



Chipsmall Limited consists of a professional team with an average of over 10 year of expertise in the distribution of electronic components. Based in Hongkong, we have already established firm and mutual-benefit business relationships with customers from,Europe,America and south Asia,supplying obsolete and hard-to-find components to meet their specific needs.

With the principle of "Quality Parts,Customers Priority,Honest Operation,and Considerate Service",our business mainly focus on the distribution of electronic components. Line cards we deal with include Microchip,ALPS,ROHM,Xilinx,Pulse,ON,Everlight and Freescale. Main products comprise IC,Modules,Potentiometer,IC Socket,Relay,Connector.Our parts cover such applications as commercial,industrial, and automotives areas.

We are looking forward to setting up business relationship with you and hope to provide you with the best service and solution. Let us make a better world for our industry!



Contact us

Tel: +86-755-8981 8866 Fax: +86-755-8427 6832

Email & Skype: info@chipsmall.com Web: www.chipsmall.com

Address: A1208, Overseas Decoration Building, #122 Zhenhua RD., Futian, Shenzhen, China





Basic Kit for Turtle 2WD SKU:ROB0118

Function Introduction

This Kit will teach you how to build a automatic obstacle - avoidance robot which is achieved on the platform of the Turtle Robot, based on ultrasonic sensor as distance measuring device, and combined with servo.

