

How Does a C Program Talk to a Scribbler Robot?

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How Does it Work?

Workstation

Robot

2

The workstation executes the command `rConnect`. The workstation searches for all Bluetooth beacons in the area, and utilizes the MyroC library to identify the robot with the correct name matching the workstation.

1

The robot periodically sends out a Bluetooth **beacon**. This beacon establishes the robot's proximity and name.

3

The workstation and robot interact to negotiate communications.

4

THE CONNECTION IS ESTABLISHED

5

A program executes the command `rBeep`. The command `rBeep` is translated into byte code. Then the workstation uses the MyroC library to relay that data to the robot through the socket.

6

A MESSAGE IS SENT

7

The robot receives the `rBeep` command, reads the message, and follows the command.

8

THE ROBOT BEEPS

9

`rDisconnect` severs the connection between the robot and the workstation.

10

THE ROBOT DISCONNECTS

MyroC/Scribbler Language

The MyroC library and your Scribbler robot have an agreed upon low-level language or **byte code**. Commands such as `rForward`, `rBeep`, and `rTakePicture` are translated from C to binary and streamed through Bluetooth.

Example Code

```
/* This code demonstrates the scribbler robot's
 * beep function for 1 second at 400 hertz.
 */
#include "MyroC.h"
int main()
{
    rConnect("/dev/rfcomm0");

    rBeep(1,400);

    rDisconnect();

    return 0;
} //main
```

Bluetooth Protocol

The robot gives out a signal to the workstation every 5 milliseconds. The `rConnect()` command uses Bluetooth to identify the robot signal and establishes a connection to the robot assigned to the workstation. After establishing a connection, the workstation sends data packets to the robot through the ports to accomplish the given commands.

