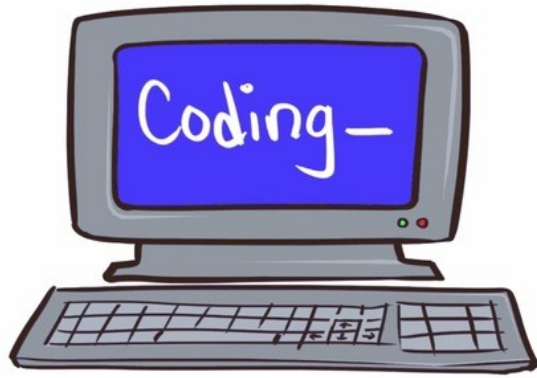


Class 47



Robot

Multi-wifi login

Oled display with easyoled

Blynk

H-Bridge (L298) 2 motors

~~Servomotors 2~~

~~IR remote~~

~~Wheel counters 2~~

IMU

Sonar HC-sr04 2

Ztimer 2

~~Feelers/bumpers 1~~

Sketches

robot0.ino

blynk2steering.ino

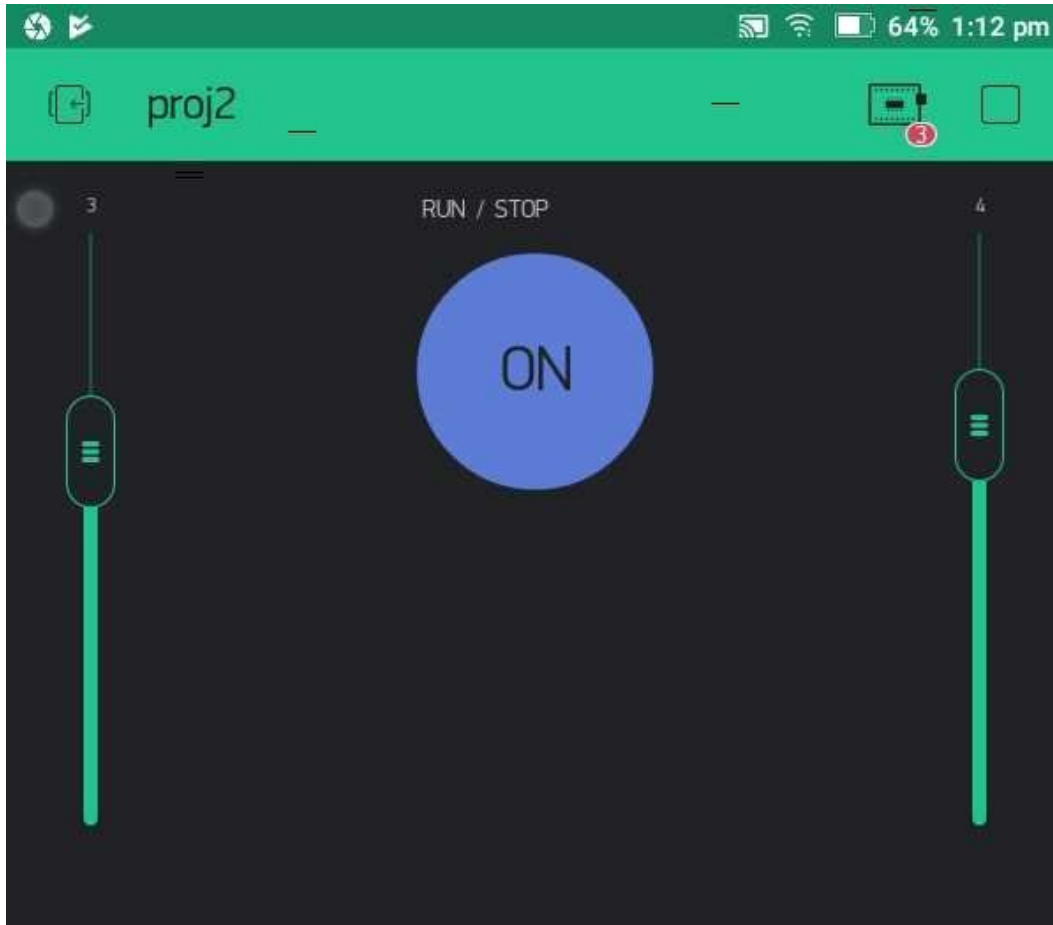