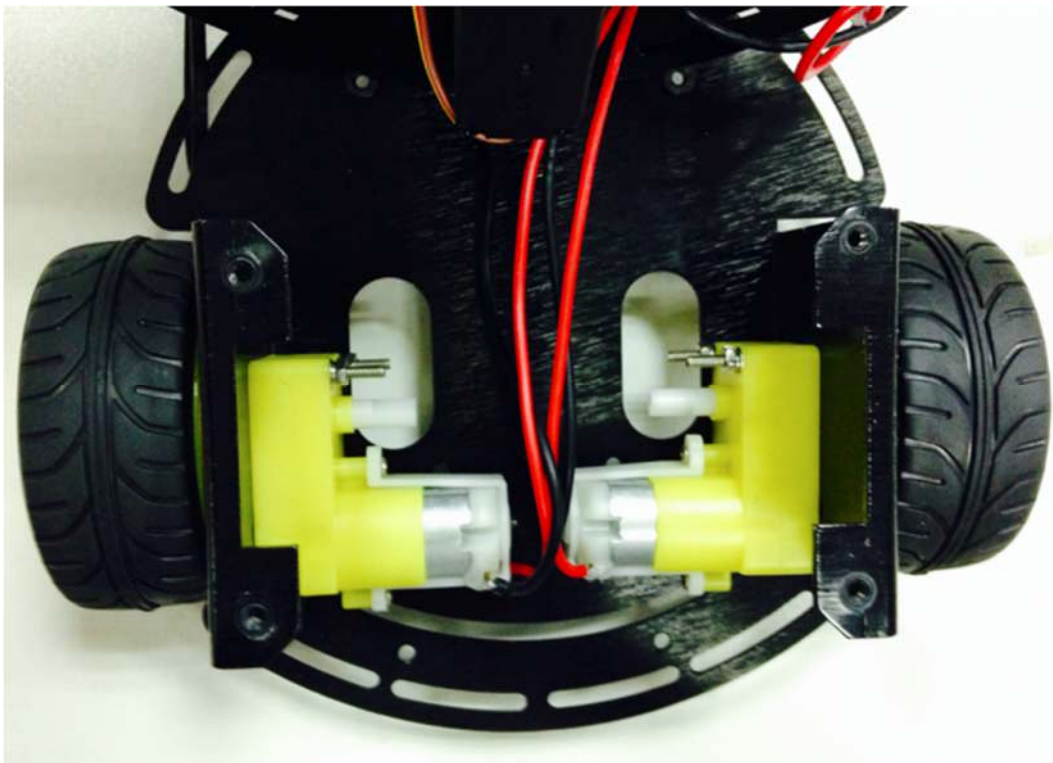
STEP 1: Assemble Robot

Refer to Instruction Manual

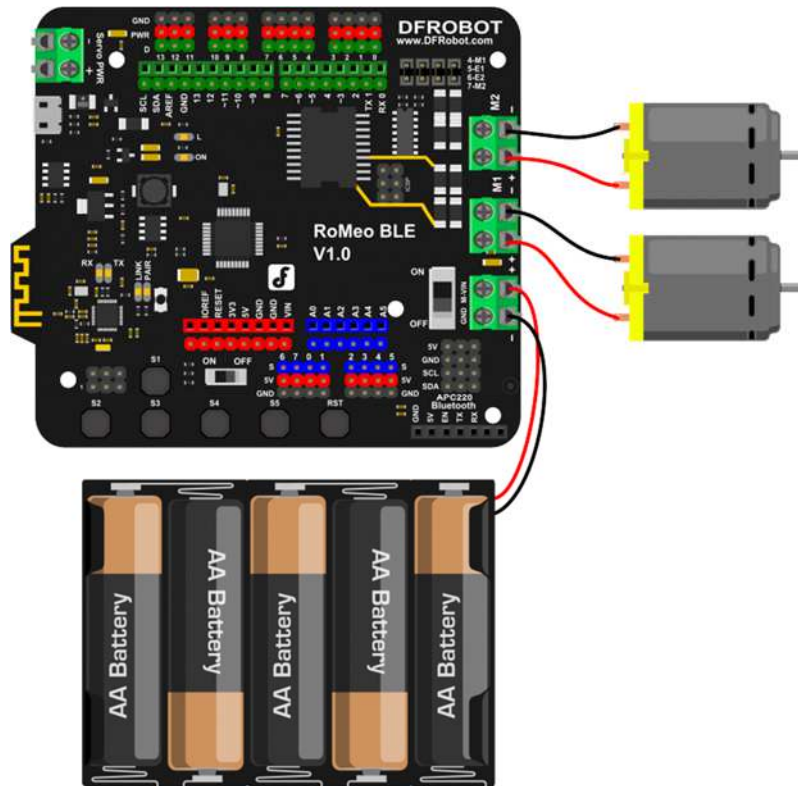
<http://www.dfrobot.com.cn/image/data/ROB0005/CN/ROB0005%20InstructionManual%20V1.1.pdf>

Precautions:

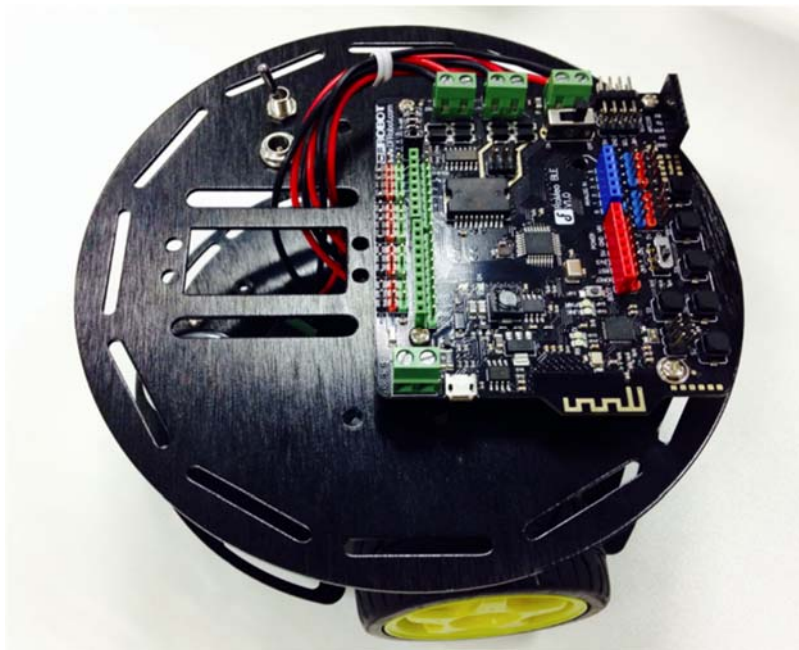
1. Instruction Manual says nothing about how to deal with motor wire. The next picture tells it.



