacer

They are metal parts for supporting the plate and sensor board. They are made from nicle plating metal. Includes 6 of 33mm. metal hexagonal spacers. Each standoff has 3mm. thread through-hole.



### 1.6.10 Plastic spacer

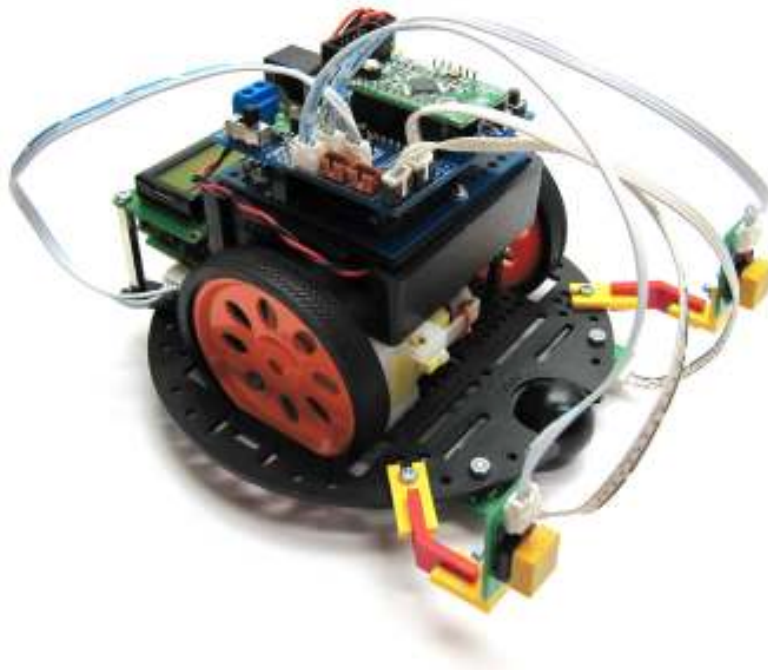
They are some mechanical parts for supporting the plate and sensor board. This kit includes 4 pieces set of plastic spacer (3mm., 10mm., 15mm. and 25mm.) 4 sets



## 2 : Building POP-BOT mobile robot

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### 2.1 POP-BOT features



- Move with DC motor gearboxes and wheels.
- Controlled by Arduino POP-168 microcontroller module. Based on ATmega168 microcontroller.
- Programmable via serial port and support the USB to serial port converter.
- Support variety of sensors such as Infrared refelctor for line tacking, Touch sensor for object avoiding, Infrared ranger or Distance sensor for touchless object avoiding.
- Support the wired remote control included PlayStation controller.
- Support the wireless serial data communication module suhc as Xbee, XBee-Pro and Bluetooth.
- Includes 16x2 Serial LCD module for monitoring and display operting status.
- 2 servo motor driver port. Support small RC servo motor 4.8 to 6V.
- Requires 4 of AA batteries. The Alcaline, Evolta and Rechargeable Ni-MH are recommended.

## 2.2 Part list



**Circle base x 1**



**RBX-168 board with POP-168 x1**



**Box holder x 1**



**Circle wheel and tire x 2**



**DC motor gearbox x 2**



**33mm. metal spacer x 4**



**Serial LCD module x 1**



**Infrared reflector x 2**



**Switch module x 2**



**Plastic joiners**



**Right angled metal shaft 2x2 x 2**



**2mm. self-tapping screw x 2**



**Plastic spacer set**



**Screw and Nut set**

## 2.3 Building procedure

(1) Attache both DC motor gearboxes with the Box holder by 3x8mm. flat screws.



(2) Attache 2 of 33mm. metal spacers with the Box holder by 3x8mm. flat screws at the position following the pictures below.

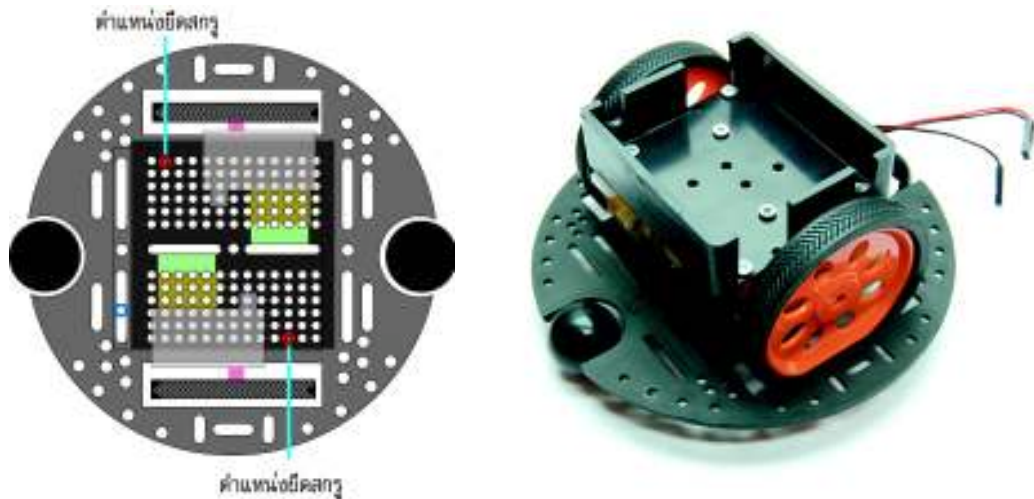


(3) Insert the wheel with tire to DC motor gearbox's shaft and fix with 2mm. self-tapping screws.



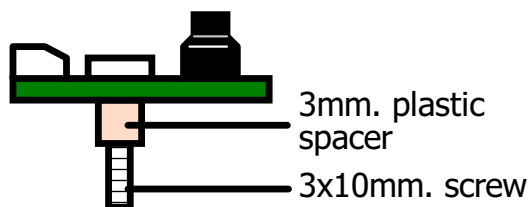


(4) Attach the gearbox structure as shown in step (3) with the circle base by using 3x6mm. screws at the position following the pictures below. See the wheels position is the center of base.

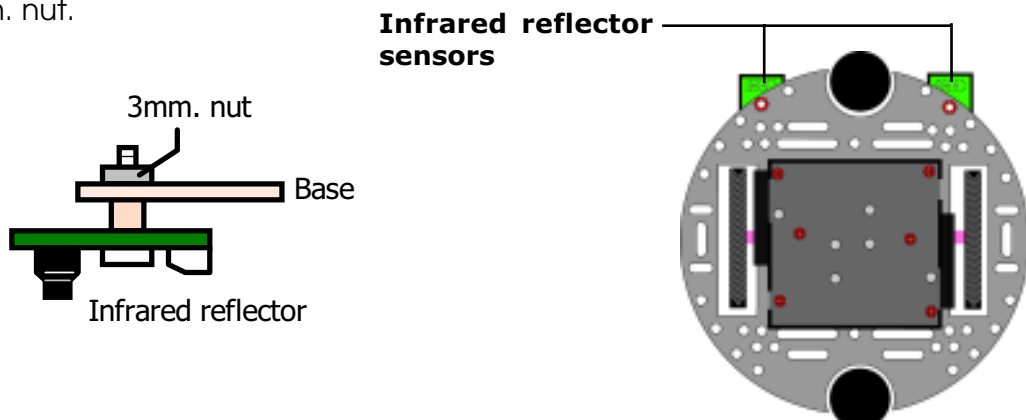


(5) Insert the 3x10mm. screw via the Infrared reflector's hole and 3mm. plastic spacer. Make 2 sets.

Infrared reflector sensor



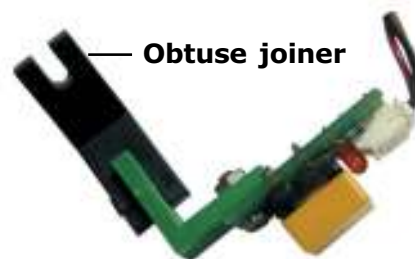
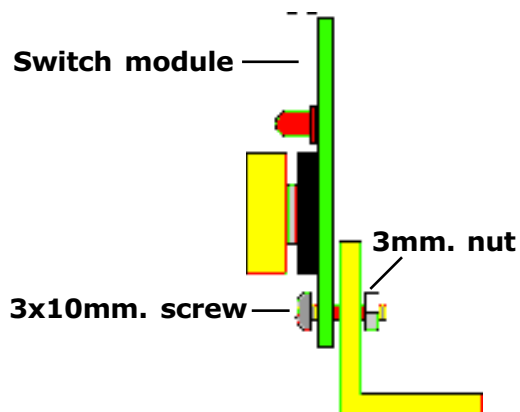
(6) Fix both Infrared reflector structures from step (5) at the in-front-of robot base both side by using 3mm. nut.



(7) Now the POP-BOT chasis with Infrared reflector sensors is ready.



(8) Attach the Right angle joiner with Switch module by using 3x10mm. screw and 3mm. nut following connect the obtuse joiner at the end of the right angle joiner. Make 2 sets.



(9) Fix 2 pieces of Straight joiner at the front of robot chasis by using 3x6mm. screws and 3mm. nuts. Next, connect the Switch structures from step (9) at the end of Straight joiners.



(10) Attach 2 of 33mm. metal spacers with SLCD16x2 module by using 3x6mm. screws. Next, fix the straight joiner at the end of spacer by using 3x10mm. screw.

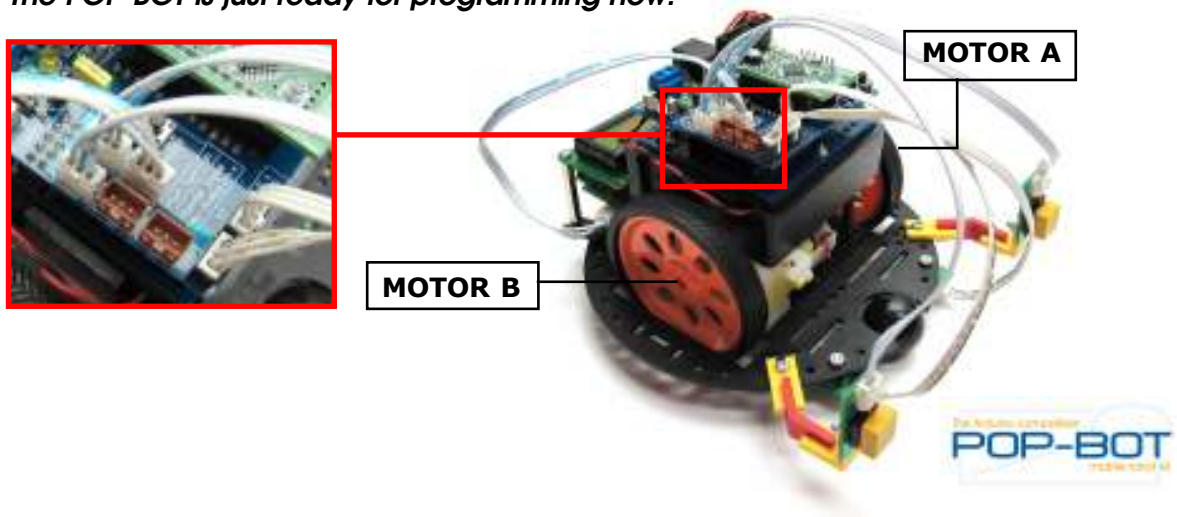


(11) Fix the SLCD16x2 structure from step (10) at the back of robot chasis following the picture below by using 3x10mm. screws and 3mm. nuts



(12) Put the RBX-168 board into the Box holder. Connect all cables. Start with Left motor cable to MOTOR A output, Right motor cable to MOTOR B output. Connect the left Infrared reflector cable to **A7** pin, the right Infrared reflector cable to **A6** pin. Next, connect the the leftt switch module cable to **15/A1** pin, the right switch cable to **17/A3** and connect SLCD16x2 to **16/A2 pin**.

***The POP-BOT is just ready for programming now.***





## 3 : Introduction to Arduino IDE

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Arduino is an open-source electronics prototyping platform based on flexible, easy-to-use hardware and software. It's intended for artists, designers, hobbyists, and anyone interested in creating interactive objects or environments.\*

This chapter describe about introduction to Arduino. Begin with Installation, explain about Arduino IDE components and Menu bar details.

### 3.1 Installation software

(1) Insert the POP-BOT CD-ROM to CD drive of your computer.

(2) Enter the **Software** → **Arduino** folder. Find the **ArduinoSetup.exe** and double-click. The installation will start .



POP-BOT CD-ROM contains the Arduino software V15 , all example codes for POP-BOT activities and necessary library files. You can get the latest version of Arduino at [www.arduino.cc](http://www.arduino.cc). However you need to ensure the correct path of POP-BOT library after you upgrade the new version of Arduino IDE.

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\* Introduction paragraph is from Arduino website ([www.arduino.cc](http://www.arduino.cc))

## 3.2 Arduino environment

After starting Arduino IDE, the main window will appear as shown in the figure 3-1. The Arduino includes the environments as follows.

- **Menu** : Select the operation command
- **Toolbar** : Includes all most command button
- **Tabs** : Allows you to manage sketches with more than one file (each of which appears in its own tab).
- **Text editor** : Text editor area for creating the sketch.
- **Message area** : Shows the program operation status such as compiling result.
- **Text area** : The space demonstrates compiling information and Serial data Terminal window if enable.

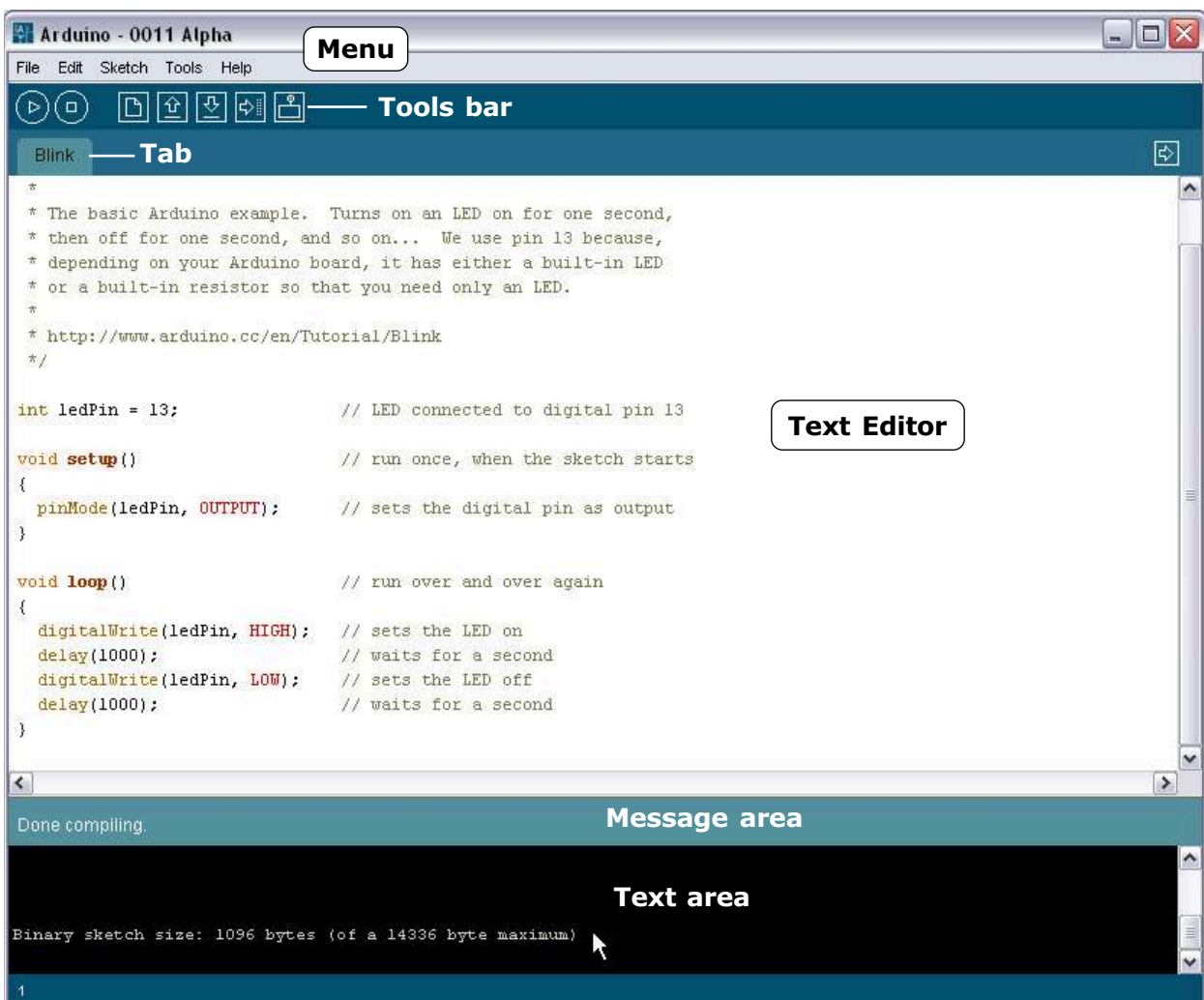


Figure 3-1 Arduino environment

## 3.3 Menu bar

### 3.3.1 File

The Arduino calls the code as **Sketch**. This menu contains many commands like open, save and close the sketch as follows :

- **New** : Creates a new sketch, named is the current date format "sketch\_YYMMDDa".
- **Sketchbook**
  - **Open** : Open the exist sketch.
  - **Example** : Open the example sketch.
- **Save** : Save the current sketch
- **Save as** : Save the current sketch as another name.
- **Upload to I/O board** : Uploads your code to the Arduino I/O board (POP-168 module). Make sure to save or verify your sketch before uploading it.
- **Preference** : Set some preference of Arduino environment
- **Quit** : Exit the Arduino IDE

### 3.3.2 Edit

The Edit menu provides a series of commands for editing the Arduino files.

- **Undo** : Reverses the last command or the last entry typed.
- **Redo** : Reverses the action of the last Undo command. This option is only available, if there has already been an Undo action.
- **Cut** : Removes and copies selected text to the clipboard.
- **Copy** : Copies selected text to the clipboard.
- **Paste** : Inserts the contents of the clipboard at the location of the cursor, and replaces any selected text.
- **Select All** : Selects all of the text in the file which is currently open in the text editor.
- **Find** : Finds an occurrence of a text string within the file open in the text editor and gives the option to replace it with a different text.
- **Find Next** : Finds the next occurrence of a text string within the file open in the text editor.

### 3.3.3 Sketch

This menu provides a series of commands for compile the code and manage library.

- **Verify/Compile** : Verify and compiles the code
- **Stop** : Stops current activity.
- **Add file** : Opens a file navigator. Select a code files to add it to the sketches "data" directory.

- **Import Library** : Import the addition library.
- **Show Sketch folder** : Opens the directory for the current sketch.

### 3.3.4 Tools

This menu provides commands about tools for developing the Arduino sketch and setting up the Arduino hardware.

- **Auto Format** : Attempts to format the code into a more human-readable layout. Auto Format was previously called Beautify.

- **Archive Sketch** : Compress the current sketch to the zip file.
- **Export Folder** : Open the folder that contain the curretn sketch.

- **Board** : Choose the Arduino hardware. For POP-BOT, choose **POP-168** or **Arduino Mini**

- **Serial Port** :Allows to select which serial port to use as default for uploading code to the Arduino I/O Board or monitor data coming from it. The data coming from the Arduino I/O Board is printed in character format in the text area region of the console.

### 3.3.5 Help

This menu contains many information in HTML format for supporting the Arduino user.

- **Getting Start** : Opens the How to start Arduino.
- **Troubleshooting** : Suggest the solution when meet the problem in Arduino.
- **Environment** : Describe about Arduino environments

- **Reference** : Opens the reference in the default Web browser. Includes reference for the language, programming environment, libraries, and a language comparison.

- **Frequently Asked Question** : See the popular question and answer about Arduino.

- **Visit [www.arduino.cc](http://www.arduino.cc)** : Opens default Web browser to the Arduino homepage.

- **About Arduino** : Opens a concise information panel about the software.

## 3.4 Tools bar



**Verify/Compile** : Checks your code for errors.



**Stop** : Stops the serial monitor, or unhighlight other buttons.



**New** : Creates a new sketch.



**Open** : Presents a menu of all the sketches in your sketchbook.



**Save** : Saves your sketch.



**Upload to I/O Board** : Uploads your code to the Arduino I/O board (POP-168 module). Make sure to save or verify your sketch before uploading it.



**Serial Monitor** : Displays serial data being sent from the Arduino board (USB or serial board). To send data to the board, enter text and click on the "send" button or press enter. Choose the baud rate from the drop-down that matches the rate passed to **Serial.begin** in your sketch. Note that on Mac or Linux, the Arduino board will reset (rerun your sketch from the beginning) when you connect with the serial monitor.

## 3.5 Arduino programming reference notice

This activity book will not describe about Arduino programming. You can read and make the understanding about Arduino syntax and programming reference from Help menu or learn from Arduino website at [www.arduino.cc](http://www.arduino.cc).

Addition, you can learn from 40-pages of **Arduino Programming Notebook**. Also download from Arduino website in *Playground* page.





## 4 : POP-BOT program development by Arduino

The POP-BOT program development can summarize as the diagram following the figure 4-1.