stopAtWall.ino

trim_manual.ino

compass_correct.ino

robot0

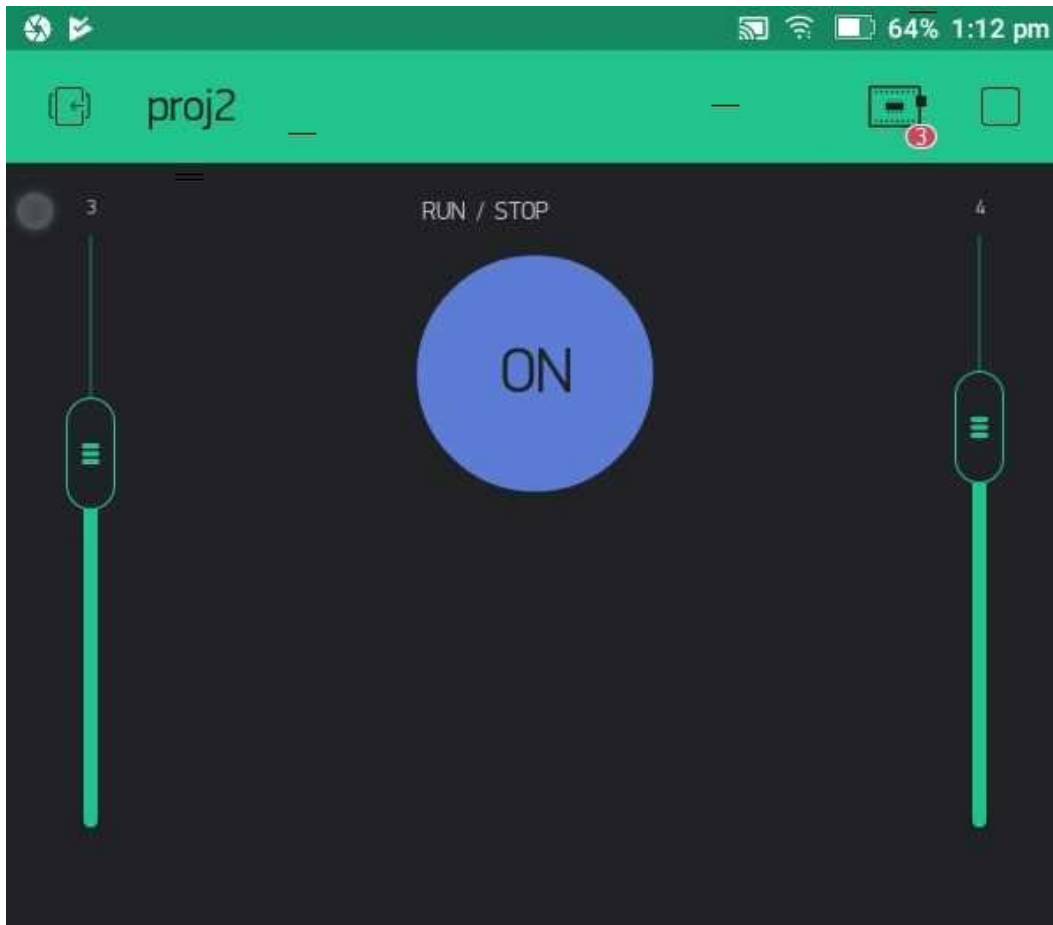
- We had this last week.
- Simply putting in all the devices we have learned about this year.
- Can they all live together in one sketch?
- No delay() stopping other processes running freely?
- No wheels operating yet!