2. Finished the robot chassis. Then following the connection diagram to wire the hardware.



Motor Connection



Physical map

STEP 2: Debug Motor

Download the Code

```
int speedPin_M1 = 5;    //M1 Speed Control
int speedPin_M2 = 6;    //M2 Speed Control
int directionPin_M1 = 4;    //M1 Direction Control
int directionPin_M2 = 7;    //M1 Direction Control

void setup() {

}

void loop() {
    carAdvance(100,100);
    delay(1000);
    carBack(100,100);
    delay(1000);
    carTurnLeft(250,250);
    delay(1000);
    carTurnRight(250,250);
    delay(1000);
}

void carStop() {          // Motor Stop
    digitalWrite(speedPin_M2,0);
    digitalWrite(directionPin_M1,LOW);
    digitalWrite(speedPin_M1,0);
    digitalWrite(directionPin_M2,LOW);
}

void carAdvance(int leftSpeed,int rightSpeed) {          //Move forward
    analogWrite (speedPin_M2,leftSpeed);                //PWM Speed Control
```

```
digitalWrite(directionPin_M1,HIGH);
analogWrite (speedPin_M1,rightSpeed);
digitalWrite(directionPin_M2,HIGH);
}

void carBack(int leftSpeed,int rightSpeed){           //Move backward
  analogWrite (speedPin_M2,leftSpeed);
  digitalWrite(directionPin_M1,LOW);
  analogWrite (speedPin_M1,rightSpeed);
  digitalWrite(directionPin_M2,LOW);
}

void carTurnRight(int leftSpeed,int rightSpeed){     //Turn Right
  analogWrite (speedPin_M2,leftSpeed);
  digitalWrite(directionPin_M1,LOW);
  analogWrite (speedPin_M1,rightSpeed);
  digitalWrite(directionPin_M2,HIGH);
}

void carTurnLeft(int leftSpeed,int rightSpeed){     //Turn Left
  analogWrite (speedPin_M2,leftSpeed);
  digitalWrite(directionPin_M1,HIGH);
  analogWrite (speedPin_M1,rightSpeed);
  digitalWrite(directionPin_M2,LOW);
}
```