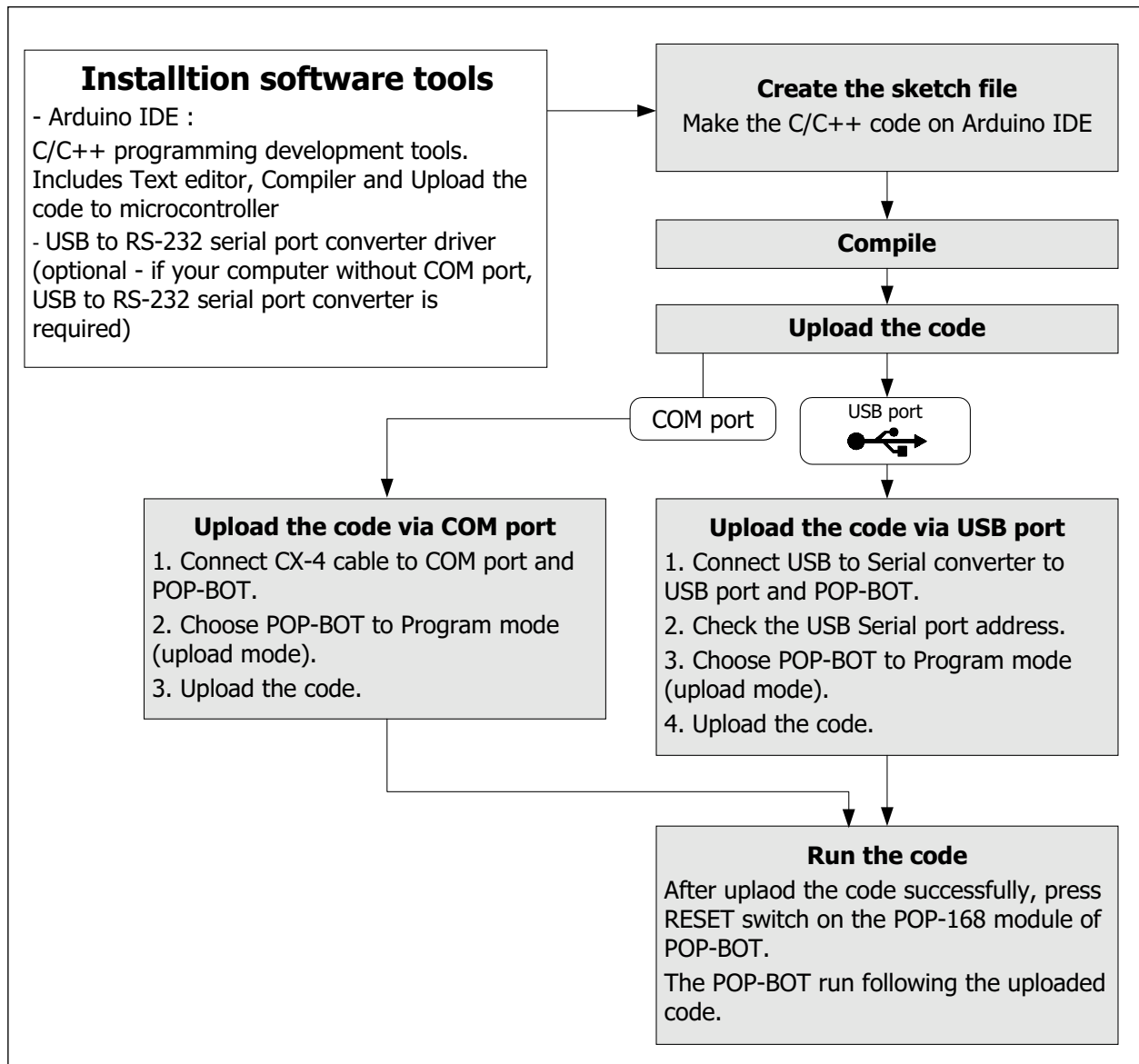
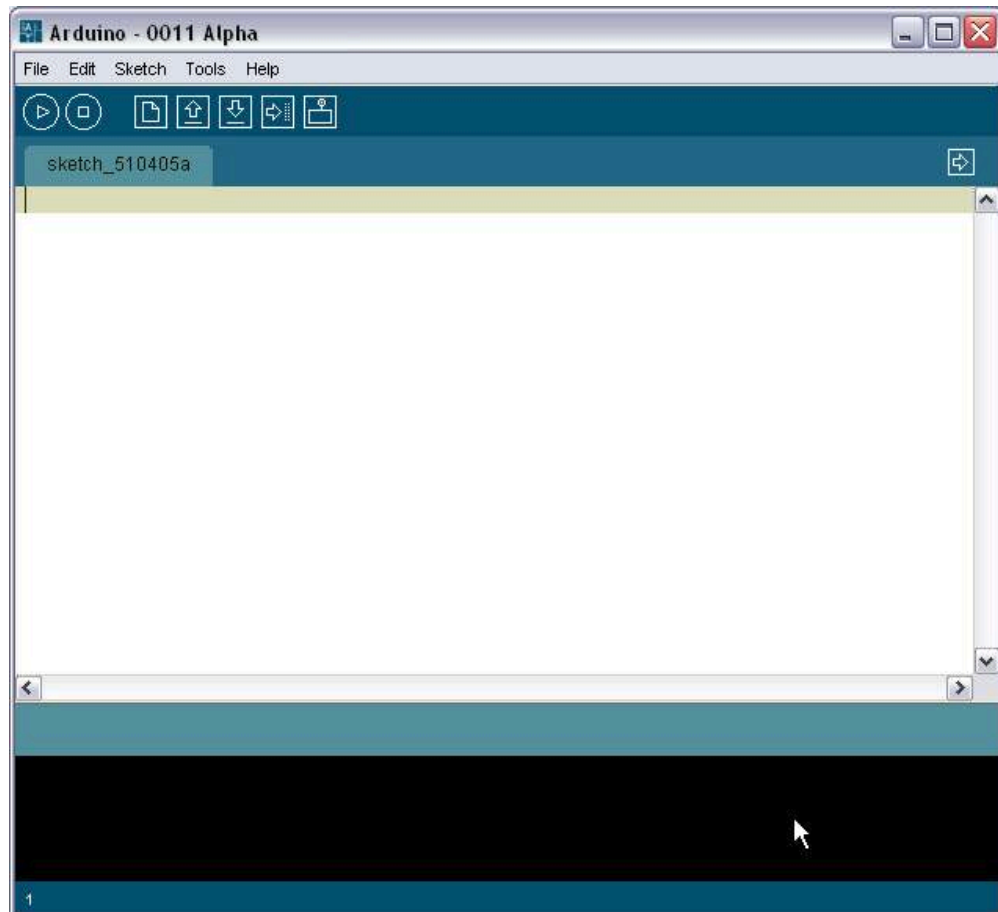


Figure 4-1 Programming development diagram of POP-BOT by using Arduino IDE

## 4.1 Getting start POP-BOT with Arduino

Run Arduino IDE by clicking the **Start → All Programs → POP-168 Software Package → Arduino**

The first launch of Arduino show the screen below.



### 4.1.1 Arduino POP-168 hardware configuration

#### 4.1.1.1 Select microcontroller chip

Select the menu **Tools → Board → POP-168** or **Arduino Mini** (can use both versions)

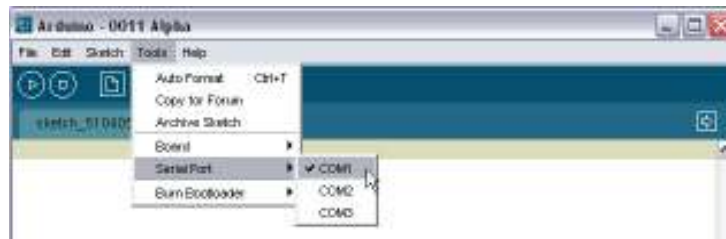




### 4.1.1.2 Select the COM port

Uploading the sketch from Arduino IDE to POP-168 module requires serial port communication. It can work with virtual COM port that created from USB to Serial port converter.

Select menu **Tools** → **Serial Port** . You can select the target COM port.



Normally on-board serial port will be COM1 or COM2. For USB Serial port address will be COM3 or higher. But Arduino can support COM port not higher COM9.

### 4.1.2 Open the exemple sketch file


Select the menu **File** → **Sketchbook** → **Examples** → **Digital** → **Blink**



The example code; Blink.pde will appear on the text editor area.



### 4.1.3 Compile the sketch

After open the sketch file and edit ready, you can compile this sketch by selecting the menu **Sketch** → **Verify/Compile** or click on the button 

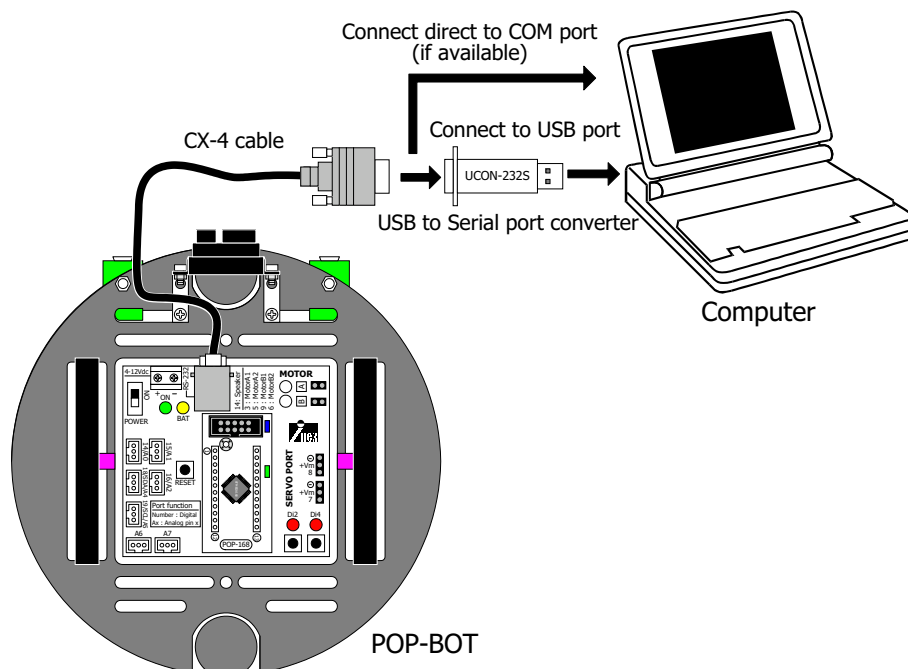


The status bar at the bottom of main screen will display the compilation status. If compile no error, it reports **Done compiling** and the Text area will display message of binary sketch size.

### 4.1.4 Uploading the sketch to POP-168 module

Downloading the machine code from compiling to Arduino hardware is called Uploading. You must prepare the Arduino hardware ready for uploading by setting the POP-168 to Bootloader mode. The procedure is :

(1) Connect the POP-BOT with your computer COM port by CX-4 cable or via USB to Serial port converter.



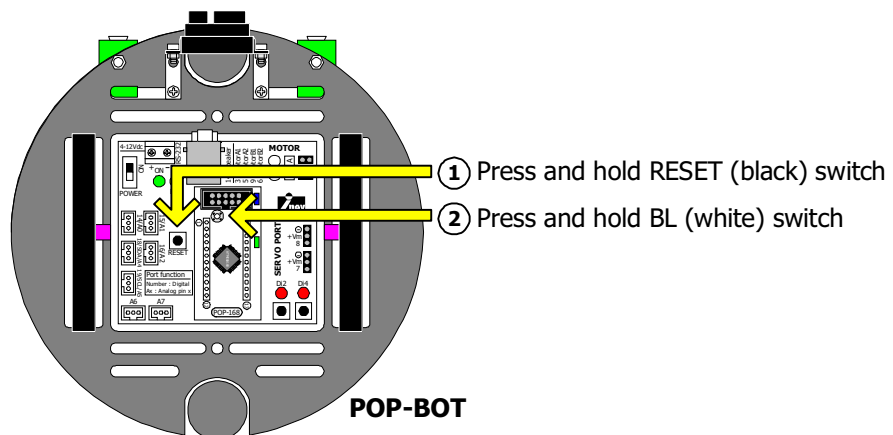
(2) Set POP-168 module to program mode. It has 2 options.

**(2.1) Use RESET switch on RBX-168 board and BL switch on POP-168 module**

(2.1.1) Turn on POP-BOT

(2.1.2) Press and hold RESET switch on the RBX-168 controller board.

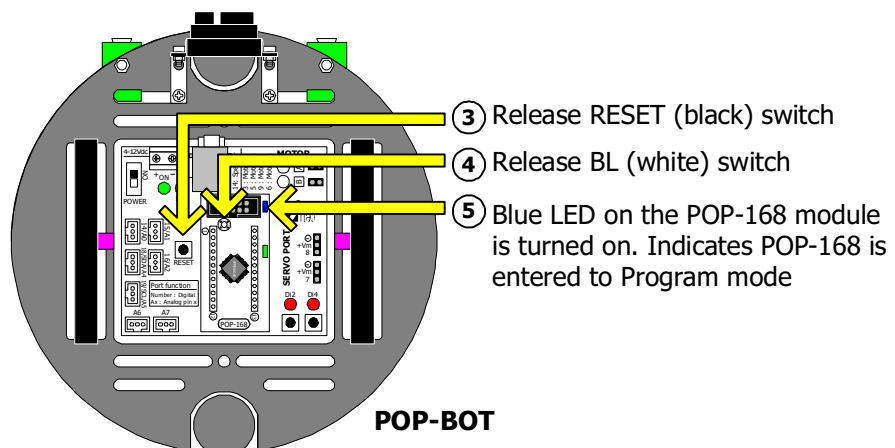
(2.1.3) Press and hold BL switch on the POP-168 module.



(2.1.4) Release the RESET switch.

(2.1.5) Release the BL switch following.

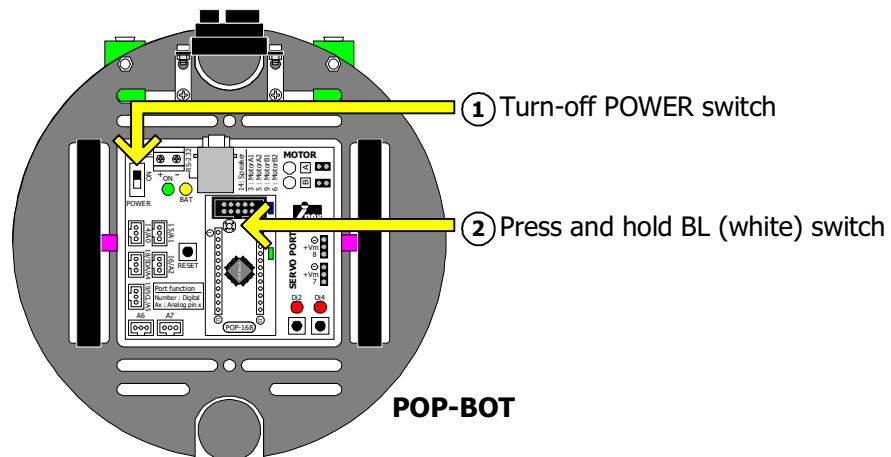
If Blue LED on POP-168 is turned on and not blink, then POP-168 had entered Bootloader mode and ready to uploaded.



**(2.2) Use POWER T switch on RBX-168 board and BL switch on POP-168 module**

(2.2.1) Turn off the POP-BOT.

(2.2.2) Press and hold BL switch.



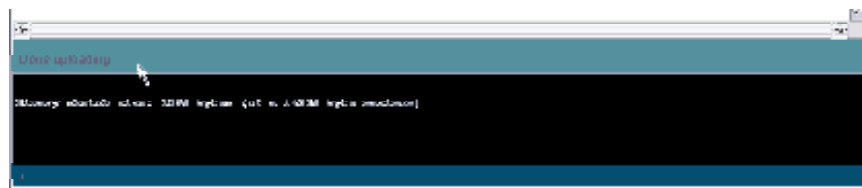
(2.2.3) Turn-on the POWER switch

(2.2.4) Release the BL switch

*If Blue LED on POP-168 is turned on and not blink, then POP-168 had entered Bootloader mode and ready to uploaded.*

(3) At Arduino IDE, select menu **File → Upload to I/O Board**. Wait for uploading.

(4) When uploading complete, the status bar at the bottom of main screen will display message **Done Uploading**.



(5) After the uploading is finished, press RESET switch again. The sketch will run on the POP-BOT.

*The LED at Di13 (Blue LED) on the POP-168 module blinks 1 second rate.*

## 4.2 Setting the UCON-4; USB to RS-232 serial port converter cable and UCON-232S converter for Arduino programming development

The POP-BOT requires computer interface and Arduino for uploading the code. Normally use RS-232 serial port or COM port. POP-BOT kit Lite version prepares only the CX-4 serial port cable. For modern computer provide the main interface port as USB. Therefore the USB to RS-232 serial port converter is required.

Before using the UCON-4 and UCON-232S, you must install the suitable driver and check some configuration.

### 4.2.1 Driver installation

Double click at USBDriverInstallerV2.x.x.exe (x.x is number of version) file from POP-BOT bundled CD-ROM to start the driver installation. The installation dialogue-box will appear below.



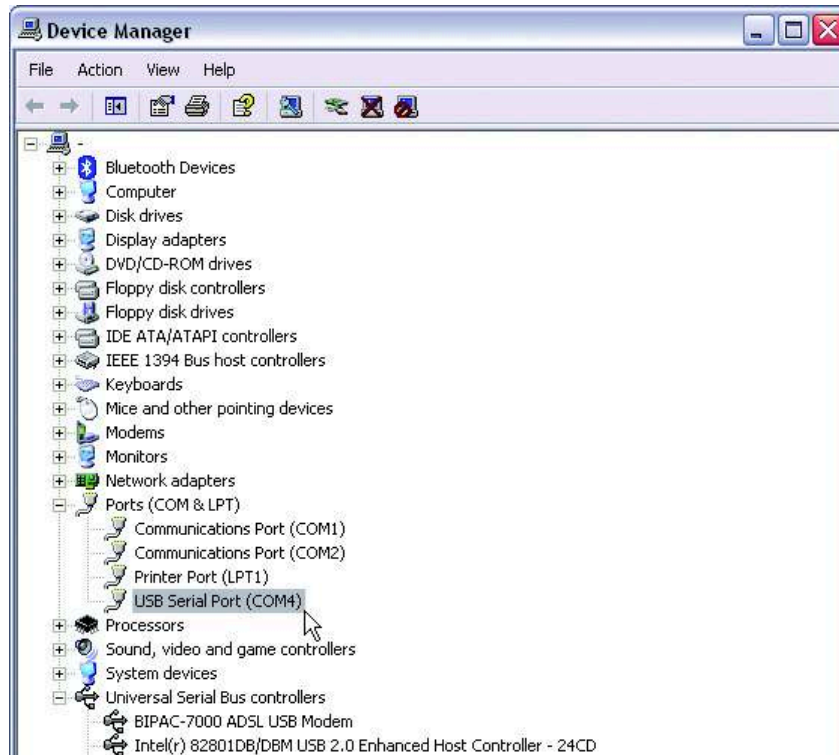
### 4.2.2 Check the USB serial port address

(1) Plug the USB cable or UCON-232S to USB port. Wait a moment.

(2) Check the Virtual COM port or USB Serial port address by clicking Start → Control Panel → System → Hardware → Device Manager



(3) See the list of USB serial port and remember the COM port address to work with UCON-4 cable and UCON-232S. Normally it will create COM3 or higher. In this example is **COM4**

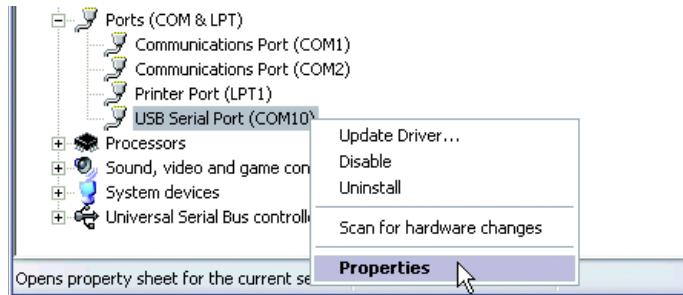


### 4.2.3 UCON-4 cable and UCON-232S with Arduino operation notice

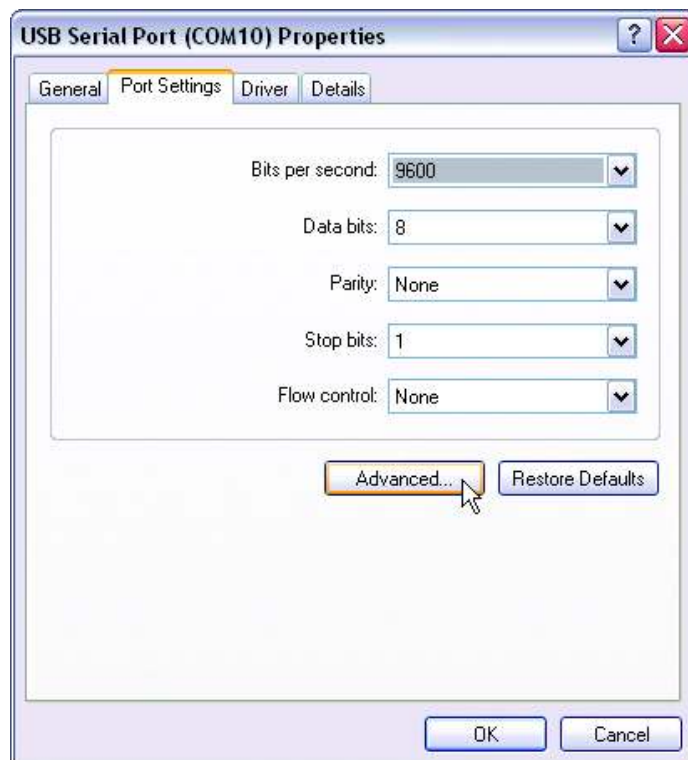
Normally Arduino software can interface with COM port not higher than COM9. Thus, user must make sure the USB serial port address not higher than COM9. If higher, please do following procedure.

- (1) Connect the UCON-4 cable or UCON-232S to Computer USB port.
- (2) Check the COM port address by clicking at **Start → Control Panel → System**
- (3) Select the **Hardware** tab and click on the **Device Manager** button.