blynk2steering

Separate control each wheel
Fwd / back

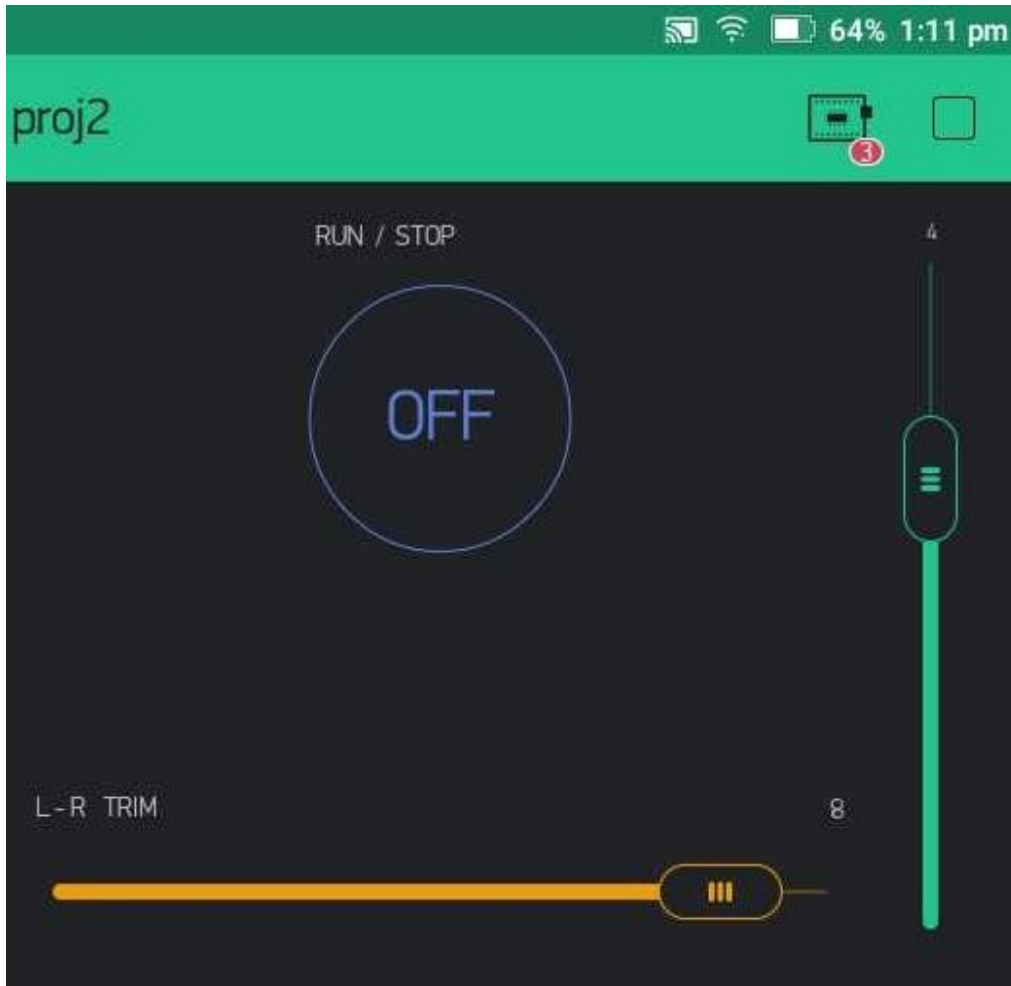
On/off button V1 0/1
Left speed V14 scaled -10 to +10
Right speed V13 scaled -10 to +10



stopAtWall

Add function to STOP
if approaching wall

On/off button V1 0/1
Left speed V14 scaled -10 to +10
Right speed V13 scaled -10 to +10
Sonar set 15 cm



trim_manual

Coded only for fwd movement

On/off button V1 0/1
Speed V14 scaled 0 to +10
L / R Trim V15 scaled -10 to +10



compass_correct

An attempt to

SET a compass (bearing) reference

And to adjust L/R trim using current deviation from correct bearing

On / Off
Speed
Trim

as before

Re-Reference button to set bearing
(button not switch) on V4