STEP 3 : Install Upper Plate

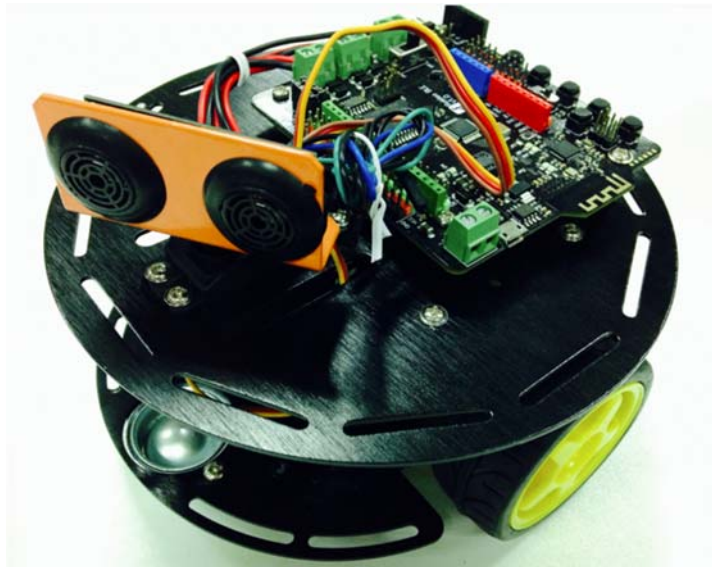
1. Prepare the Materials



2. Fixed Ultrasonic Sensor Position

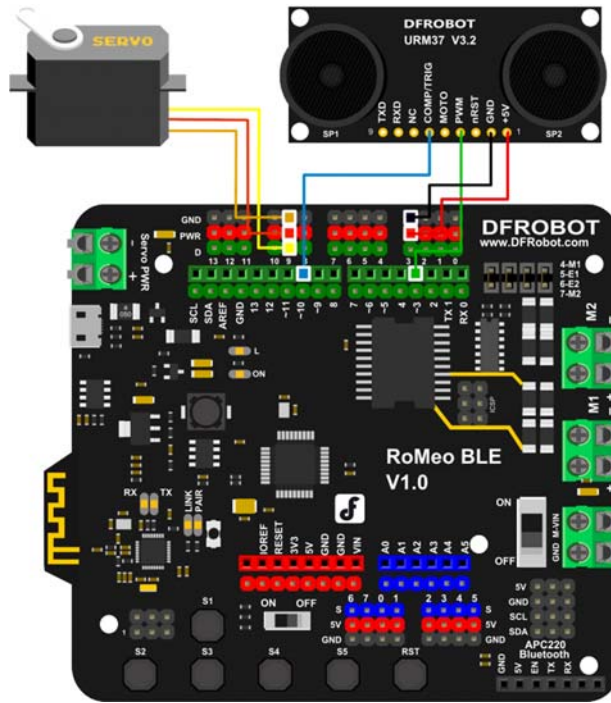
Please see the Installation Manual <http://www.dfrobot.com.cn/images/upload/File/20141030183325g7lofm.pdf>