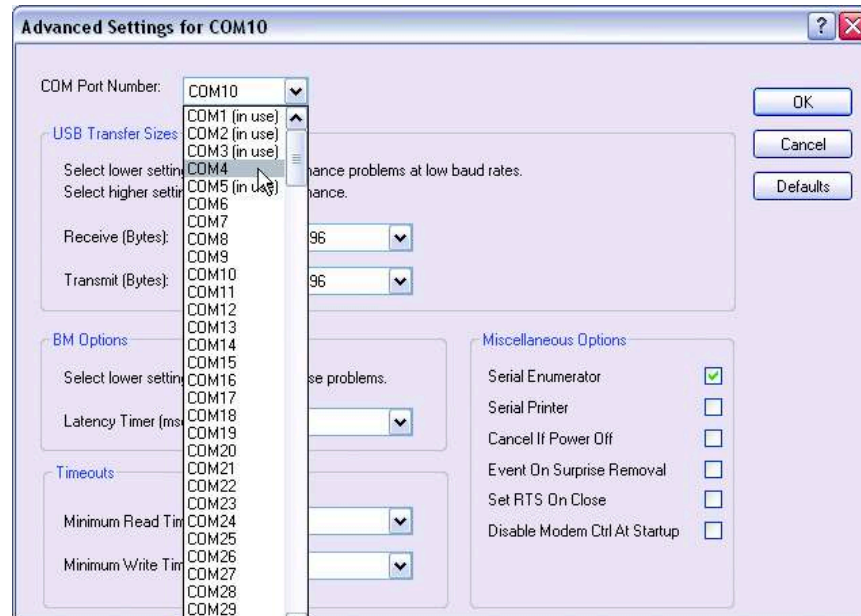
(4) Check the hardware listing. At the Port listing, you will found **USB Serial port (COM x)**. If COM port is higher than COM9 (this example is COM10), please click on the right-button mouse and select to **Properties**



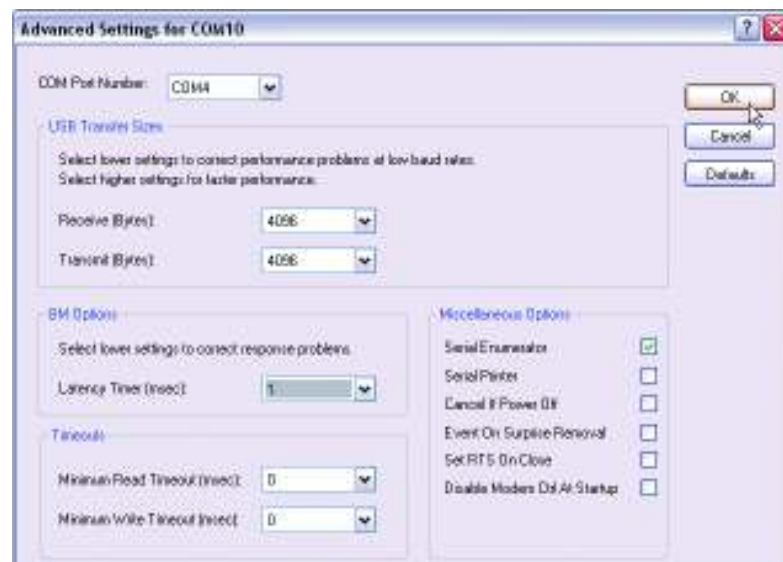
(5) The **USB Serial Port (COM10) Properties** window will appear. Select the **Port Setting** tab and set all value following the figure below and click on the **Advance** button



(6) The Advanced Setting for COM10 will appear. Click on the **COM Port Number** box to change to **COM4** or another port in range **COM1** to **COM9**.

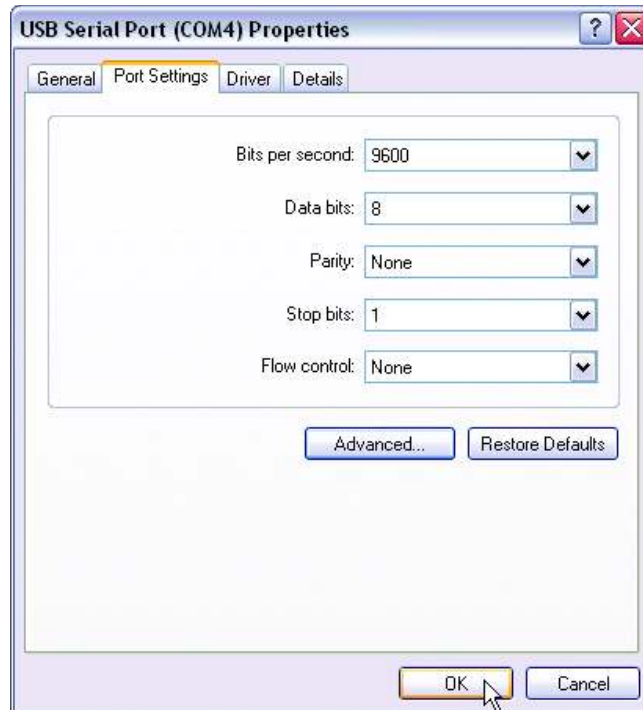


(7) Set the value following the figure below. Especially at the **Latency Timer (msec)** suggested to set to 1 and check the box at **Serial Enumerator**. Click **OK** button.





(8) Go back to the USB Serial Port Properties. Now the *COMport number at the title bar will change to COM4*. Click on the **OK** button.



(9) Remove the UCON-4 cable or UCON-232S from USB port and re-plug again. Check the USB Serial port address. The new address must be **COM4**. Now the UCON-4 cable and UCON-232S are ready for using with Arduino IDE software.





## 5 : POP-BOT movement activities

The POP-BOT has 2 channels of DC motor drivers. You can control the speed and direction of DC motor rotation with software. Because DC motor is driven by PWM (Pulse width modulation) signal. In this section describe how to drive DC motor with PWM and how to generate PWM signal of Arduino POP-168 microcontroller in C programming.

### 5.1 Basic operation of driving DC motor with PWM

By changing (modulating) the width of the pulse applied to the DC motor we can increase or decrease the amount of power provided to the motor, thereby increasing or decreasing the motor speed. Notice that, although the voltage has a fixed amplitude, it has a variable duty cycle. That means the wider the pulse, the higher the speed.

Refer Figure 5-1, the  $V_s$  supplies PWM signal to DC motor. The speed is dependent on  $T_{on}$  time (ON time of motor). At this time, DC motor will receive the full voltage;  $V_m$ . If  $T_{on}$ 's width is more, DC motor is received more voltage. It rotate in high speed. The ratio of  $T_{on}$  time in percentage with period ( $T$ ) is called Duty cycle. You can calculate this as follows :

$$\% \text{ duty cycle} = 100 \times \frac{T_{on}}{T_{on} + T_{off}} \dots\dots\dots(5.1)$$

$$\text{PWM frequency} = \frac{1}{T_{on} + T_{off}} = \frac{1}{T} \dots\dots\dots(5.2)$$

$$\text{Average DC motor voltage drop} = \text{Supply voltage} \times \text{duty cycle} (\%) \dots\dots\dots(5.3)$$

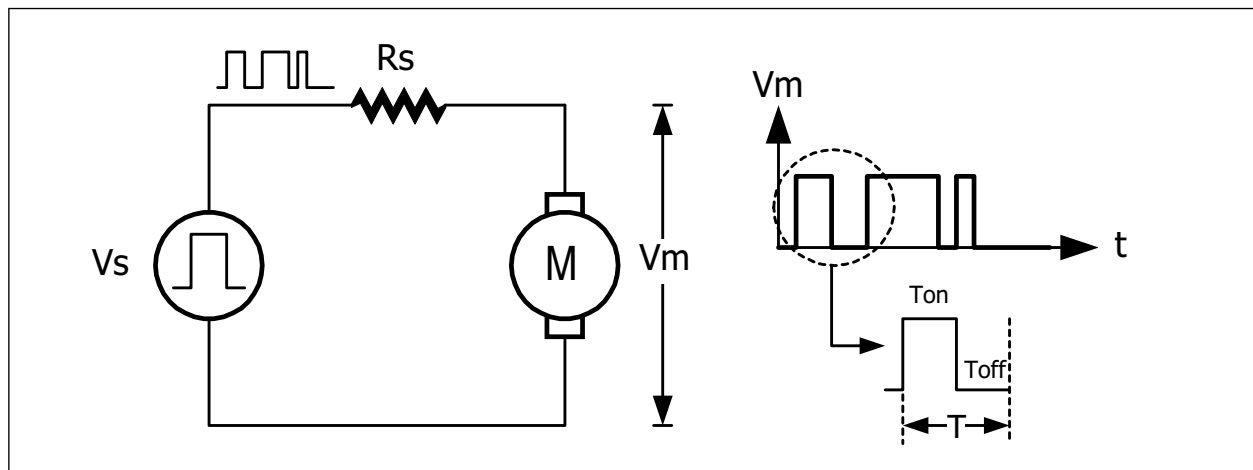


Figure 5-1 : The PWM signal for driving DC motor

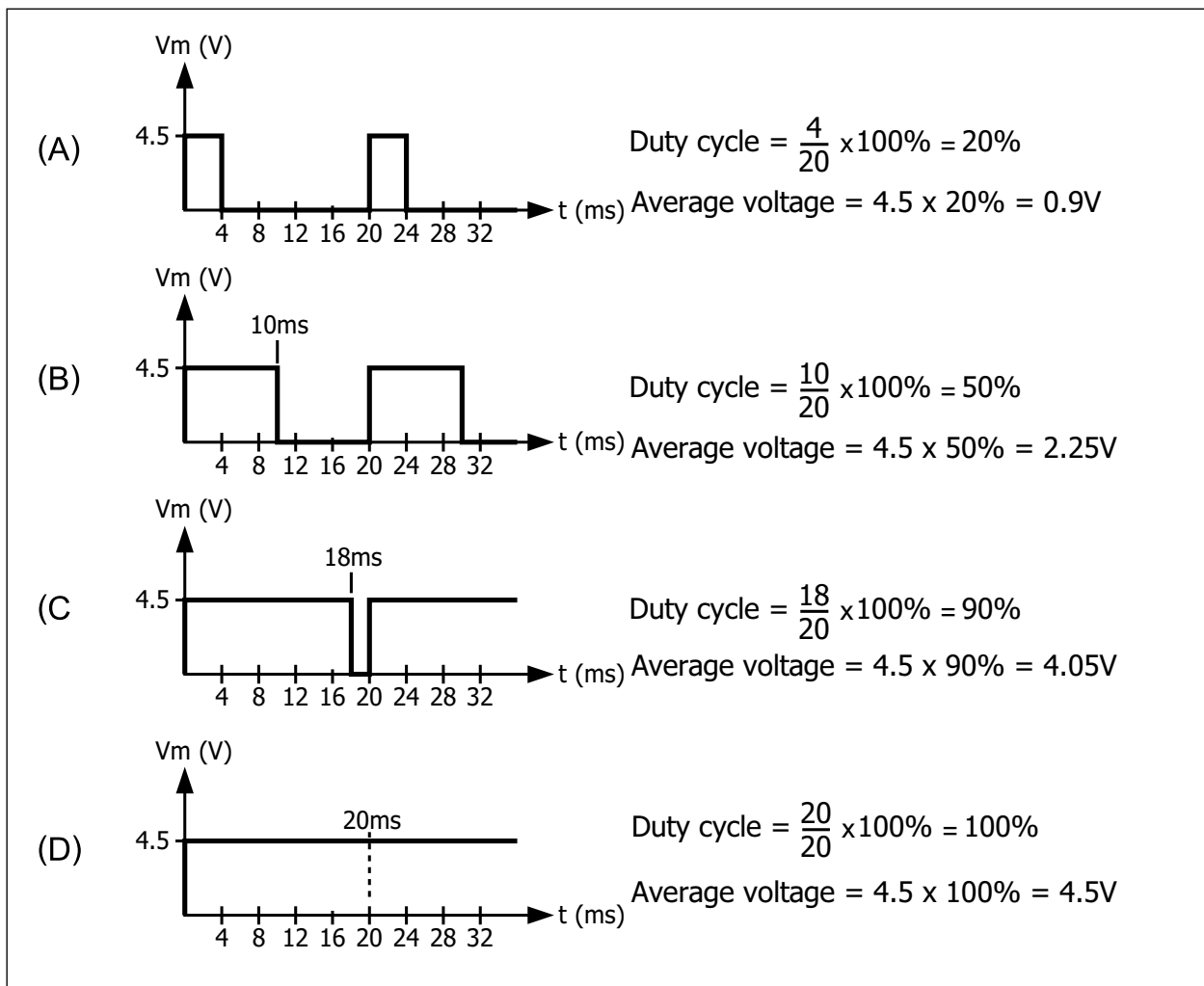


Figure 5-2 : Shows the relation between the different duty cycle and voltage across the DC motor.

Although the duty cycle is determine the motor speed. But DC motor can operate at limit frequency. If the PWM frequency is over the limit, DC motor will stop because its operation reach to saturation point. The example PWM signal in figure 5-2 has 20 milliseconds period and 50Hz frequency.

In Figure 5-2 (A) the PWM duty cycle is 20%. Motor will rotate with lowest speed because the voltage drop is only 0.9V. When increase the duty cycle in Figure 5-2 (B) and (C), voltage is applied to DC motor increase. Its speed is increase too.

In Figure 5-2 (D) the voltage is applied to DC motor full level because duty cycle is 100%. Thus, controlling the PWM duty cycle is a method of motor speed control.

## 5.2 Arduino with PWM

Arduino has a special function to generate PWM signal and outs to any digital pins. It is `analogWrite()`. User can adjust PWM duty cycle from 0 to 100% with value between 0 to 255.

At value = 0, no PWM signal is occurred. Voltage output as 0V.

At value = 51, The PWM signal has positive pulse width 20% of period. The duty cycle is equal to 20%.

At value = 127, The PWM signal has positive pulse width half of period. The duty cycle is equal to 50%.

At value = 191, The PWM signal has positive pulse width 75% of period. The duty cycle is equal to 75%.

At value = 255, The PWM signal has full positive pulse width. The duty cycle is equal to 100%.

The figure 5-2 shows the PWM signal at any duty cycle.

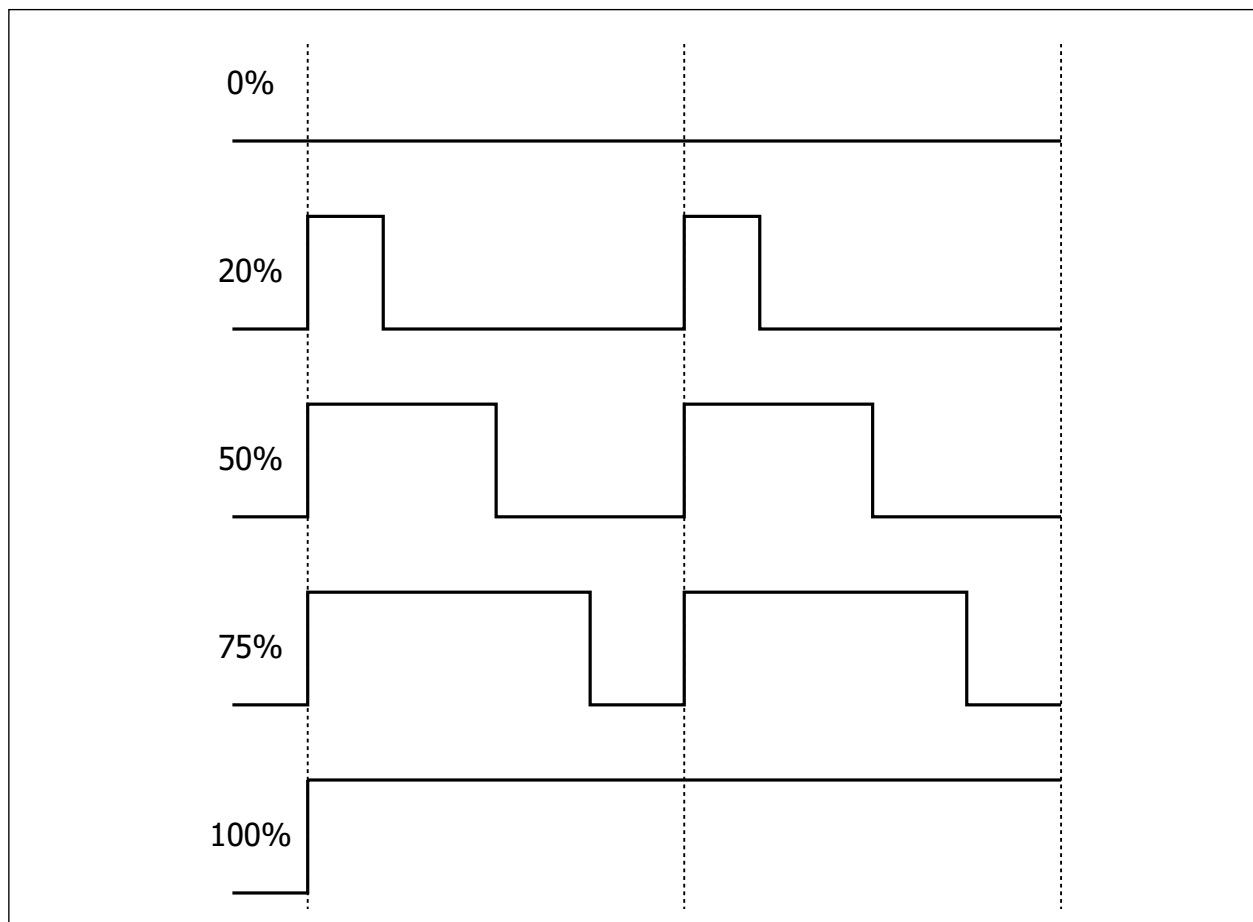


Figure 5-2 shows the PWM signal at any duty cycle.

Output voltage of PWM signal is average value relate the duty cycle. You can calculate from this relation below :

$$\text{Output\_voltage} = (\text{on\_time} / \text{off\_time}) * \text{max\_voltage}$$

We can use the PWM signal from `analogWrite()` function to adjust the LED brightness or amplify to drive the DC motor. The Arduino's pin that assigned to PWM output will output the PWM continue until do the `analogWrite()` function in new period or execute `digitalRead` and `digitalWrite` function at same pin.

Arduino POP-168 module has 4 analog output pins; it includes pin 3, 5, 6 and 9 (D3, D5, D6 and D9).

The `analogWrite` function format is

**`analogWrite(pin,value);`**

Thus; *pin as The Arduino's port pin 3, 5, 6 and 9*

*value as Duty cycle value 0 to 255.*

# Activity 1 : POP-BOT basic movement

## Activity 1-1 Forward and Backward movement

A1.1 Open the Arduino IDE and create the sketch code from Listing A1-1.

A1.2 Set the POP-BOT into Program mode. Upload the sketch to the robot.

A1.3 Turn-off power and Remove the download cable.

A1.4 Make sure the robot is on a flat surface. Turn-on the power and observe the operation.

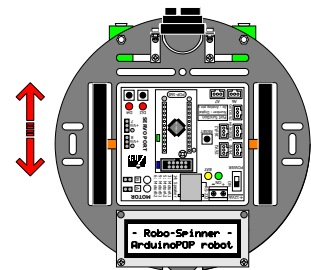
*The POP-BOT moves forward. See both LED motor indicators light in green color. After 1 second, both indicators change color to red and the robot moves backward.*

*If this is incorrect you will need to re-connect the motor cable to its opposite port/polarity. Do this until your robot moves correctly. Once its done, Use this motor port configuration for all your programming activities from now on. The robot will move forward and backward continually until you turn off its power.*

```

/*****
* POP-BOT V1.0
* Running Forward/Backward Full Speed
*****/
void setup() {
  pinMode(3, OUTPUT);      // Motor A1
  pinMode(5, OUTPUT);      // Motor A2
  pinMode(6, OUTPUT);      // Motor B2
  pinMode(9, OUTPUT);      // Motor B1
}
void Forward() {           // Robo-Spinner Go Forward Routine
  digitalWrite(3, HIGH);
  digitalWrite(5, LOW);
  digitalWrite(6, HIGH);
  digitalWrite(9, LOW);
}
void Backward() {          // Robo-Spinner Go Backward Routine
  digitalWrite(3, LOW);
  digitalWrite(5, HIGH);
  digitalWrite(6, LOW);
  digitalWrite(9, HIGH);
}
void loop() {
  Forward();
  delay(1000);
  Backward();
  delay(1000);
}
*****/

```



Listing A1-1 : Forward\_Backward.pde file; the Arduino sketch file for driving POP-BOT to forward and backward direction.

## Activity 1-2 Circle-shape movement control

With setting the different speed for each motor, it cause the robot move in circle-shape. You can try with this procedure as follows :

A1.5 Create a new sketch file and write the following C Codes shown in Listing A1-2.

A1.6 Set the POP-BOT into Program mode. Upload the sketch to the robot.

A1.7 Turn-off power and Remove the download cable.

A1.8 Make sure the robot is on a flat surface. Turn-on the power and observe the robot.

*The robot moves with circle-shape continually until you press the button switch at D 4 pin of P0 P-BOT controller board to stop the robot movement*

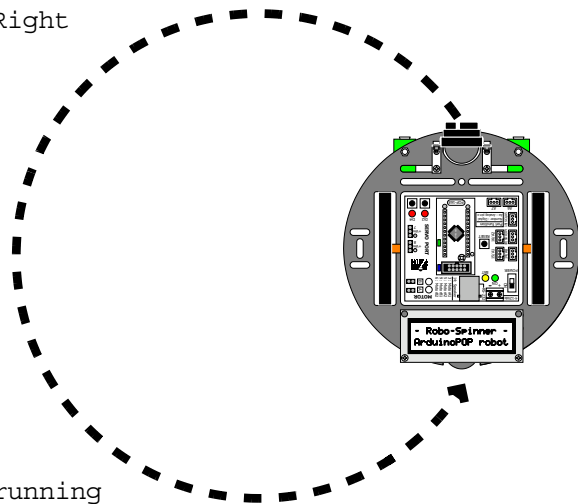
---

```

/*****
* POP-BOT V1.0
* Filename : MotorSpeedControl.pde
* Left Motor Lowspeed and Right Motor Highspeed Robo-Spinner Run in Circle
*****/
void setup(){
  pinMode(3,OUTPUT);      // Motor A1
  pinMode(5,OUTPUT);      // Motor A2
  pinMode(6,OUTPUT);      // Motor B2
  pinMode(9,OUTPUT);      // Motor B1
  pinMode(2,INPUT);       // Switch Left
  pinMode(4,INPUT);       // Switch Right
}
void Forward(int Lspeed,int Rspeed){
  analogWrite(3,Lspeed);
  digitalWrite(5,LOW);
  analogWrite(6,Rspeed);
  digitalWrite(9,LOW);
}
void Motor_Stop(){
  digitalWrite(5,LOW);
  digitalWrite(3,LOW);
  digitalWrite(6,LOW);
  digitalWrite(9,LOW);
}
void loop(){
  Forward(80,255);        // Circle running
  if(digitalRead(4)==0){  // if Switch Press
    Motor_Stop();         // Stop
    while(1);
  }
}
*****/

```

---



**Listing A1-2 : MotorSpeedControl.pde file; the Arduino sketch file for circle movement of POP-BOT**



## Activity 1-3 Square-shape movement control

A1.9 Create a new sketch file and write the following C Codes shown in Listing A1-3.

A 1.10 Upload the sketch to the robot. Turn-off power and Remove the download cable.

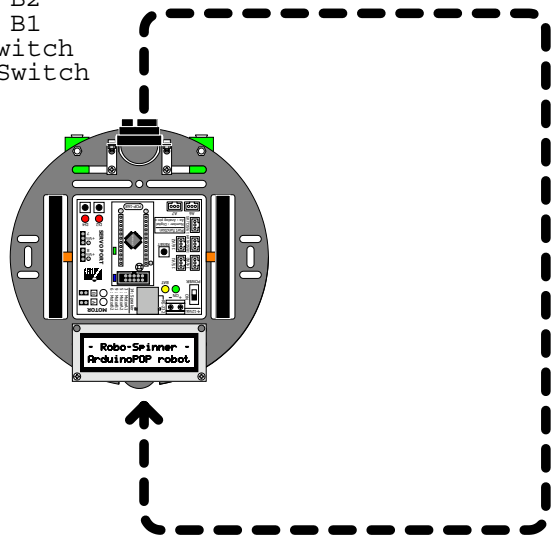
A1.11 Turn-on the power and observe the robot.

*The robot will be activated if SW1 or SW2 is being pressed. If you Press SW1, the robot will move forward and turn left continually, making a square. If you press SW2, the operation is vice versa.*

```

/*****
* Robo-Spinner V1.0
* Filename : Rectangle_Running.pde
* Running 90 Degree Turnleft And Turnright
*****/
void setup() {
    pinMode(3,OUTPUT);          // Motor A1
    pinMode(5,OUTPUT);          // Motor A2
    pinMode(6,OUTPUT);          // Motor B2
    pinMode(9,OUTPUT);          // Motor B1
    pinMode(2,INPUT);           // LeftSwitch
    pinMode(4,INPUT);           // RightSwitch
}
void Forward(int speed) {
    analogWrite(3,speed);
    digitalWrite(5,LOW);
    analogWrite(6,speed);
    digitalWrite(9,LOW);
}
void Spin_Left(int speed) {
    analogWrite(5,speed);
    digitalWrite(3,LOW);
    analogWrite(6,speed);
    digitalWrite(9,LOW);
}
void Spin_Right(int speed) {
    analogWrite(3,speed);
    digitalWrite(5,LOW);
    analogWrite(9,speed);
    digitalWrite(6,LOW);
}
void loop() {
    if (digitalRead(2)==0) {      // Switch Di2 Press
        while(1) {
            Forward(125);
            delay(900);
            Spin_Left(125);      // Turnleft 90 degree
            delay(400);
        }
    }
    if (digitalRead(4)==0) {      // Switch Di4 Press
        while(1) {
            Forward(125);
            delay(900);
            Spin_Right(125);     // Turnright 90 degree
            delay(400);
        }
    }
}

```



Listing A1-3 : Rectangle\_Running.pde file; the Arduino sketch file for square-shape movement



## Activity 2 : POP-BOT Bumper

### Activity 2-1 Simple collision detection

This activity is program the robot to detect the collision of both switches at the front of the POP-BOT robot. After a collision is encountered, the robot will move backward and change the its direction of movement.

A2.1 Open the Arduino IDE and create the sketch code from Listing A2-1.

A2.2 Set the POP-BOT into Program mode. Upload the sketch to the robot.

A2.3 Turn-off power and Remove the download cable.

A2.4 Prepare the demonstration area by placing and securing boxes or objects on the surface.

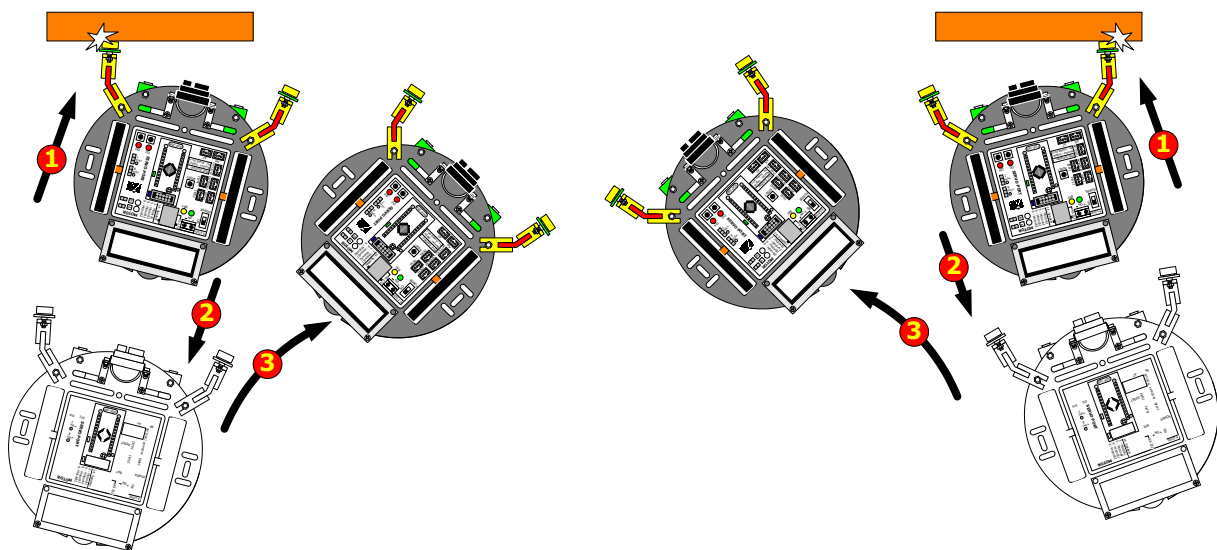
A2.5 Place the robot on the demonstration area. Turn-on the power and observe the robot.

The POP-BOT will read both switch status from **15/A1** and **17/A3** port. If any switch is pressed or touches some object, the result is logic `!0i`.

*In a normal operation, the robot will move forward continually.*

*If the Left Switch module touches any object, the robot will move backward and change its moving direction to its right to avoid the object*

*If the Right Switch module touches any object, the robot will move backward and change its moving direction to its left to avoid the object*



Robot attacks the object in the left.

Robot attacks the object in the right.

---

```

/*****
* POP-BOT V1.0
* Filename : BumperRobot.pde
* POP-BOT with bumper sensor
*****/
void setup() {
  pinMode(3,OUTPUT);           // Motor A1
  pinMode(5,OUTPUT);           // Motor A2
  pinMode(6,OUTPUT);           // Motor B2
  pinMode(9,OUTPUT);           // Motor B1

  pinMode(15,INPUT);           // Left Switch
  pinMode(17,INPUT);           // Right Switch
}

void loop(){
  Forward(150);
  if (digitalRead(15)==0) {      // Test Bumper Switch From Left
    Backward(150);delay(500);
    Spin_Right(200);delay(400);
  }
  if (digitalRead(17)==0) {      // Test Bumper Switch From Right
    Backward(150);delay(400);
    Spin_Left(200);delay(400);
  }
}
/*****/
void Forward(int speed){
  analogWrite(3,speed);
  digitalWrite(5,LOW);
  analogWrite(6,speed);
  digitalWrite(9,LOW);
}
void Backward(int speed){
  analogWrite(5,speed);
  digitalWrite(3,LOW);
  analogWrite(9,speed);
  digitalWrite(6,LOW);
}

void Spin_Left(int speed){
  analogWrite(5,speed);
  digitalWrite(3,LOW);
  analogWrite(6,speed);
  digitalWrite(9,LOW);
}
void Spin_Right(int speed){
  analogWrite(3,speed);
  digitalWrite(5,LOW);
  analogWrite(9,speed);
  digitalWrite(6,LOW);
}
/*****/

```

---

**Listing A2-1 : BumperRobot.pde file; the Arduino sketch file for POP-BOT Bumper activity.**

## Activity 2-2 Trapped in a corner situation

When the POP-BOT is in a corner, it is caught in between whereby to the left or right is a wall. This causes continuous hitting of the walls and thus trapping the robot in this corner. The solution is to modify your exiting C Code from Listing A2-1 to that which is shown in Listing A2-2.

A2.6 Open the Arduino IDE and create the sketch code from Listing A2-2.

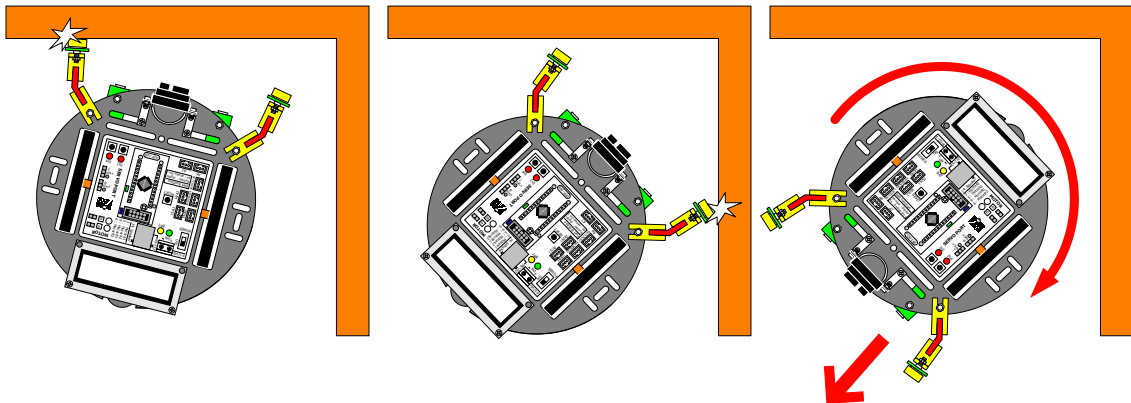
A2.7 Set the POP-BOT into Program mode. Upload the sketch to the robot.

A2.8 Turn-off power and Remove the download cable.

A2.9 Prepare the demonstration area by placing and securing boxes or objects on the surface same in Activity 2-1.

A2.10 Place the robot on the demonstration area. Turn-on the power and observe the robot.

*The robot will move forward and check for collision. If this happens over 5 times consecutively, the robot will spin 180 degrees to change its direction.*



```

/*****
* POP-BOT V1.0
* Filename : CornerEscape.pde
* Robot escapes from corner
*****/
int Count=0;
int Flag_0;

void setup(){
  pinMode(3,OUTPUT);      // Motor A1
  pinMode(5,OUTPUT);      // Motor A2
  pinMode(6,OUTPUT);      // Motor B2
  pinMode(9,OUTPUT);      // Motor B1

  pinMode(15,INPUT);      // Left Switch
  pinMode(17,INPUT);      // Right Switch
}

void loop(){
  Forward(150);

```

```

    if (Count>5){                                     // Trapped in a corner more than 5 times ?
        Count=0;
        Backward(150);                                // Escape from corner
        delay(2000);
        Spin_Right(200);
        delay(800);
    }

    if (digitalRead(15)==0){                           // Test left switch
        if(Flag_==1){                                  // Check previous state
            Count++;
        }
        else{
            Count=0;
        }
        Flag_ =0;
        Backward(150);                                // Normal operate
        delay(500);
        Spin_Right(200);
        delay(400);
    }

    if (digitalRead(17)==0){                           // Test right switch
        if(Flag_==0){                                  // Check previous state
            Count++;
        }
        else{
            Count=0;
        }
        Flag_ =1;
        Backward(150);                                // Normal operate
        delay(400);
        Spin_Left(200);
        delay(400);
    }
}
/*****/
void Forward(int speed){
    analogWrite(3,speed);
    digitalWrite(5,LOW);
    analogWrite(6,speed);
    digitalWrite(9,LOW);
}
void Backward(int speed){
    analogWrite(5,speed);
    digitalWrite(3,LOW);
    analogWrite(9,speed);
    digitalWrite(6,LOW);
}
void Spin_Left(int speed){
    analogWrite(5,speed);
    digitalWrite(3,LOW);
    analogWrite(6,speed);
    digitalWrite(9,LOW);
}
void Spin_Right(int speed){
    analogWrite(3,speed);
    digitalWrite(5,LOW);
    analogWrite(9,speed);
    digitalWrite(6,LOW);
}
/*****/

```

Listing A2-2 : CornerEscape.pde file; the Arduino sketch file for trapped in a corner solution of POP-BOT





## 6 : POP-BOT with Serial LCD

The Serial LCD or SLCD16x2 is the 16 characters 2 lines LCD module that communicates by serial interface. It receives data serially and displays on the LCD. Accept serial data at 2400 or 9600 baud rate. Normally LCD interfacing requires at least 6 wires but SLCD16x2 need only one signal wire. This display module is suitable for POP-BOT robot.

### 6.1 SLCD16x2 information

#### 8.1.1 Features

- Serial Input or Invert/Non-invert TTL/CMOS logic level.
- 1/8 or 1/16 Duty can be selected by jumper.
- Scott Edwards's LCD Serial Backpack™ command compatible addition with Extended Command that make LCD control easier.
- Easy to interface with the microcontroller
- Operation with +5 Vdc supply

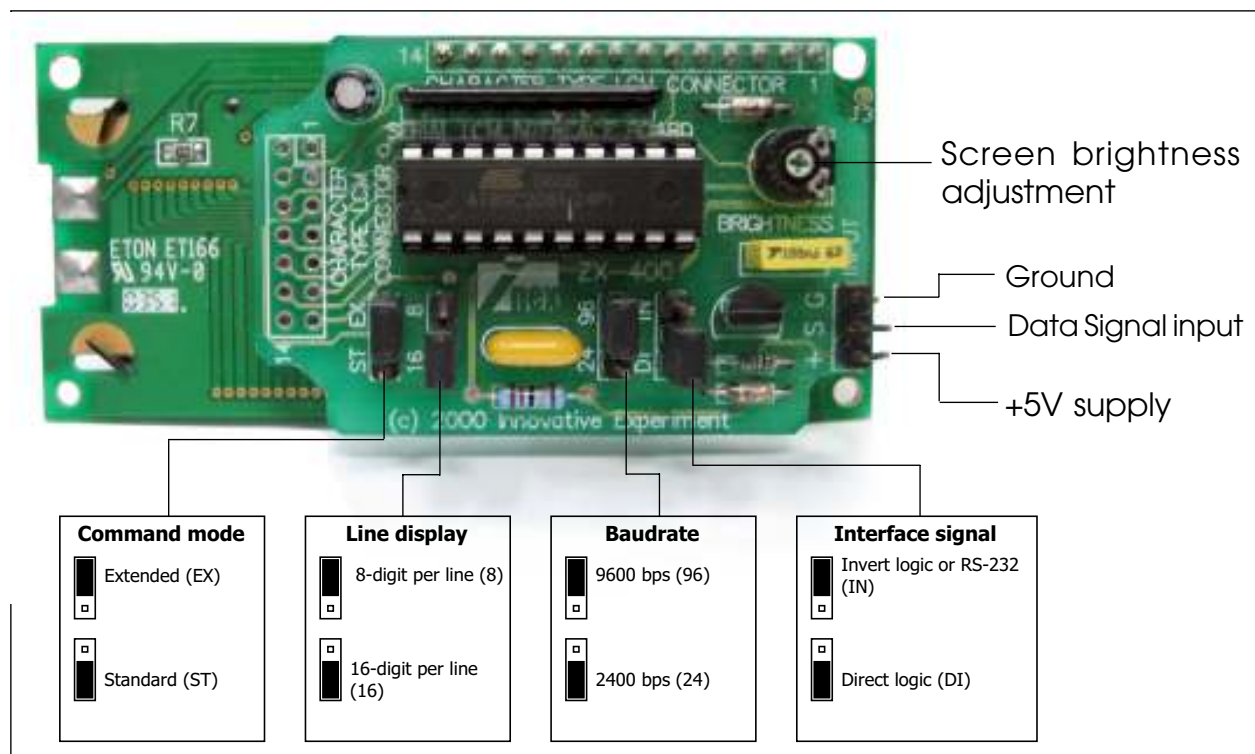


Figure 6-1 Details of SLCD16x2's jumper selections

## 6.1.2 Setting up

In the figure 6-1, it shows the detail of SLCD16x2 backside. The user will see 4 jumpers configured as follows :

(1) **Mode command jumper** : Selects the command modes. SLCD16x2 has 2 modes. One is Standard command (ST). This mode compatible with Scott Edwards's LCD Serial Backpack™. Another mode is Extended mode command (EX). **For POP-BOT activities select Standard command mode (ST).**

(2) **Lines jumper** : Selects the line displays ; 1/8 and 1/16 Duty. 1/8 Duty means displaying 8 digit per line. 1/16 Duty means displaying 16 digit per line or more. Normally set to **1/16**.

(3) **Baudrate select jumper** : 2 selections as 2400 and 9600 bps (bit per second) with 8N1 data format (8-bit data, no parity bit and 1 stop bit). **For POP-BOT set to 9600**

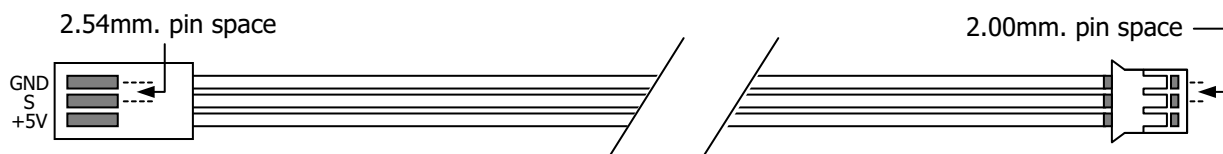
(4) **Interface signal jumper** : 2 selections as Invert logic TTL/CMOS level (IN) and Direct logic TTL/CMOS level (DI). **For POP-BOT set to DI**

SLCD16x2 provides a brightness adjustment with variable resistor at **BRIGHTNESS** position.

Interfacing connector has 3 pins : +5V Supply voltage (+), Serial data input (S) and Ground (G).

## 6.1.3 Interfacing SLCD16x2 with POP-BOT

The JST3AA-8 cable is required for connecting between SLCD with POP-BOT controller board. This cable wire assignment can show below.



The JST3AA-8 cable has the both ends as 2.00mm. housing. It will be connect to JST connector of any port of POP-BOT controller board and the input connector of SLCD16x2

After connecting, set all jumpers as follows :

- ï Select command mode to Standard (ST).
- ï Select the lines display to 16-digit per line (16).
- ï Select baudrate to 9600 bps (96).
- ï Select the interface signal to Direct (DI).



## 6.1.4 Data and Command sending

Once the SLCD16x2 is properly connected and configured, data and command can be sent serially. For data sending, you can send any message such as "Hello" via serial I/O directly, "Hello" message will be shown on your LCD.

For command sending, you can send standard instruction set to LCD (see Figure 8-2) and precede it with the instruction prefix character, ASCII 254 (0FE hex or 11111110 binary). SLCD16x2 treats the byte immediately after prefix as an instruction, then automatically returns to data mode.