3. Fixed Servo Position

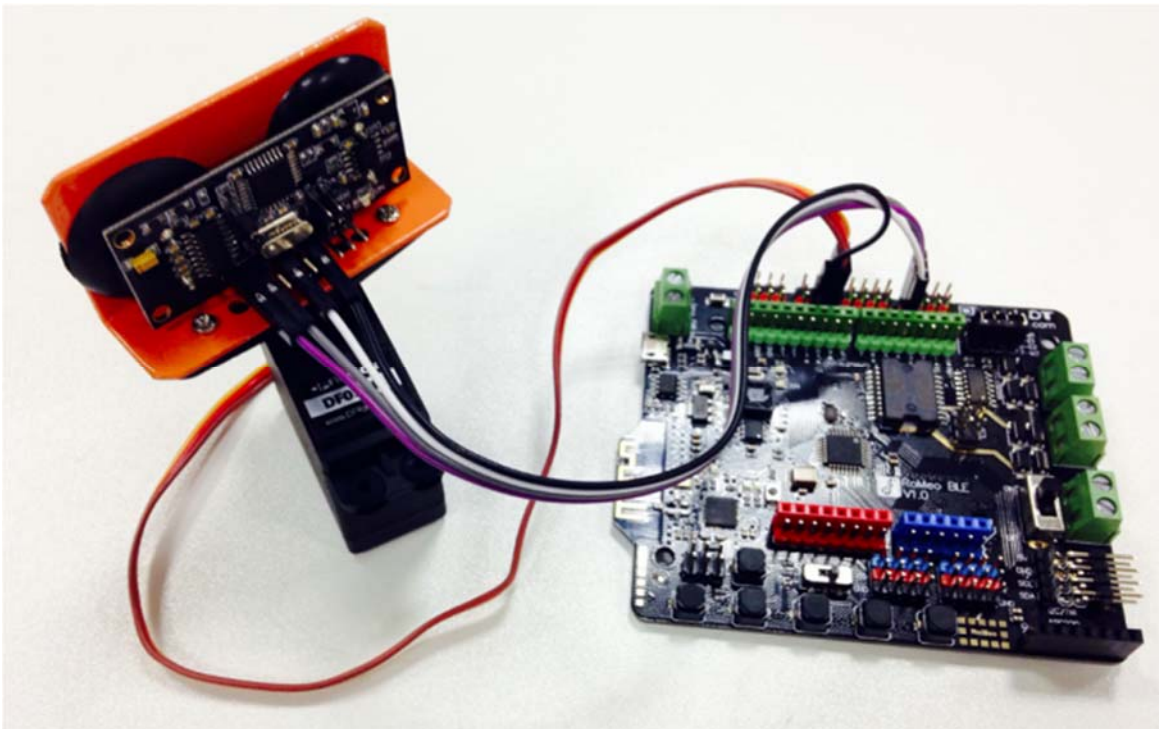


STEP4: Debug Ultrasonic Sensor and Servo

1. Hardware Connection



Ultrasonic Sensor and Servo Control



2. Download Code

Install the library firstly. **Metro libray** <http://www.dfrobot.com.cn/images/upload/File/20141031110246wu4065.rar>

```
#include <Servo.h>
#include <Metro.h>
Metro measureDistance = Metro(50);
Metro sweepServo = Metro(20);

unsigned long actualDistance = 0;

Servo myservo; // create servo object to control a servo
int pos = 60;
int sweepFlag = 1;

int URPWM = 3; // PWM Output 0-25000US, Every 50US represent 1cm
int URTRIG= 10; // PWM trigger pin
uint8_t EnPwmCmd[4]={0x44,0x02,0xbb,0x01}; // distance measure command

void setup(){ // Serial initialization
  myservo.attach(9);
  Serial.begin(9600); // Sets the baud rate to 9600
  SensorSetup();
}

void loop(){
  if(measureDistance.check() == 1){
    actualDistance = MeasureDistance();
    // Serial.println(actualDistance);
    // delay(100);
  }

  if(sweepServo.check() == 1){
    servoSweep();
  }
}
```



```

}

}

void SensorSetup() {
    pinMode(URTRIG, OUTPUT); // A low pull on pin COMP/TRIG
    digitalWrite(URTRIG, HIGH); // Set to HIGH
    pinMode(URPWM, INPUT); // Sending Enable PWM mode comm
and
    for(int i=0;i<4;i++){
        Serial.write(EnPwmCmd[i]);
    }
}

int MeasureDistance() { // a low pull on pin COMP/TRIG triggering a se
nsor reading
    digitalWrite(URTRIG, LOW);
    digitalWrite(URTRIG, HIGH); // reading Pin PWM will output
pulses
    unsigned long distance=pulseIn(URPWM,LOW);
    if(distance==50000) { // the reading is invalid.
        Serial.print("Invalid");
    }else{
        distance=distance/50; // every 50us low level stands for 1cm
    }
    return distance;
}

void servoSweep() {
    if(sweepFlag ) {
        if(pos>=60 && pos<=120) {
            pos=pos+1; // in steps of 1 degree
            myservo.write(pos); // tell servo to go to po
sition in variable 'pos'
        }
    }
}

```

```

        if(pos>119)  sweepFlag = false;           // assign the var
variable again
    }else {
        if(pos>=60 && pos<=120){
            pos=pos-1;
            myservo.write(pos);
        }
        if(pos<61)  sweepFlag = true;
    }
}

```

STEP 5: Debugging Robot

```

#include <Servo.h>
#include <Metro.h>
Metro measureDistance = Metro(50);
Metro sweepServo = Metro(20);

int speedPin_M1 = 5;    //M1 Speed Control
int speedPin_M2 = 6;    //M2 Speed Control
int directionPin_M1 = 4;    //M1 Direction Control
int directionPin_M2 = 7;    //M1 Direction Control
unsigned long actualDistance = 0;

Servo myservo; // create servo object to control a servo
int pos = 60;
int sweepFlag = 1;

int URPWM = 3; // PWM Output 0-25000US, Every 50US represent 1cm
int URTRIG= 10; // PWM trigger pin
uint8_t EnPwmCmd[4]={0x44,0x02,0xbb,0x01}; // distance measure command

void setup(){ // Serial initialization
    myservo.attach(9);
}