An example: To clear screen on LCD, clear instruction is 00000001 binary (or ASCII 1), send (254) and (1) to SLCD16x2 (where parentheses in ( ) symbols mean single bytes set to these values)

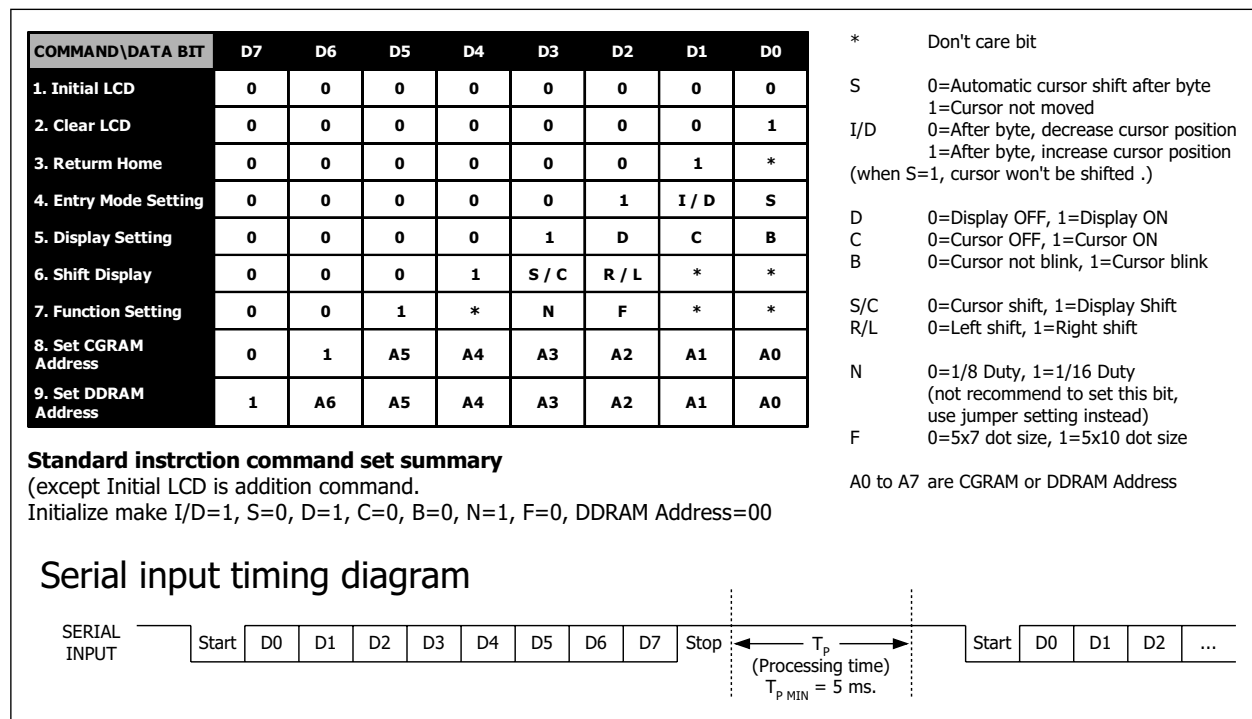


Figure 6-2 SLCD16x2 command summary and timing diagram

## 6.1.5 LCD Characters

Most of the LCD characters (Figure E) cannot be changed because they are stored in the ROM. However, the first eight symbols, corresponding to ASCII 0 through 7, are stored in the RAM. By Writing new values to the character-generator RAM (CGRAM), you can alter these characters as you want in 5x8 dots size.

HEX	00h	20h	30h	40h	50h	60h	70h	A0h	B0h	C0h	D0h	E0h	F0h														
DEC	0	32	40	48	56	64	72	80	88	96	104	112	120	160	168	176	184	192	200	208	216	224	232	240	248		
0			(	0	8	0	H	P	X	`	h	P	X			イ	ー	ワ	ネ	タ	ミ	リ	α	λ	ρ	Σ	
1			!	)	1	9	A	I	Q	Y	a	i	q	y		■	ウ	ア	ケ	ノ	チ	△	ル	ä	ˆ	au	
2			"	*	2	:	B	J	R	Z	b	j	r	z		「	エ	イ	コ	ハ	ツ	×	レ	E	i	θ	チ
3			#	+	3	;	C	K	S	L	c	k	s	l		」	オ	ウ	サ	ヒ	テ	モ	□	ε	×	ω	π
4			\$	,	4	<	D	L	T	¥	d	l	t	¥		、	ャ	イ	シ	フ	ト	†	ワ	μ	φ	Ω	π
5			%	-	5	=	E	M	U	l	e	m	u	}		・	ユ	オ	ス	ハ	ナ	1	ン	α	ε	U	÷
6			&	.	6	>	F	N	V	^	f	n	v	→		ヲ	ヨ	カ	セ	ホ	ニ	ヨ	ˆ	o	ñ	Σ	
7			'	/	7	?	G	O	W	_	g	o	w	←		ア	ッ	キ	ソ	マ	ヌ	ラ	"	a	ö	π	■

NOTE: Custom characters occupy ASCII 0-7  
ASCII 8-15 repeat the custom characters  
ASCII 128-159 are used for Extended Mode Command only

**LCD character set.** (Built-in character on HD44780A or SED1278F0A)

Create your symbols by pointing to the CGRAM location, then write the first line whose bits form the desired pattern, and point to next CGRAM address to write bits later. Repeat this procedure until 8 times (one character), your character is ready to use now. CGRAM 0 is located on CGRAM Address 0x00 to 0x07, CGRAM 1 on 0x08 to 0x0F, CGRAM 2 on 0x10 to 0x17, ...until CGRAM 7 on 0x38 to 0x3F. See figure below

Bitmap Layout						Byte Values	
	bit 4	bit 3	bit 2	bit 1	bit 0	binary	decimal
byte 0	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>	xxxx0000	0
byte 1	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>	xxxx00100	4
byte 2	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>	xxxx00010	2
byte 3	<input checked="" type="checkbox"/>	<input checked="" type="checkbox"/>	<input checked="" type="checkbox"/>	<input checked="" type="checkbox"/>	<input checked="" type="checkbox"/>	xxxx11111	31
byte 4	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>	<input checked="" type="checkbox"/>	<input type="checkbox"/>	xxxx00010	2
byte 5	<input type="checkbox"/>	<input type="checkbox"/>	<input checked="" type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>	xxxx00100	4
byte 6	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>	xxxx00000	0
byte 7	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>	<input type="checkbox"/>	xxxx00000	0

### Defining custom symbols.

Example: Load arrow symbol on CGRAM 3, a program would send the following bytes to the SLCD controller.

```
[254], [01011000 b], [0],
[254], [01011001 b], [4],
[254], [01011010 b], [2],
[254], [01011011 b], [31],
[254], [01011100 b], [2],
[254], [01011101 b], [4],
[254], [01011110 b], [0],
[254], [01011111 b], [0]
```

## Standard LCD Instruction set

Only the instruction register (IR) and the data register (DR) of the LCD can be controlled by the MCU. Before starting the internal operation of the LCD, control information is temporarily stored into these registers to allow interfacing with various MCUs, which operate at different speeds, or various peripheral control devices. The internal operation of the LCD is determined by signals sent from the MCU. These signals, which include register selection signal (RS), read/write signal (R/W), and the data bus (DB0 to DB7), make up the LCD instructions (Table 3). There are four categories of instructions that:

- Designate LCD functions, such as display format, data length, etc.
- Set internal RAM addresses
- Perform data transfer with internal RAM
- Perform miscellaneous functions

Although looking at the table you can make your own commands and test them. Below is a brief list of useful commands which are used frequently while working on the LCD.

Instruction	Hex	Decimal
Function Set: 8-bit, 1 Line, 5x7 Dots	0x30	48
Function Set: 8-bit, 2 Line, 5x7 Dots	0x38	56
Function Set: 4-bit, 1 Line, 5x7 Dots	0x20	32
Function Set: 4-bit, 2 Line, 5x7 Dots	0x28	40
Entry Mode	0x06	6
Display off Cursor off (clearing display without clearing DDRAM content)	0x08	8
Display on Cursor on	0x0E	14
Display on Cursor off	0x0C	12
Display on Cursor blinking	0x0F	15
Shift entire display left	0x18	24
Shift entire display right	0x1C	30
Move cursor left by one character	0x10	16
Move cursor right by one character	0x14	20
Clear Display (also clear DDRAM content)	0x01	1
Set DDRAM address or cursor position on display	0x80+add*	128+add*
Set CGRAM address or set pointer to CGRAM location	0x40+add**	64+add**

\* **DDRAM address given in LCD basics section**

\*\* **CGRAM address from 0x00 to 0x3F, 0x00 to 0x07 for char1 and so on..**

## 6.2 Things to know about interface Arduino with SLCD16x2

The procedure of Arduino POP-168 with Serial LCD interfacing is :

(1) Include the **SoftwareSerial.h** library with `#include` command

(2) Define the POP-168 port pin with `#define` command as follows.

```
#define rxPin 3    // Set Di 3 as serial receiver pin or rxPin
#define txPin 2    // Set Di 2 as serial transmitter pin or txPin
SoftwareSerial mySerial = SoftwareSerial(rxPin, txPin);
```

(3) At **setup()**, you need to set the transmit pin to High logic, delay and set baudrate to 9600 with `mySerial.begin(9600);` command. The sample setup code is shown below.

```
digitalWrite(txPin, HIGH); // set txPin high (as recommended)
delay(1000);

// define pin modes for tx, rx pins:
pinMode(rxPin, INPUT);
pinMode(txPin, OUTPUT);
mySerial.begin(9600);          // set baudrate
```

It is recommended setup code for Arduino when interface with Serial LCD or SLCD16x2 module.

The important commands for interfacing with SLCD16x2 module of POP-BOT are :

(1) Initialized command :

```
mySerial.print(0xFE,BYTE);
mySerial.print(Command,BYTE);
```

(2) Clear LCD screen :

```
mySerial.print(0x01,BYTE);
```

(3) Move cursor to top left position or HOME position :

```
mySerial.print(0x80,BYTE);
```

(4) Move cursor to left position of bottom line :

```
mySerial.print(0xC0,BYTE);
```

(5) For writing the message, user must put message and covered by " ".

```
mySerial.print("Hello");    // Show "HELLO"
```

## Activity 3 : SLCD16x2 simple programming

---

A3.1 Open the Arduino IDE and create the sketch code from Listing A3-1.

A3.2 Set the POP-BOT into Program mode. Upload the sketch to the robot.

A3.3 Reset the POP-BOT and observe the SLCD16x2 operation.

*The SLC D 16x2 shows message below:*

```
POP-BOT
Hello World !
```

---

```

/*****
* POP-BOT V1.0
* Filename : SimpleLCD.pde
* Show message on SLCD
*****/
#include <SoftwareSerial.h>
#define rxPin 16
#define txPin 16
SoftwareSerial MySerial = SoftwareSerial(rxPin,txPin);

void setup(){
  digitalWrite(txPin,HIGH);
  delay(1000);
  pinMode(txPin,OUTPUT);
  MySerial.begin(9600);
  delay(1000);
}
void loop(){
  MySerial.print(0xFE,BYTE);
  MySerial.print(0x80,BYTE);
  MySerial.print("POP-BOT");
  MySerial.print(0xFE,BYTE);
  MySerial.print(0xC0,BYTE);
  MySerial.print("Hello World !");
  while(1);
}

```

---

Listing A3-1 : SimpleLCD.pde file; the Arduino sketch file for demonstration the simple operation of Serial LCD with POP-BOT



## Activity 4 : Control the SLCD16x2 with command

You can control many display operations of SLCD16x2 such as set the line display, clear screen, select the display format etc. by sending the control commands to SLCD16x2. For the Standard command mode, start byte must start with 0xFE and following the command. User can see the LCD command in SLCD information topic in this chapter.

A4.1 Open the Arduino IDE and create the sketch code from Listing A4-1.

A4.2 Set the POP-BOT into Program mode. Upload the sketch to the robot.

A4.3 Reset the POP-BOT and observe the SLCD16x2 operation.

*The SLCD16x2 show many message displaying following the specific by program.*

```

/*****
 * POP-BOT V1.0
 * Filename : SLCDRunningText.pde
 * Show running text and number on Serial LCD
 *****/
#include <SoftwareSerial.h>
#define rxPin 16
#define txPin 16
SoftwareSerial MySerial = SoftwareSerial(rxPin,txPin);

void setup(){
  digitalWrite(txPin,HIGH);
  delay(1000);
  pinMode(txPin,OUTPUT);
  MySerial.begin(9600);
  delay(1000);
}
void LCD_CMD(int Command){
  MySerial.print(0xFE,BYTE);          // Command
  MySerial.print(Command,BYTE);
}
void loop(){
  int i;
  LCD_CMD(0x80);                      // First Line
  MySerial.print("POP-BOT");
  LCD_CMD(0xC0);                      // Second Line
  MySerial.print("Hello World !");
  delay(2000);

  LCD_CMD(0x01);                      // Clear Screen Command
  LCD_CMD(0x85);                      // ROW 1,COL 5
  MySerial.print("From");
  delay(500);

  LCD_CMD(0x07);                      // Shift left text
  for(i=0;i<9;i++){
    MySerial.print(" ");
    delay(200);
  }
}

```

```

LCD_CMD(0x05); // Shift right text
for(i=0;i<9;i++){
  MySerial.print(" ");
  delay(200);
}

for(i=0;i<9;i++){ // Blinking text
  LCD_CMD(0x08);
  delay(200);
  LCD_CMD(0x0C);
  delay(200);
}

LCD_CMD(0x00); // Show text
MySerial.print("Innovative"); // Line 1
LCD_CMD(0xC0);
MySerial.print("Experiment"); // Line 2
delay(5000);
i=0;

// Show Number
LCD_CMD(0x01); // Clear screen
MySerial.print("Counter"); // Line 1
while(1){
  i++;
  LCD_CMD(0xC5); // Line 2
  MySerial.print(i,DEC);
  delay(100);
}
}

```

### **Program description**

**Part 1** Initial the communication module in microcontroller and SLCD16x2

**Part 2** Select the target line to display. The top line (0x80) is set to show POP-BOT message. The bottom line (0xC0) is set to show Hello World! message.

**Part 3** Send the Clear screen command (0x01) and define the first letter at 5th digit on the top line of LCD (0x85) to show From message.

**Part 4** Send the shift left command (0x07) and loop to shift the From message to left direction.

**Part 5** Send the shift right command (0x05) and loop to shift the From message back to start.

**Part 6** Loop for sending the Turn-off display command (0x08) and Turn-on display command (0x0C) and swap. It cause the message From will be blink.

**Part 7** The operation is same Part 2 but change the message on top line as Innovative and bottom line as Experiment

---

**Listing A4-1 : SLCDrunningText.pde file; the Arduino sketch file for demonstration more function of Serial LCD operation**







## 7 : POP-BOT line tracking

Line following or Line tracking is a popular and common activity in robotics learning. The purpose of this activity is to learn about how to interface analog sensors. In the POP-BOT robot kit, it has a pair of Infrared reflector sensor for this activity. Two IR Reflector sensors will be installed at the bottom of the POP-BOT so that it can detect both white and black lines.

### 7.1 ZX-03 : Infrared reflector sensor

The heart of this sensor is TCRT5000 reflective object sensor. It is designed for close proximity infrared (IR) detection. There is an infrared diode behind its transparent blue window and an infrared transistor behind its black window. When the infrared emitted by the diode reflects off a surface and returns to the black window, it strikes the infrared transistor's base, causing it to conduct current. The more infrared incident on the transistor's base, the more current it conducts. The figure 7-1 shows the operation of ZX-03 sensor.

When used as an analog sensor, the ZX-03 can detect shades of gray on paper and distances over a short range if the light in the room remains constant.

The suitable distance from sensor to line or floor is during 3 to 8 mm. The output voltage is during 0.1 to 4.8V and digital value from 10-bit A/D converter is 20 to 1,000. Thus, ZX-03 will be suitable to apply to line tracking sensor.

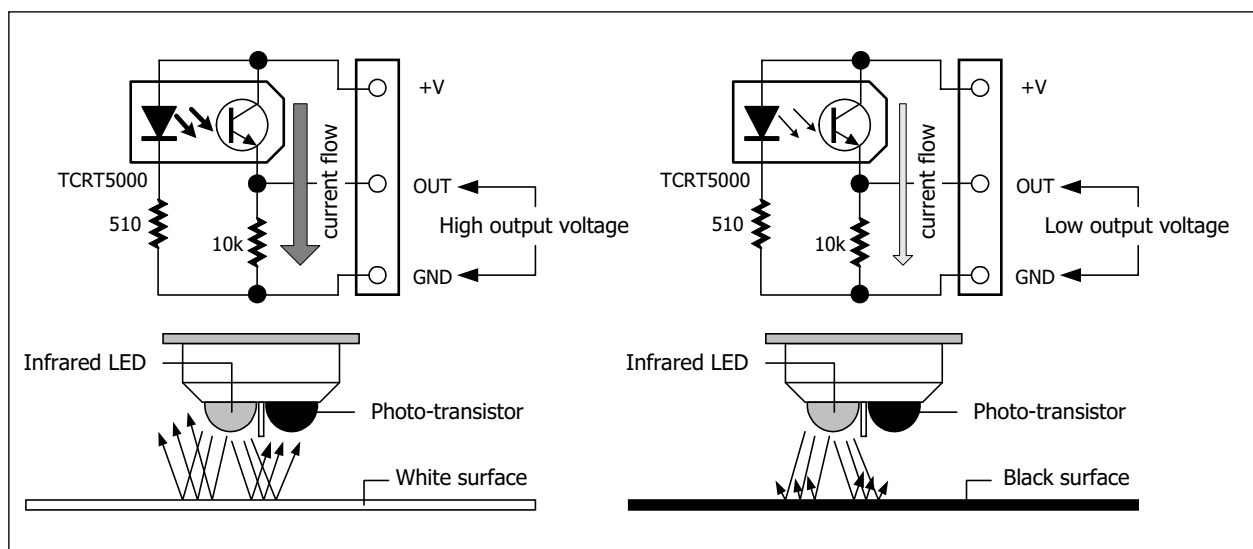


Figure 7-1 The operation of ZX-03 Infrared reflector sensor board with white and black surface

## 7.2 Line tracking activity preparation

### 7.2.1 Demonstration field component preparation

All activities are described in this chapter use the 'make your own demonstration field'. They include white surface with black line and black surface with white line field. You must make your own field using the items below (not provided in this kit) :

1. Polypropylene board or PP board white and Black sheet. Size is 90 x 60 cm. However the sizing can change depending on your applications and resources.
2. Black and white electrical tape 1 inches width 2 rolls per color. 3M brand is recommended.
3. Scissors or a Cutter

### 7.2.2 Set the reference value for line tracking activity with `analogRead()` function

POP-BOT can detect the difference between lines and surface by reading the infrared reflector sensors value via analog input ports. POP-BOT programming use **`analogRead()`** function of Arduino for reading analog sensor port.

POP-BOT reads the black line and surface data with low value (less than 400 and minimum is 0) and reads the white line and surface data with high value (higher than 500 and maximum is 1023). The reference value for making the decision about line or surface is average value from summing of black and white surface as follows :

$$\text{Reference value} = (\text{White surface value} + \text{black surface value}) / 2$$

The activity 5 shows the detail of the reference value for this line tracking activity.

## Activity 5 : Testing black and white area

The POP-BOT robot is attached with 2 of Infrared reflector modules at bottom of the robot base. Thus, this activity will only dwell on the programming.

Before developing the robot to track the line, developers must program the robot to detect the difference between black and white surface.

A5.1 Open the Arduino IDE and create the sketch code from Listing A5-1.

A5.2 Set the POP-BOT into Program mode. Upload the sketch to the robot.

A5.3 Disconnect the download cable.

---

```

/*****
* POP-BOT V1.0
* Filename : AnalogRead.pde
* Read analog signal from Infrared reflector sensor to show on SLCD
*****/
#include <SoftwareSerial.h>
#define rxPin 16
#define txPin 16
SoftwareSerial MySerial = SoftwareSerial(rxPin,txPin);
int LeftSensor;
int RightSensor;

void setup(){
    digitalWrite(txPin,HIGH);
    pinMode(txPin,OUTPUT);
    MySerial.begin(9600);
    delay(1000);
}
void LCD_CMD(int Command){
    MySerial.print(0xFE,BYTE);          // Command
    MySerial.print(Command,BYTE);
}
void loop(){
    LeftSensor = analogRead(7);          // Read value from left sensor
    RightSensor = analogRead(6);         // Read value from right sensor
    LCD_CMD(0x80);                       // Set display to first Line
    MySerial.print("L Sensor=          "); // Show left sensor value on 1st line
    LCD_CMD(0x8A);
    MySerial.print(LeftSensor,DEC);

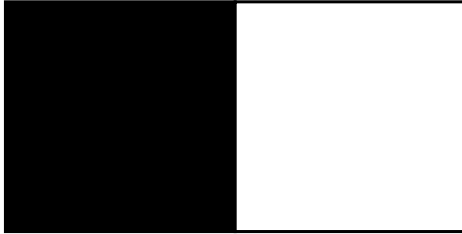
    LCD_CMD(0xC0);                       // Set display to second Line
    MySerial.print("R Sensor=          "); // Show right sensor value on 2nd line
    LCD_CMD(0xCA);
    MySerial.print(RightSensor,DEC);
    delay(200);
}

```

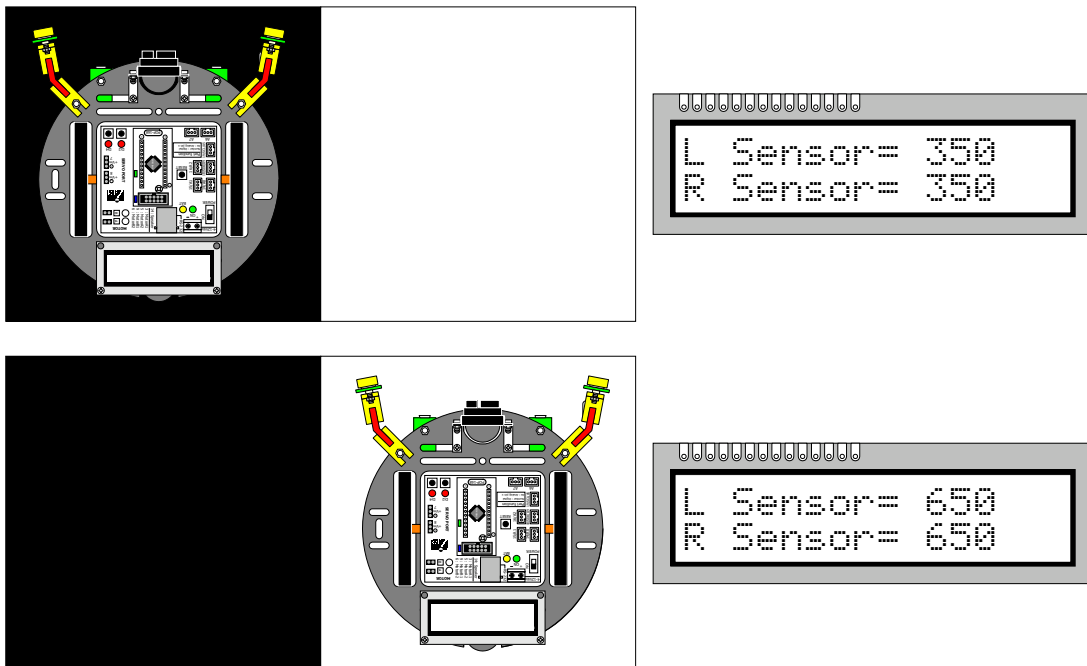
---

**Listing A5-1 : AnalogRead.pde file; the Arduino sketch file for reading the Infrared reflector sensor to display on Serial LCD of POP-BOT robot**

A5.4 Make the black & white testing sheet similar to the illustration as shown below. The white surface area is 30 x 30 cm. and black surface is 30 x 30cm. (recommended).



A5.5 Place the POP-BOT that is programmed already from step A5.3 above the white surface of the testing chart. Turn on the robot. See the reading value at SLCD screen and record it. After that, read value of black surface and record the value also.



*The result is:*

The white surface value is between 500 and 950

The black surface value is between 100 and 400

The example reference value for detecting the line is  $(650+350) / 2 = 500$ .



## Activity 6 : POP-BOT border movement

---

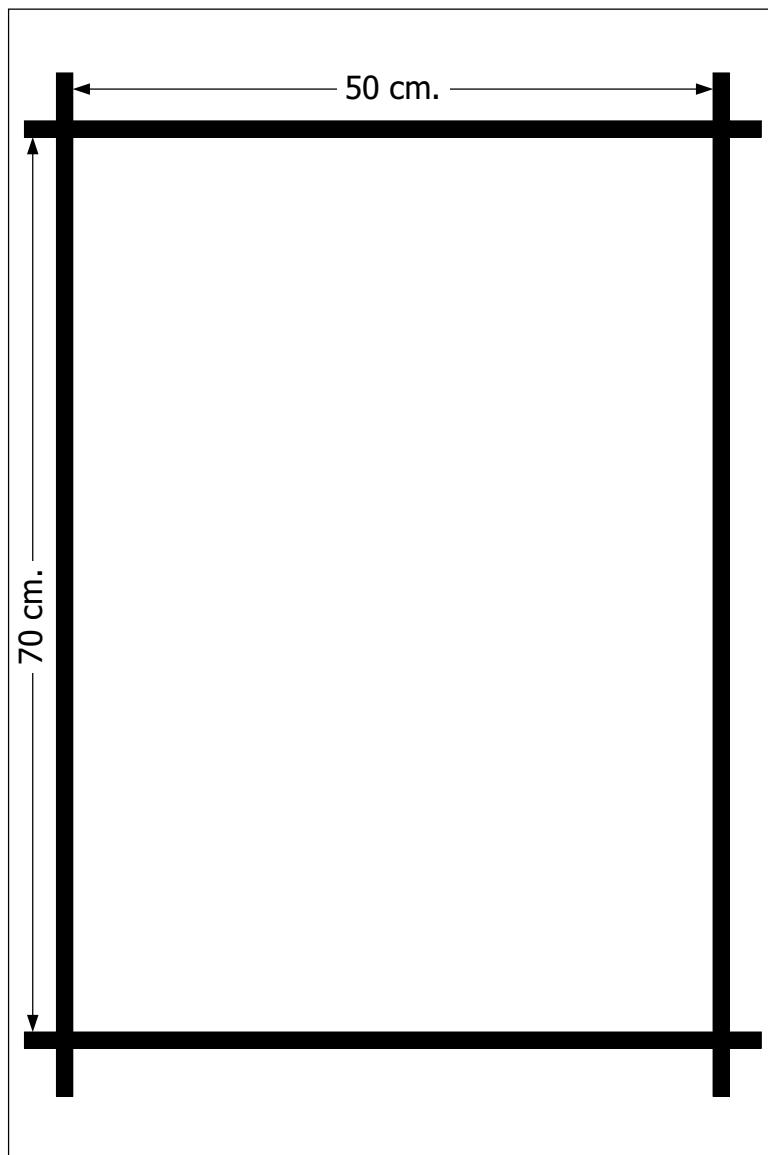
After knowing the values of the black and white surfaces, the next activity touches on how to move POP-BOT within the black border.

A6.1 Open the Arduino IDE and create the sketch code from Listing A6-1

A6.2 Set the POP-BOT into Program mode. Upload the sketch to the robot.

A6.3 Disconnect the download cable.

A6.4 Make the border field following the illustration below. The white surface area is 90 x 60 cm. and black line width is 1 inches (2.5 cm.)



---

```

/*****
* POP-BOT V1.0
* Filename : BlackBorderMove.pde
* POP-BOT moves in the black border line
*****/
int Ref=500;
int Left,Right;
void setup(){
  pinMode(3,OUTPUT);          // Motor A1
  pinMode(5,OUTPUT);          // Motor A2
  pinMode(6,OUTPUT);          // Motor B2
  pinMode(9,OUTPUT);          // Motor B1
}
void loop(){
  Left = analogRead(7);        // Read value from the left ZX-03 sensor
  Right = analogRead(6);       // Read value from the right ZX-03 sensor
  if (Left>Ref && Right>Ref){   // Both sensors detect the white surface
    Forward(150);
  }
  else if (Left<Ref && Right<Ref){ // Both sensors detect the black line
    Backward(150);delay(100);
  }
  else if (Left<Ref) {         // Only left sensor detects the black line
    Backward(150);delay(300);
    Spin_Right(150);delay(500);
  }
  else if (Right<Ref){         // Only right sensor detects the black line
    Backward(150);delay(300);
    Spin_Left(150);delay(400);
  }
}
void Forward(int speed){
  analogWrite(3,speed);
  digitalWrite(5,LOW);
  analogWrite(6,speed);
  digitalWrite(9,LOW);
}
void Backward(int speed){
  analogWrite(5,speed);
  digitalWrite(3,LOW);
  analogWrite(9,speed);
  digitalWrite(6,LOW);
}
void Spin_Left(int speed){
  analogWrite(5,speed);
  digitalWrite(3,LOW);
  analogWrite(6,speed);
  digitalWrite(9,LOW);
}
void Spin_Right(int speed){
  analogWrite(3,speed);
  digitalWrite(5,LOW);
  analogWrite(9,speed);
  digitalWrite(6,LOW);
}

```

---

**Listing A6-1 : BlackBorderMove.pde file; the Arduino sketch file for black border movement demonstration of POP-BOT**

A6.5 Place the POP-BOT within the black border field. Turn on the robot. Observe the robot movement.

*P0 P-B0 T moves forward on the white surface until any sensor detects the black border. This is robot behavior:*

***If both sensor detect the black line :*** *P0 P-B0 T move backward for a short while and then forward again.*

***If the left sensor detects the black line :*** *P0 P-B0 T move backward for a short while, spin right and then forward again.*

***If the right sensor detects the black line :*** *P0 P-B0 T move backward for a short while, spin left and then forward again.*

*Finally, P0 P-B0 T moves within the black border continually.*



## Activity 7 : POP-BOT with ping-pong movement

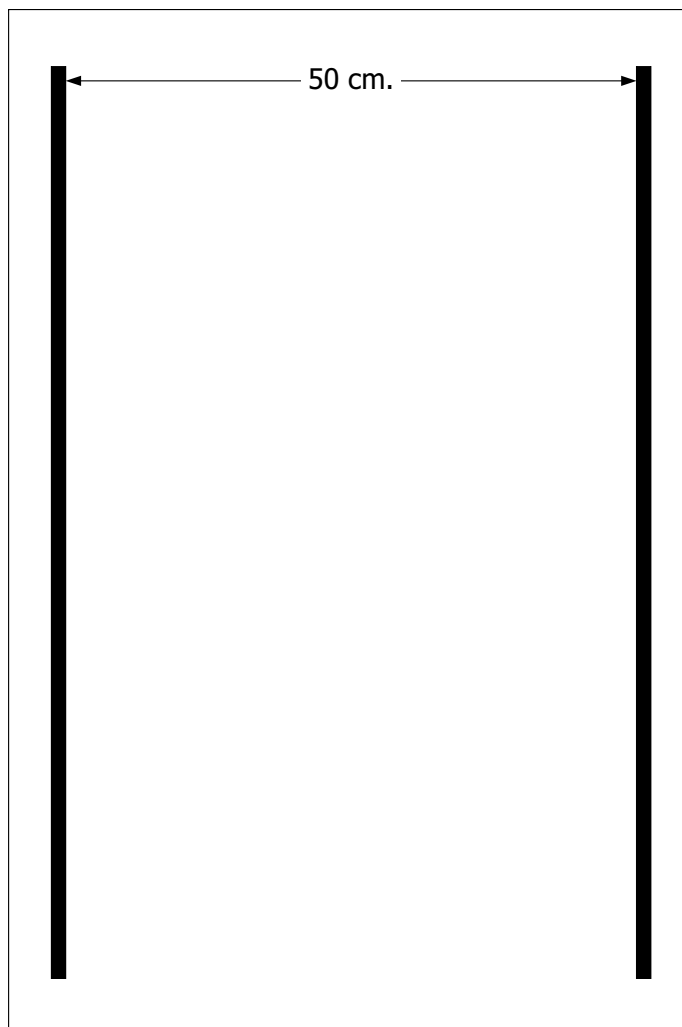
In this activity, it shows how POP-BOT move in a ZIG-ZAG format. The black line is the turning point. The POP-BOT moves forward until found the black line to change the direction. Loop this operation always. Thus, robot will move within space between both black lines.

A7.1 Open the Arduino IDE and create the sketch code from Listing A6-1

A7.2 Set the POP-BOT into Program mode. Upload the sketch to the robot.

A7.3 Disconnect the download cable.

A7.4 Make the Ping-pong field following the illustration below. The white surface area is 90 x 60 cm. and black line width is 1 inches (2.5 cm.)





---

```

/*****
* POP-BOTV1.0
* Filename : PingPong.pde
* POP-BOT moves zigzag with 2 parallel lines
*****/
int Ref=500;
int Left,Right;
void setup(){
  pinMode(3,OUTPUT);          // Motor A1
  pinMode(5,OUTPUT);          // Motor A2
  pinMode(6,OUTPUT);          // Motor B2
  pinMode(9,OUTPUT);          // Motor B1
}
void loop(){
  Left = analogRead(7);        // Read value from the left ZX-03 sensor
  Right = analogRead(6);        // Read value from the right ZX-03 sensor
  if (Left>Ref && Right>Ref){    // Both sensors detect the white surface
    Forward(150);
  }
  else if (Left<Ref && Right<Ref){ // Both sensors detect the black line
    Backward(150);delay(100);
  }
  else if (Left<Ref) {          // Only the left sensor detects the line
    Spin_Right(150);
    delay(420);
  }
  else if (Right<Ref){          // Only the right sensor detects the line
    Spin_Left(150);
    delay(420);
  }
}

void Forward(int speed){
  analogWrite(3,speed);
  digitalWrite(5,LOW);
  analogWrite(6,speed);
  digitalWrite(9,LOW);
}
void Backward(int speed){
  analogWrite(5,speed);
  digitalWrite(3,LOW);
  analogWrite(9,speed);
  digitalWrite(6,LOW);
}
void Spin_Left(int speed){
  analogWrite(5,speed);
  digitalWrite(3,LOW);
  analogWrite(6,speed);
  digitalWrite(9,LOW);
}
void Spin_Right(int speed){
  analogWrite(3,speed);
  digitalWrite(5,LOW);
  analogWrite(9,speed);
  digitalWrite(6,LOW);
}

```

---

**Listing A7-1 : PingPong.pde file; the Arduino sketch file for Ping-pong movement demonstration of POP-BOT**

### Programming concept

The steps of programming in this activity are :

- (1) Find the value between the white surface and black line.
- (2) Read the sensor values and store to compare
- (3) Check the condition as follows :

**Case #1 :** Both sensors detect the white surface

**Action :** Robot moves forward.

**Case #2 :** Only the left sensor detects the black line.

**Action :** Robot spins right to change direction for moving to the black line opposite side.

**Case #3 :** Only the right sensor detects the black line.

**Action :** Robot spins left to change direction for moving to the black line opposite side.

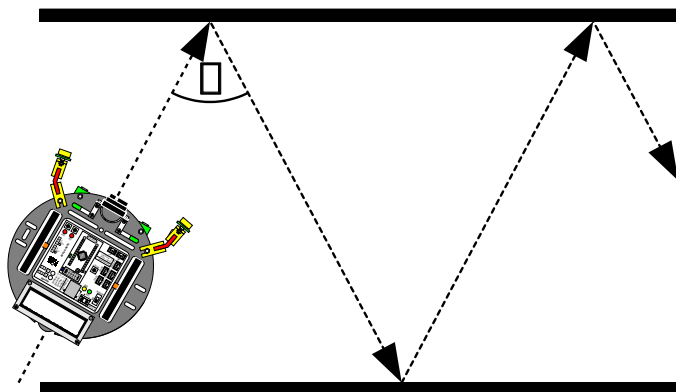
**Case #4 :** Out of 3 conditions above

**Action :** Up to programmer purpose.

- (4) Back to step (2).

A7.5 Place the POP-BOT on the Ping-pong field. Turn on the robot. Observe the robot movement.

In this program, determine the tuning time to 150 millisecond approximation. It cause the tuning angle  $\phi$  (see the illustration below). Programmer can adjust the time value to make the suitable angle for control the movement path correctly.



If the time value is more, the  $\phi$  angle is narrow. It cause the robot moves back to same path. In the other hand, the time value is less, the robot should move out of the line or possible to move parallel the lines with do not detect the lines



---

## Activity 8 : Robot moves along the black line

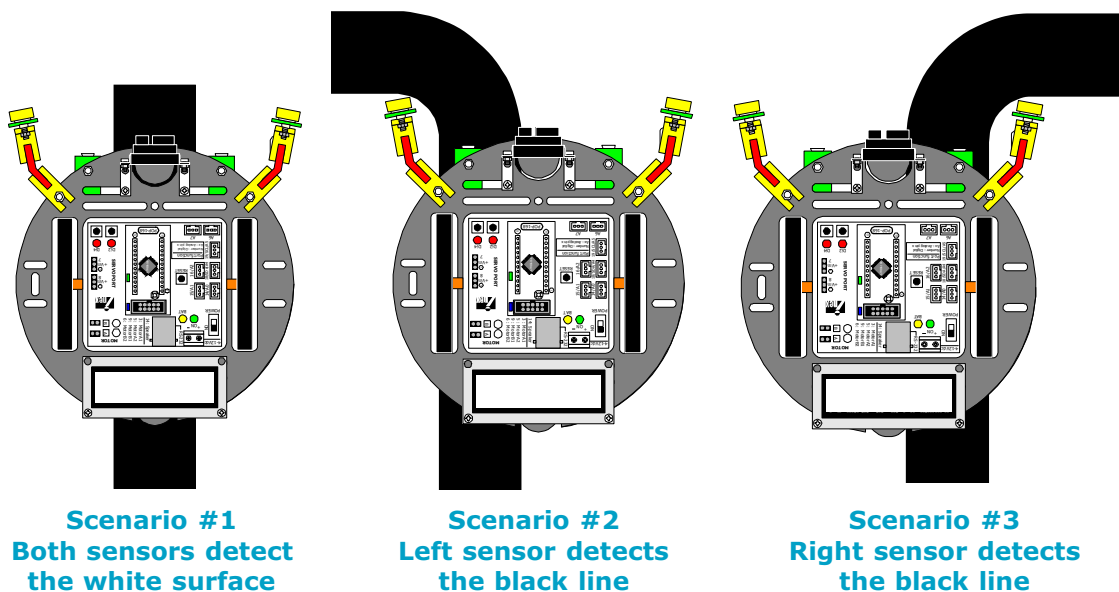
---

The robot moving along the line can be in 3 different scenarios.

**(1) Both sensors read values that are white** : The robot will move forward. Thus, this program is written so that the robot moves forward normally.

**(2) The left sensor detects the black line** : This occurs when the robot is slightly turned to the right. Thus, the program is written for the robot to move back left to resume its normal path.

**(3) The right sensor detects the black line** : This occurs when the robot is slightly turned to the left. Thus, the program is written for the robot to move back to the right to resume its normal path.



From all scenarios,, you can make the C program as follows in the listing A8-1

A8.1 Open the Arduino IDE and create the sketch code from Listing A8-1

A8.2 Set the POP-BOT into Program mode. Upload the sketch to the robot.

A8.3 Disconnect the download cable.

---

---

```

/*****
* POP-BOT V1.0
* Filename : SimpleLineTracking.pde
* POP-BOT tracks the black line
*****/
int Ref=500;
int Left,Right;
void setup(){
  pinMode(3,OUTPUT);          // Motor A1
  pinMode(5,OUTPUT);          // Motor A2
  pinMode(6,OUTPUT);          // Motor B2
  pinMode(9,OUTPUT);          // Motor B1
}
void loop(){
  Left = analogRead(7);        // Read value from left sensor
  Right = analogRead(6);       // Read value from right sensor
  if (Left>Ref && Right>Ref){   // Both sensors detect white surface
    Forward(150);
  }
  else if (Left<Ref) {         // Left sensor detects black line
    Spin_Left(250);
  }
  else if (Right<Ref){         // Rightt sensor detects black line
    Spin_Right(250);
  }
}

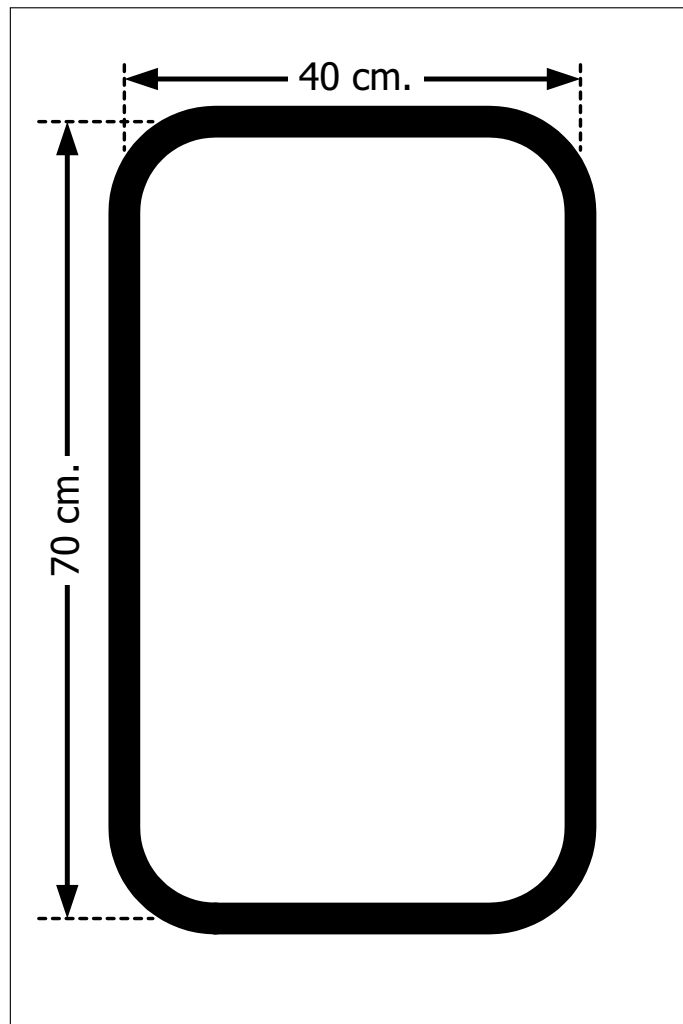
void Forward(int speed){
  analogWrite(3,speed);
  digitalWrite(5,LOW);
  analogWrite(6,speed);
  digitalWrite(9,LOW);
}
void Spin_Left(int speed){
  analogWrite(5,speed);
  digitalWrite(3,LOW);
  analogWrite(6,speed);
  digitalWrite(9,LOW);
}
void Spin_Right(int speed){
  analogWrite(3,speed);
  digitalWrite(5,LOW);
  analogWrite(9,speed);
  digitalWrite(6,LOW);
}

```

---

**Listing A8-1 : SimpleLineTracking.pde file; the Arduino sketch file for POP-BOT moves along the black line**

A8.4 Make the simple black line field following the illustration below. The white surface area is 90 x 60 cm. and black line width is 1 inches (2.5 cm.)



A8.5 Place the POP-BOT on the Black line field. Turn on the robot. Observe the robot movement.

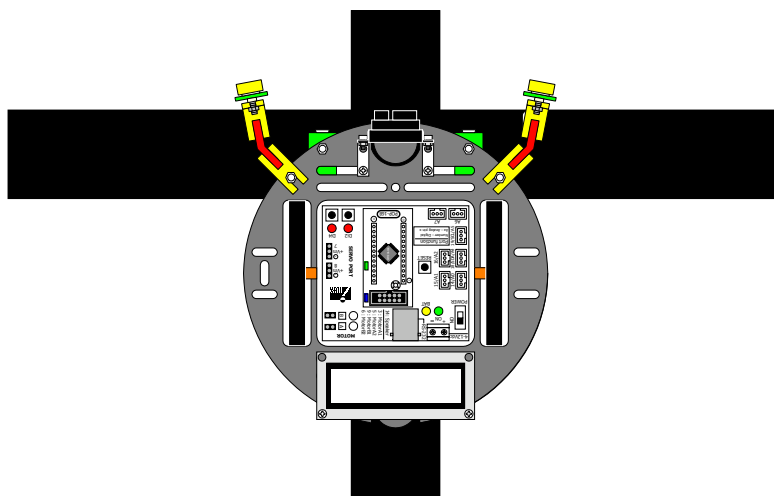
*The POP-BOT will move along the black line. It is possible that the robot moves out of the line. You can improve the precision by editing the program with adjusting the sensor reference value and adjust to the position of both infrared reflector sensors*



## Activity 9 : Line crossing detection

From the activity 8, you can improve the POP-BOT robot so that it moves along the black line and detects the junction or line with the same 2 sensors. All you have to do is to edit your program code.