```

```

Serial.begin(9600); // Sets the baud rate to 9600
SensorSetup();
}

void loop(){

  if(measureDistance.check() == 1){
    actualDistance = MeasureDistance();
    // Serial.println(actualDistance);
    // delay(100);
  }

  if(sweepServo.check() == 1){
    servoSweep();
  }

  if(actualDistance <= 30){
    myservo.write(90);
    if(pos>=90){
//          carBack(100,100);
////          Serial.println("carBack");
//          delay(100);
          carTurnRight(150,150);
//          Serial.println("carTurnRight");
          delay(100);
    }else{
//          carBack(100,100);
////          Serial.println("carBack");
//          delay(100);
          carTurnLeft(150,150);
//          Serial.println("carTurnLeft");
          delay(100);
    }
  }else{

```

```

        carAdvance(70,70);
//        Serial.println("carAdvance");
        delay(100);
    }
//    carBack(150,150);
}

void SensorSetup() {
    pinMode(URTRIG, OUTPUT);           // A low pull on pin COMP/TRIG
    digitalWrite(URTRIG, HIGH);       // Set to HIGH
    pinMode(URPWM, INPUT);           // Sending Enable PWM mode comm
and
    for(int i=0;i<4;i++){
        Serial.write(EnPwmCmd[i]);
    }
}

int MeasureDistance(){ // a low pull on pin COMP/TRIG triggering a sensor r
eading
    digitalWrite(URTRIG, LOW);
    digitalWrite(URTRIG, HIGH);       // reading Pin PWM will output
pulses
    unsigned long distance=pulseIn(URPWM,LOW);
    if(distance==50000){ // the reading is invalid.
        Serial.print("Invalid");
    }else{
        distance=distance/50; // every 50us low level stands for 1cm
    }
    return distance;
}

void carStop() { // Motor Stop
    digitalWrite(speedPin_M2,0);
    digitalWrite(directionPin_M1,LOW);
}

```

```
digitalWrite(speedPin_M1,0);
digitalWrite(directionPin_M2,LOW);
}

void carAdvance(int leftSpeed,int rightSpeed){           //Move forward
  analogWrite (speedPin_M2,leftSpeed);                 //PWM Speed Control
  digitalWrite(directionPin_M1,HIGH);
  analogWrite (speedPin_M1,rightSpeed);
  digitalWrite(directionPin_M2,HIGH);
}

void carBack(int leftSpeed,int rightSpeed){             //Move backward
  analogWrite (speedPin_M2,leftSpeed);
  digitalWrite(directionPin_M1,LOW);
  analogWrite (speedPin_M1,rightSpeed);
  digitalWrite(directionPin_M2,LOW);
}

void carTurnRight(int leftSpeed,int rightSpeed){       //Turn Right
  analogWrite (speedPin_M2,leftSpeed);
  digitalWrite(directionPin_M1,LOW);
  analogWrite (speedPin_M1,rightSpeed);
  digitalWrite(directionPin_M2,HIGH);
}

void carTurnLeft(int leftSpeed,int rightSpeed){        //Turn Left
  analogWrite (speedPin_M2,leftSpeed);
  digitalWrite(directionPin_M1,HIGH);
  analogWrite (speedPin_M1,rightSpeed);
  digitalWrite(directionPin_M2,LOW);
}

void servoSweep(){
  if(sweepFlag){
    if(pos>=60 && pos<=120){
```

```
        pos=pos+1;                                // in steps of 1 degree
        myservo.write(pos);                       // tell servo to go to po
sition in variable 'pos'
    }
    if(pos>119)  sweepFlag = false;                // assign the var
iable again
}
else {
    if(pos>=60 && pos<=120){
        pos=pos-1;
        myservo.write(pos);
    }
    if(pos<61)  sweepFlag = true;
}
}
```

Your own car was born!