When the robot moves to the black line T junction , both sensors will detect the black line. You must add the program for supporting this scenario. The improved C program is shown in the Listing A9-1.



```

/*****
* POP-BOT V1.0
* Filename : CrossingLineDetect.pde
* POP-BOT tracks the black line and beep when detect the crossing line
*****/
int Ref=700;
int Left,Right;
int Cnt=0,j;
void setup(){
  pinMode(3,OUTPUT);           // Motor A1
  pinMode(5,OUTPUT);           // Motor A2
  pinMode(6,OUTPUT);           // Motor B2
  pinMode(9,OUTPUT);           // Motor B1
  pinMode(14,OUTPUT);          // PIEZO Speaker
}
void loop(){
  Left = analogRead(7);        // Read value from left sensor
  Right = analogRead(6);       // Read Value from right sensor
  if (Left>Ref && Right>Ref){   // Both sensors detect the white surface
    Forward(150);
  }
  else if (Left<Ref && Right<Ref){ // Both sensors detect the black line.
    // It's mean crossing line.
    Cnt++;
    Motor_Stop();
    for (j=0;j<Cnt;j++){

```

```

        Beep();
        delay(100);
    }
    Forward(150);
    delay(100);
}
else if (Left<Ref) {                // Left sensor detects the black line
    Spin_Left(255);
}
else if (Right<Ref){                // Right sensor detects the black line
    Spin_Right(255);
}
}
void Beep(){                        // Beep routine
    int i;
    for (i=0;i<600;i++){
        digitalWrite(14,HIGH);
        delayMicroseconds(150);
        digitalWrite(14,LOW);
        delayMicroseconds(150);
    }
}
void sound(int freq ,int duration){
    unsigned long us;
    int duration_,i;
    us=(1000000/(freq*2));
    duration_ = (duration/(us*2));
    for (i=0;i<duration_;i++){
        digitalWrite(14,HIGH);
        delayMicroseconds(us);
        digitalWrite(14,LOW);
        delayMicroseconds(us);
    }
}
void Forward(int speed){
    analogWrite(3,speed);
    digitalWrite(5,LOW);
    analogWrite(6,speed);
    digitalWrite(9,LOW);
}
void Motor_Stop(){
    digitalWrite(3,LOW);
    digitalWrite(5,LOW);
    digitalWrite(6,LOW);
    digitalWrite(9,LOW);
}
void Spin_Left(int speed){
    analogWrite(5,speed);
    digitalWrite(3,LOW);
    analogWrite(6,speed);
    digitalWrite(9,LOW);
}
void Spin_Right(int speed){
    analogWrite(3,speed);
    digitalWrite(5,LOW);
    analogWrite(9,speed);
    digitalWrite(6,LOW);
}
}

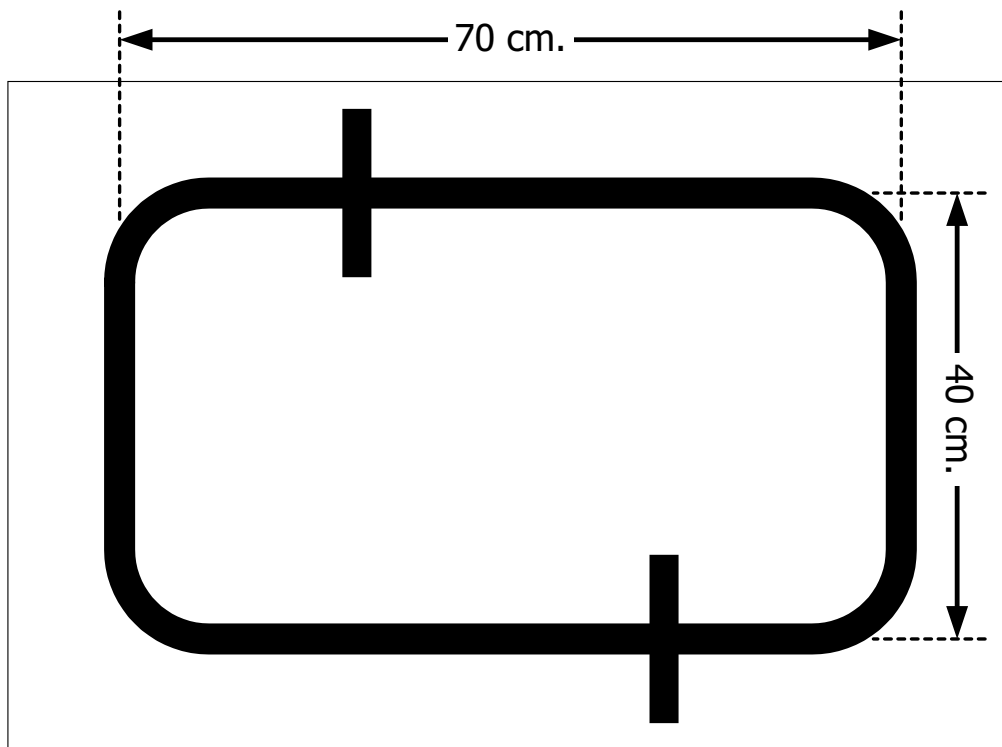
```

---

**Listing A9-1 : CrossingLineDetect.pde file; the Arduino sketch file for POP-BOT moves along the black line and detects the crossing line**

---

A9.1 Improve the simple black line field from Activity 8. Add some cross lines. Add as many junctions as you like. However, make sure that they are at least 2 robots width apart.



A9.2 Open the Arduino IDE and create the sketch code from Listing A9-1.

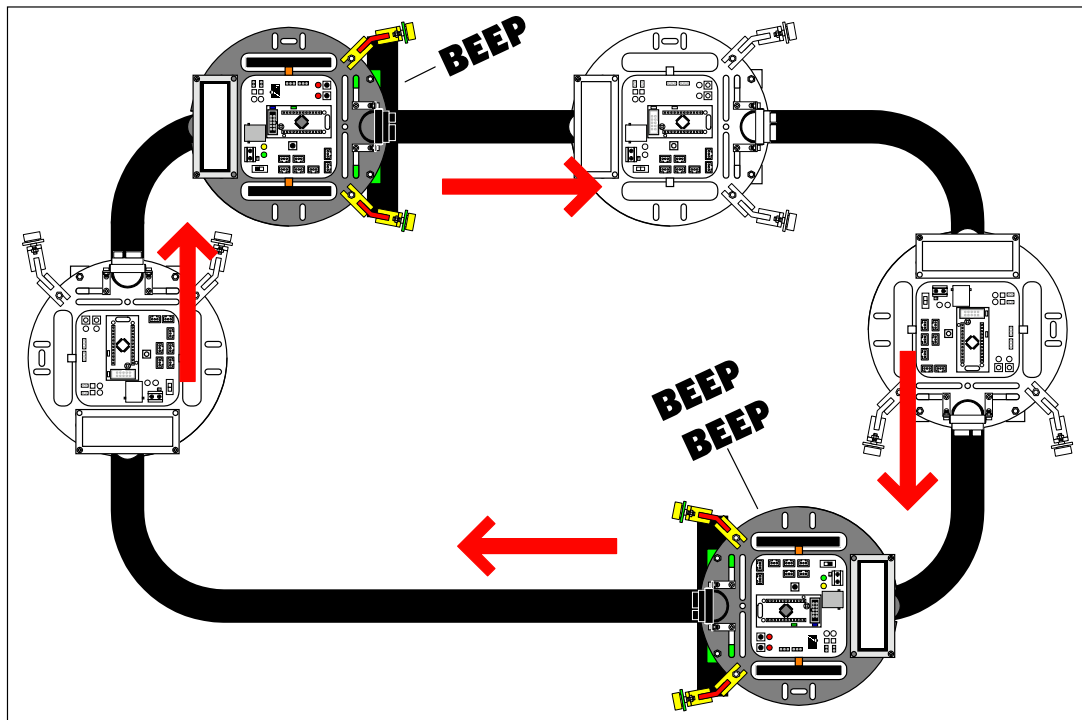
A9.2 Set the POP-BOT into Program mode. Upload the sketch to the robot.

A9.3 Disconnect the download cable.



A9.3 Place the robot on the field. Turn on power. Observe the robot movement.

*The Robot will move along the black line. When the robot detects the junction, it will brake and beep once. When it finds the second junction, the robot will drive beep twice and this will increase for the subsequent junctions*



**Note :** In the motor brake operation, the robot will stop and lock the motor's shaft immediately. But sometimes, this is not enough. You must program the robot to move backwards for a short time. This will cause the robot to stop at its position.



## Activity 10 : POP-BOT with 90 degree turning line tracking

---

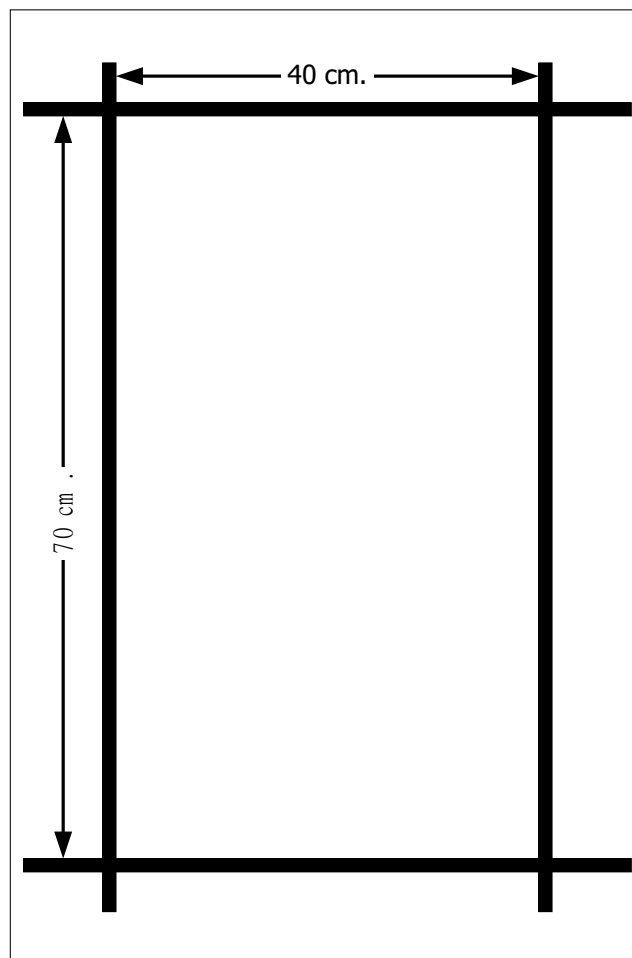
This activity features about 90 degree turning when robot detects the junction or crossing point. This technique is very important in Robotic challenges. Many line tracking challenges prepare many crossing lines or junctions. Robot must detect and moves precisely enough to maintain its movement stability.

A10.1 Open the Arduino IDE and create the sketch code from Listing A10-1

A10.2 Set the POP-BOT into Program mode. Upload the sketch to the robot.

A10.3 Disconnect the download cable.

A10.4 Make the border field following the illustration below. The white surface area is 90 x 60 cm. and black line width is 1 inches (2.5 cm.).



---

```

/*****
* POP-BOT V1.0
* Filename : RightTurnLineTracking.pde
* POP-BOT move following the line and turns right 90° when detect the crossing line
*****/
int Ref=700;
int Left,Right;
void setup(){
  pinMode(3,OUTPUT);          // Motor A1
  pinMode(5,OUTPUT);          // Motor A2
  pinMode(6,OUTPUT);          // Motor B2
  pinMode(9,OUTPUT);          // Motor B1
  pinMode(14,OUTPUT);         // PIEZO Speaker
}
void loop(){
  Left = analogRead(7);        // Read value from the left ZX-03 sensor
  Right = analogRead(6);       // Read value from the right ZX-03 sensor
  if ((Left<Ref) && (Right<Ref)){ // Detect the crossing line
    Right90();
  }
  else if ((Left>Ref) && (Right>Ref)){ // Over the line
    Forward(150);
  }
  else if (Left<Ref) {          // Only the left sensor detects the black line
    Spin_Left(150);
  }
  else if (Right<Ref){          // Only the right sensor detects the black line
    Spin_Right(150);
  }
}
/*Turn right 90 degree function */
void Right90(){
  Forward(150);
  delay(50);
  Spin_Right(200);
  delay(100);
  while(analogRead(6)>Ref);
  delay(50);
}
/*Movement function*/
void Forward(int speed){
  analogWrite(3,speed);
  digitalWrite(5,LOW);
  analogWrite(6,speed);
  digitalWrite(9,LOW);
}
void Spin_Left(int speed){
  analogWrite(5,speed);
  digitalWrite(3,LOW);
  analogWrite(6,speed);
  digitalWrite(9,LOW);
}
void Spin_Right(int speed){
  analogWrite(3,speed);
  digitalWrite(5,LOW);
  analogWrite(9,speed);
  digitalWrite(6,LOW);
}

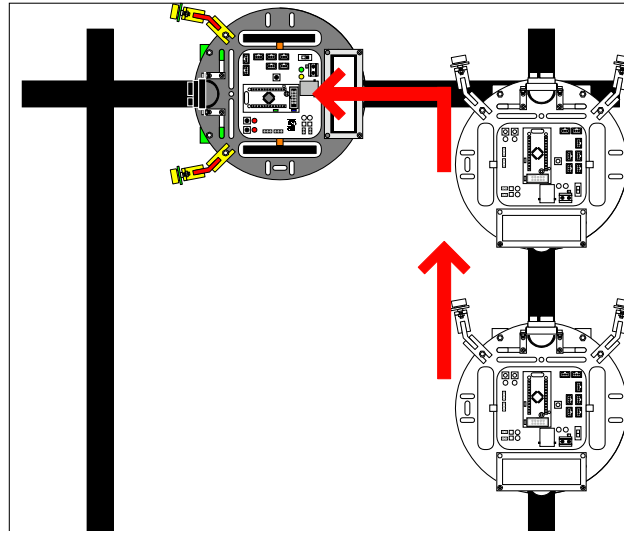
```

---

**Listing A10-1 : CrossingLineDetect.pde file; the Arduino sketch file for POP-BOT moves along the black line and detects the crossing line**

A10.5 Place the POP-BOT over the line. Turn on and observe the robot movement.

*POP-BOT moves along the line. Every time robot detects the crossing line, it turn right with 90 degrees angle and continues to follow the line.*



*The most important factor of this activity is **Right90** function. It is C/C++ function for Arduino. We can describe the function operation as follows :*

1. After robot's sensor detect the junction, POP-BOT must move forward 0.05 second for setting the robot's position at the centre of crossing line.
2. Spin right and delay 0.1 second
3. Loop to read the right sensor value and return until detect the black line.
4. Delay 0.05 second before back to main loop.

The source code of this function is shown below.

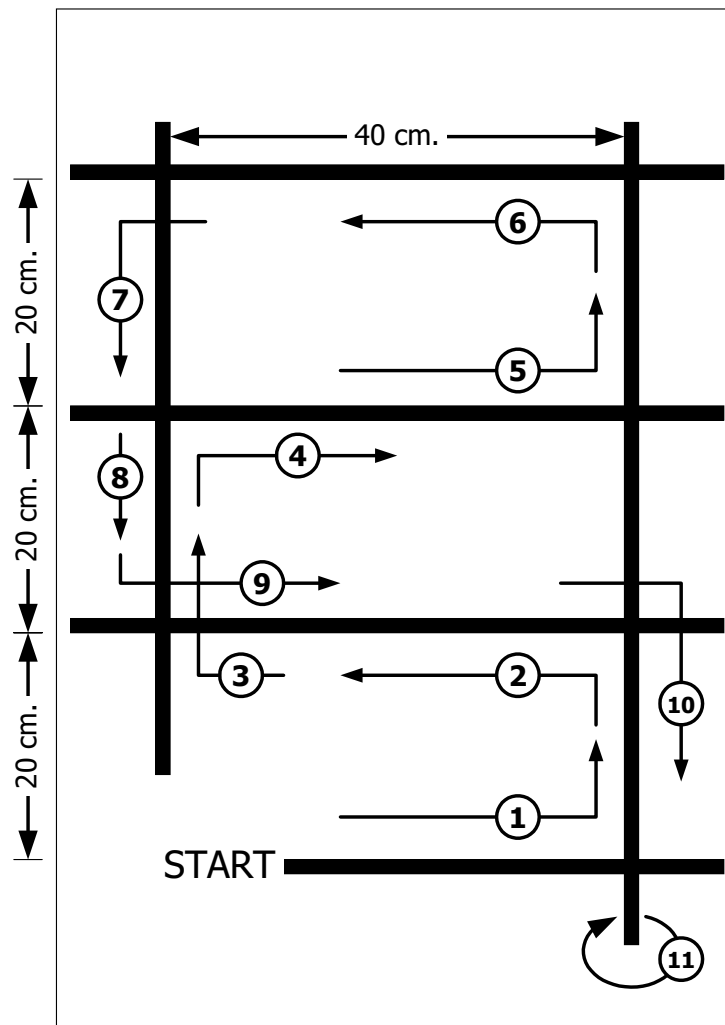
```
/*Turn right 90 degree function */
void Right90(){
    Forward(150);
    delay(50);
    Spin_Right(200);
    delay(100);
    while(analogRead(6)>Ref);
    delay(50);
}
```



## Activity 11 : Multi-crossing line mission

This activity is taken from many popular line tracking mission in many robotic games. Many crossing line are included the field. The robot must move following the line and detect every crossing point or junction and make the decision to turn left or right or forward or backward.

With the example code in Activity 8 to 10, you can combine all to make the complete code for solving the multi-crossing line mission. The example field and movement path are shown below.



A11.1 Open the Arduino IDE and create the sketch code from Listing A11-1

A11.2 Set the POP-BOT into Program mode. Upload the sketch to the robot.

A11.3 Disconnect the download cable.

---

```

/*****
* POP-BOT V1.0
* Filename : MultiCrossingLineDetect.pde
* POP-BOT move following the line and check the crossing line to do complex movement
*****/
int Ref=700;
int Left,Right;
int Cnt=0;
void setup(){
  pinMode(3,OUTPUT);          // Motor A1
  pinMode(5,OUTPUT);          // Motor A2
  pinMode(6,OUTPUT);          // Motor B2
  pinMode(9,OUTPUT);          // Motor B1
  pinMode(14,OUTPUT);         // PIEZO Speaker
}
void loop(){
  while(Cnt<11){
    Left = analogRead(7);      // Read value from the left ZX-03 sensor
    Right = analogRead(6);     // Read value from the right ZX-03 sensor
    if ((Left<Ref) && (Right<Ref)){ // Found crossing point
      Cross();
    }
    else if ((Left>Ref) && (Right>Ref)){ // Move across the line a short while
      Forward(150);
    }
    else if (Left<Ref) { // Only left sensor detects the black
line      Spin_Left(150); // Spin left a short while
    }
    else if (Right<Ref){ // Only right sensor detects the black
line      Spin_Right(150); // Spin right a short while
    }
  }
  Forward(200);
  delay(200);
  Spin_Left(200); // Turn around
  delay(2000);
  Motor_Stop();
  Beep();
  while(1);
}
void Cross(){
  Cnt++;
  if (Cnt==11){
    Motor_Stop();
  }
  else if (Cnt==8){ // Check for Forward
    Forward(200);
    delay(300);
  }
  else if(Cnt==3 || Cnt==4 || Cnt==10 ){ // Check for Turn right 90 degree
    Right90();
  }
  else{ // else Turn Left
    Left90();
  }
}

```

---

```

/*Turn 90 degree function */
void Right90(){
    Forward(150);
    delay(50);
    Spin_Right(200);
    delay(100);
    while(analogRead(6)>Ref);
    delay(50);
}
/*Turn left 90 degree function */
void Left90(){
    Forward(150);
    delay(50);
    Spin_Left(200);
    delay(100);
    while(analogRead(7)>Ref);
    delay(50);
}
void Beep(){
    int i;
    for (i=0;i<600;i++){
        digitalWrite(14,HIGH);
        delayMicroseconds(150);
        digitalWrite(14,LOW);
        delayMicroseconds(150);
    }
}
void Forward(int speed){
    analogWrite(3,speed);
    digitalWrite(5,LOW);
    analogWrite(6,speed);
    digitalWrite(9,LOW);
}
void Spin_Left(int speed){
    analogWrite(5,speed);
    digitalWrite(3,LOW);
    analogWrite(6,speed);
    digitalWrite(9,LOW);
}
void Spin_Right(int speed){
    analogWrite(3,speed);
    digitalWrite(5,LOW);
    analogWrite(9,speed);
    digitalWrite(6,LOW);
}
void Motor_Stop(){
    digitalWrite(3,LOW);
    digitalWrite(5,LOW);
    digitalWrite(6,LOW);
    digitalWrite(9,LOW);
}

```

---

**Listing A11-1 : MultiCrossingLineDetect.pde file; the Arduino sketch file for POP-BOT moves along the black line and detects the crossing line to solving the Multi-crossing line mission**

---

A11.4 Place the POP-BOT at the START point (see the field illustration). Turn on and observe the robot movement.

*POP-BOT moves along the line following the movement path that show in the field illustration. POP-BOT will do 3 scenarios when a junction is detected :*

*Scenario 1 : Move forward after detect the junction*

*Scenario 2 : Turn left after detect the junction*

*Scenario 3 : Turn right after detect the junction*

*From the movement path; it has Scenario 1 only one position at 8th junction, Scenario 2 has 3 positions at 3rd-4th-10th junction. POP-BOT will do Scenario 3 for the rest junction.*

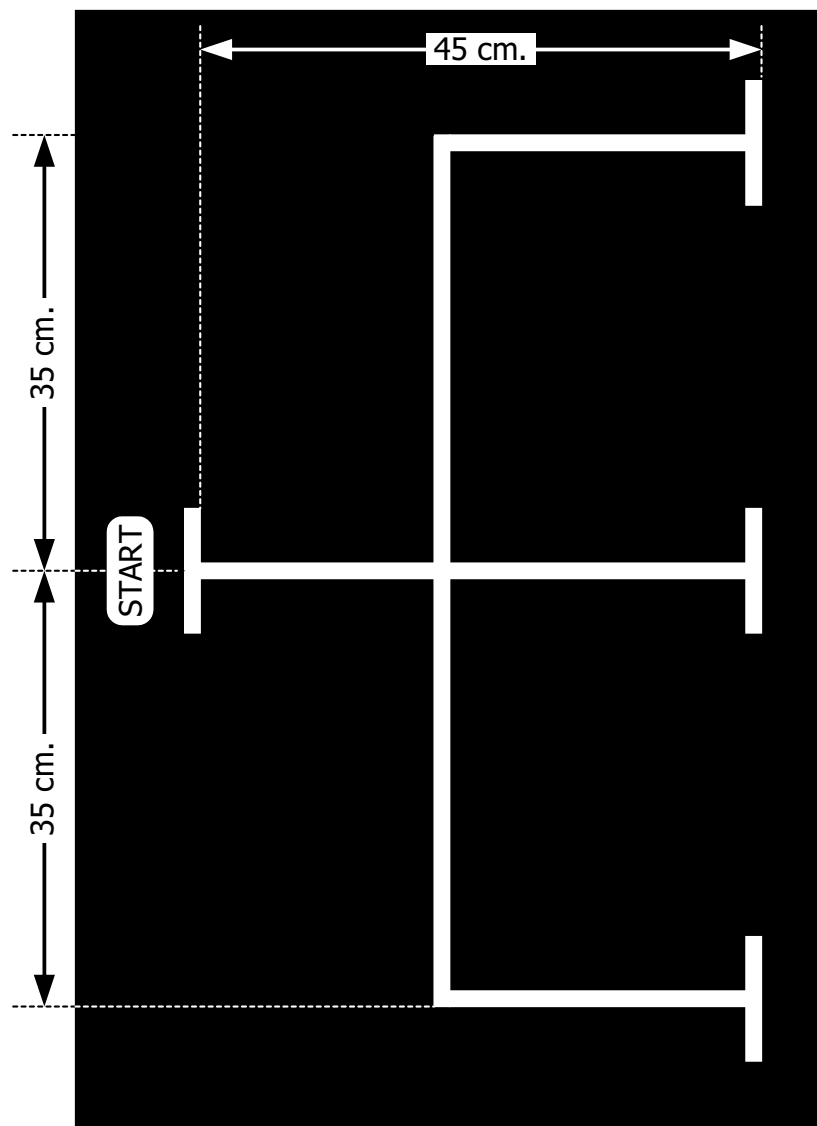
*After POP-BOT moves pass the last junction (11th), POP-BOT will turn around 2 seconds and stop.*





## Activity 12 : White line challenges

This activity is taken from the mission in robotic games. The difference from Activity 11 are line color and movement path. This activity change the line color as white on the black surface. See the illustration of field below. The mission is track the line from START to 3 ending lines or destinations. You can place a balloon at each end of line. Robot must pierce the balloon. Competitor who can pierce all balloons fastest is the winner.



A12.1 Open the Arduino IDE and create the sketch code from Listing A12-1

A12.2 Set the POP-BOT into Program mode. Upload the sketch to the robot.

A12.3 Disconnect the download cable.

---

```

/*****
* POP-BOT V1.0
* Filename : WhiteLineDetect.pde
* POP-BOT move following the line and check the junction to do complex movement
* for piercing the ballon at the 3 destinations
*****/
int Ref=400;
int Left,Right;
int Cnt=0;

void setup(){
  pinMode(3,OUTPUT);          // Motor A1
  pinMode(5,OUTPUT);          // Motor A2
  pinMode(6,OUTPUT);          // Motor B2
  pinMode(9,OUTPUT);          // Motor B1
  pinMode(14,OUTPUT);         // PIEZO Speaker
}

void loop(){
  while(Cnt<12){
    Left = analogRead(7);      // Read value from the left ZX-03 sensor
    Right = analogRead(6);     // Read value from the right ZX-03 sensor
    if ((Left<Ref) && (Right<Ref)){ // Detect the black crossing line
      Cross();
    }
    else if ((Left>Ref) && (Right>Ref)){ // Detect the white line
      Forward(150);
    }
    else if (Left<Ref) {        // Only the left sensor detects the line
      Spin_Right(150);         // Turn right
    }
    else if (Right<Ref){        // Only the right sensor detects the line
      Spin_Left(150);          // Turn left
    }
  }
  while(1);                    // Endless loop
}

void Cross(){
  Cnt++;
  if (Cnt==12){
    Motor_Stop();
  }
  else if (Cnt==2 || Cnt==10 ){ // Check for turning right 90 deg.
    Right90();
  }
  else if (Cnt==3 || Cnt==6 || Cnt==9 ){ // Check for turning left 180 deg.
    Left180();
  }
  else{                          // else turn left 90 deg.
    Left90();
  }
}

```

---

```

/*Turn right 90 degree function */
void Right90(){
    Forward(150);
    delay(50);
    Spin_Right(200);
    delay(100);
    while(analogRead(6)<Ref);
    delay(50);
}

/*Turn left 90 degree function */
void Left90(){
    Forward(150);
    delay(50);
    Spin_Left(200);
    delay(100);
    while(analogRead(7)<Ref);
    delay(50);
}

/*Turn left 180 degree function */
void Left180(){
    Spin_Left(200);
    delay(300);
    while(analogRead(7)<Ref);
    delay(50);
}

/*Movement function*/
void Forward(int speed){
    analogWrite(3,speed);
    digitalWrite(5,LOW);
    analogWrite(6,speed);
    digitalWrite(9,LOW);
}
void Spin_Left(int speed){
    analogWrite(5,speed);
    digitalWrite(3,LOW);
    analogWrite(6,speed);
    digitalWrite(9,LOW);
}
void Spin_Right(int speed){
    analogWrite(3,speed);
    digitalWrite(5,LOW);
    analogWrite(9,speed);
    digitalWrite(6,LOW);
}
void Motor_Stop(){
    digitalWrite(3,LOW);
    digitalWrite(5,LOW);
    digitalWrite(6,LOW);
    digitalWrite(9,LOW);
}

```

---

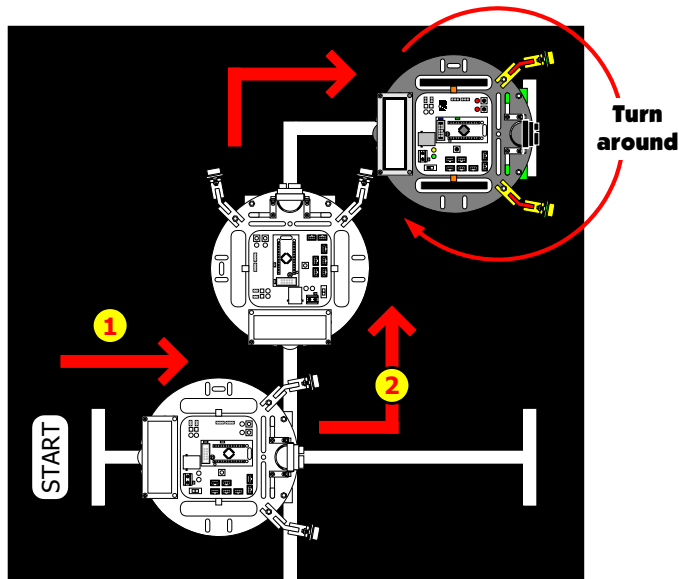
**Listing A12-1 :** WhiteLineDetect.pde file; the Arduino sketch file for POP-BOT moves along the white line and detects junctions to piercing the ballon at the destinations

---

A12.4 Place the POP-BOT at the START point (see the field illustration). Turn on and observe the robot movement.

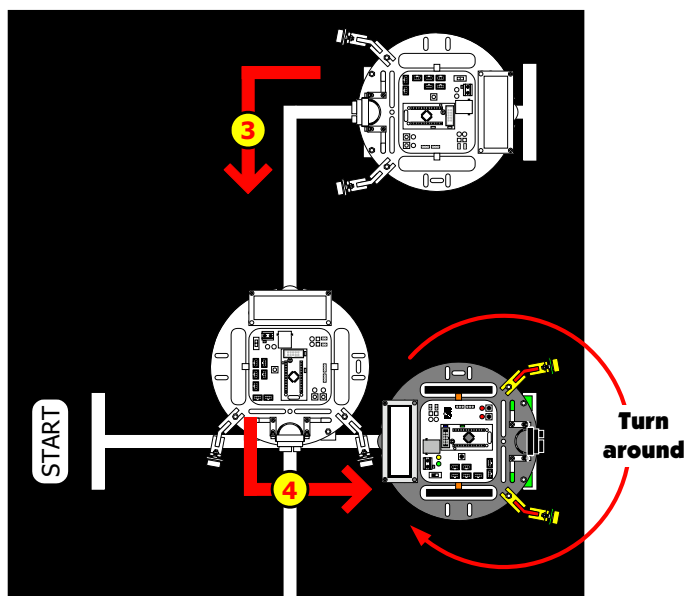
*Step 1 : POP-BOT moves along the line from START point*

*Step 2 : POP-BOT detects the first junction and turn left to move to the first destination at the left side of field.*



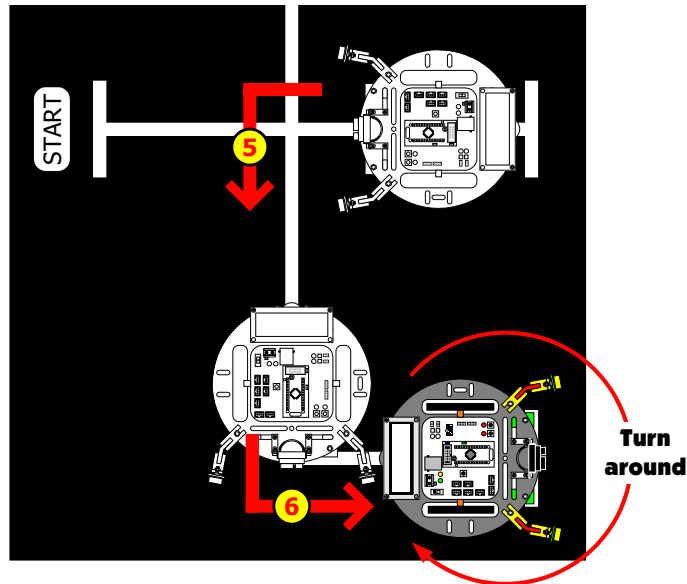
*Step 3 : POP-BOT moves back from the first destination pass the junction again.*

*Step 4 : POP-BOT detects the junction second time and turn left to move to the second destination at the middle of field.*



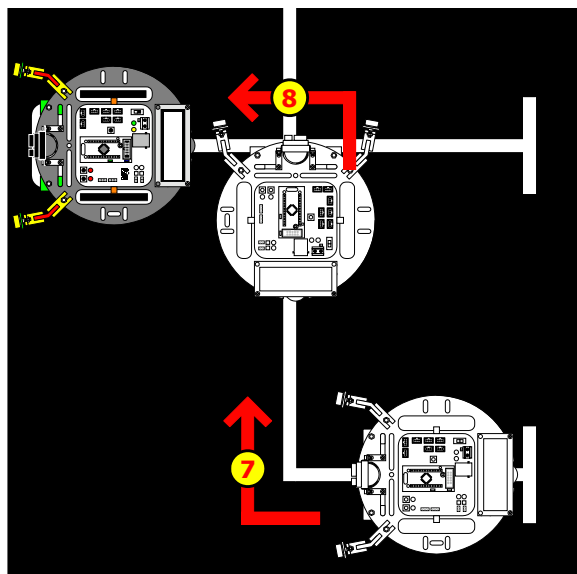
Step 5 : POP-BOT moves back from the second destination pass the junction again.

Step 6 : POP-BOT detects the junction third time and turn left to moves to the last destination at the right side of field.



Step 7 : POP-BOT moves back from the last destination pass the junction again.

Step 8 : POP-BOT detects the junction last time and moves forward to go back the START point for finishing the mission.





## 8 : POP-BOT Edging detection

---

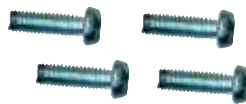
In Chapter 7, we used the infrared reflector sensors to detect the lines. Do you know these sensor able to do more ? This chapter will show an activity about using infrared reflector sensors for surface detection to control the robot move on the table and not fall off the edge of the table !

With a simple change of the position of the sensors and a simple program, you can adapt the POP-BOT to edge detection. Start assembling the mechanical parts place the sensors in the right position and create the Arduino sketch for the table surface testing.

### 8.1 Additional part list



**12-hole Straight Joiner x 2**



**3x10mm. screw x 4**



**3mm. plastic spacer x 2**



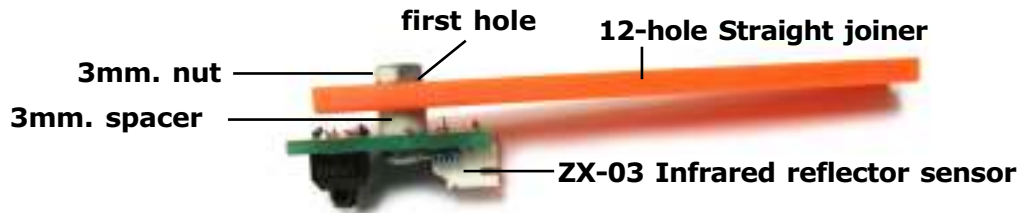
**3mm. nut x 4**

### 8.2 Modify procedure

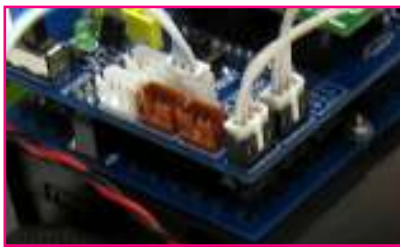
(1) Remove all Touch sensors and Line tracking sensors from the POP-BOT chasis. Now we have the simplest form of the POP-BOT mobile robot.



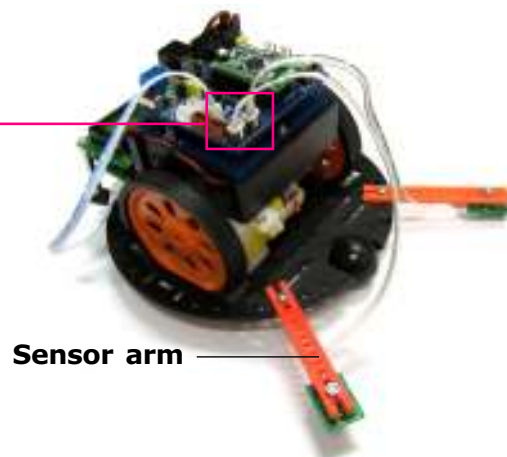
(2) Attach the ZX-03 Infrared reflector sensor with 12-hole Straight joiner at the first hole by using 3x10mm. screw, 3mm. plastic spcaer and 3mm. nut. following the photo is shown below. Do 2 sets of these.



(3) Fix both sensor structures from step (2) at the left and right hand side of front of POP-BOT chasis by using 3x10mm. screws and 3mm. nuts following the photo below. Next, connect the left sensor cable to A7 port and right sensor to A6 port. You can adjust the sensor arm position to suite your conditions.



**Photo shows the sensor connections on POP-BOT controller board**



**Sensor arm**



## Activity 13 : POP-BOT Edge detection

This activity demonstrates this interesting behavior; POP-BOT moves on the table and never drop off from the table. By using 2 of infrared reflectors that are fixed at the front of robot, you can detect the outer area of the table. It's similar to line tracking code. If sensors detect the surface, they will give a higher data. Once the sensors are out of the table, there is no infrared ray reflected from the surface to sensor and thus the return value from sensor will be low or near zero.

You can use this behavior to make the code to control the POP-BOT to move on the table and detect the table's edge.

A13.1 Open the Arduino IDE and create the sketch code from Listing A13-1.

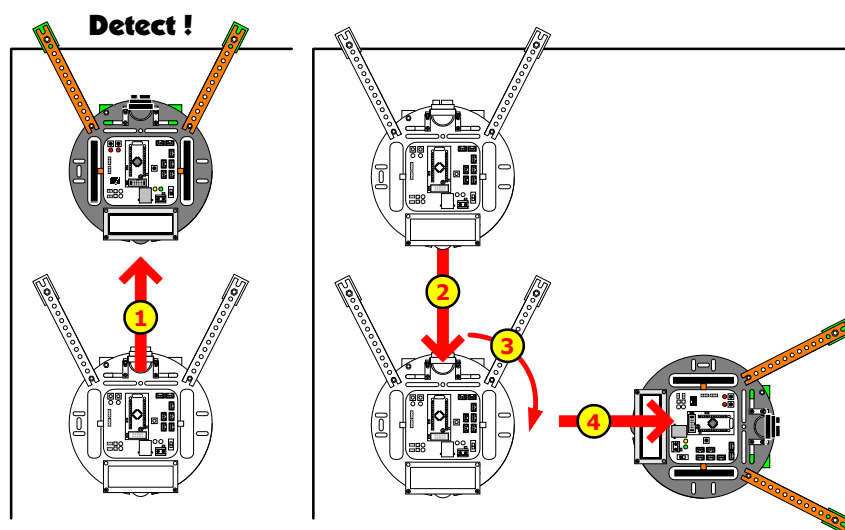
A13.2 Set the POP-BOT into Program mode. Upload the sketch to the robot.

A13.3 Disconnect the download cable.

A13.4 Place the POP-BOT on the table. You must remove all objects from the table. Turn on POP-BOT and observe the robot's movement.

*POP-BOT moves forward until the sensor out from the table's edge. POP-BOT will change the movement direction following these scenarios:*

*1. Both sensors are out from table's edge : POP-BOT moves backward and spin right then moves forward again.*



---

```

/*****
* POP-BOT V1.0
* Filename : EdgeDetect.pde
*****/
int Ref=300;
int Left,Right;
void setup(){
    pinMode(3,OUTPUT);          // Motor A1
    pinMode(5,OUTPUT);          // Motor A2
    pinMode(6,OUTPUT);          // Motor B2
    pinMode(9,OUTPUT);          // Motor B1
}
void loop(){
    Left = analogRead(7);        // Read value from the left ZX-03 sensor
    Right = analogRead(6);       // Read value from the right ZX-03 sensor
    if (Left>Ref && Right>Ref){   // Both sensors are on the table
        Forward(150);
    }
    else if (Left<Ref && Right<Ref){ // Both sensors out of the table
        Backward(150);
        delay(200);
        Spin_Right(150);
        delay(500);
    }
    else if (Left<Ref) {          // Only the left sensor outs of the table
        Backward(150);
        delay(300);
        Spin_Right(150);
        delay(400);
    }
    else if (Right<Ref){          // Only hte right sensor outs of the table
        Backward(150);
        delay(300);
        Spin_Left(150);
        delay(300);
    }
}

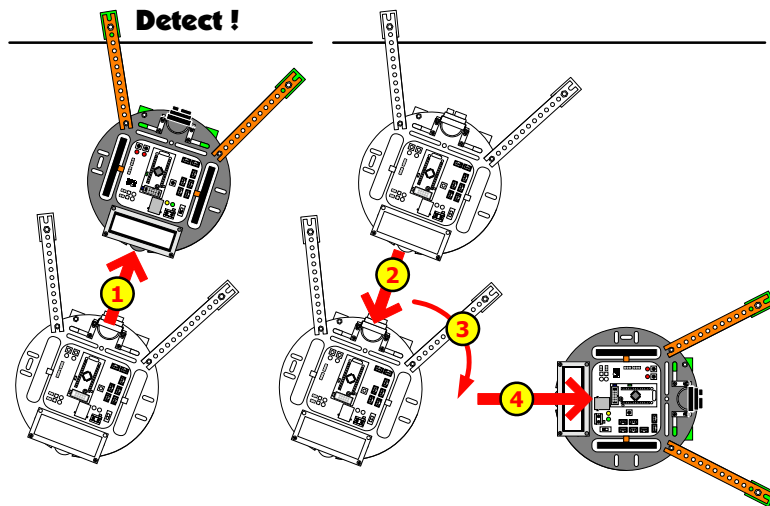
/*Movement function*/
void Forward(int speed){
    analogWrite(3,speed);
    digitalWrite(5,LOW);
    analogWrite(6,speed);
    digitalWrite(9,LOW);
}
void Backward(int speed){
    analogWrite(5,speed);
    digitalWrite(3,LOW);
    analogWrite(9,speed);
    digitalWrite(6,LOW);
}
void Spin_Left(int speed){
    analogWrite(5,speed);
    digitalWrite(3,LOW);
    analogWrite(6,speed);
    digitalWrite(9,LOW);
}
void Spin_Right(int speed){
    analogWrite(3,speed);
    digitalWrite(5,LOW);
    analogWrite(9,speed);
    digitalWrite(6,LOW);
}

```

---

**Listing A13-1 : EdgeDetect.pde file; the Arduino sketch file for POP-BOT detect and move on the table**

2. The left sensor is out from table's edge : POP-BOT moves backward and spin right then moves forward again.



3. The right sensor is out from table's edge : POP-BOT moves backward and spin left then moves forward again.

