

Занятие по робототехнике:

Аппаратная и программная отладка модели робота «Движение по линии»



```
totalWait = firstStop;
while (true)
  turn = lookToOneSide;
  servoTurn = wait for the servo to be finished turning
  < 90;
  totalWait++;
}

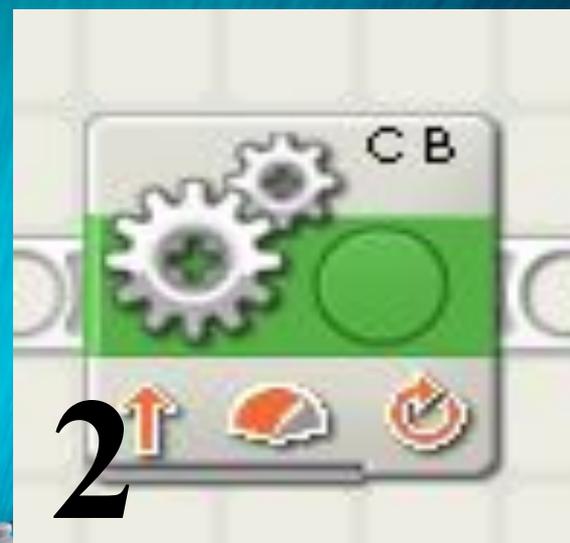
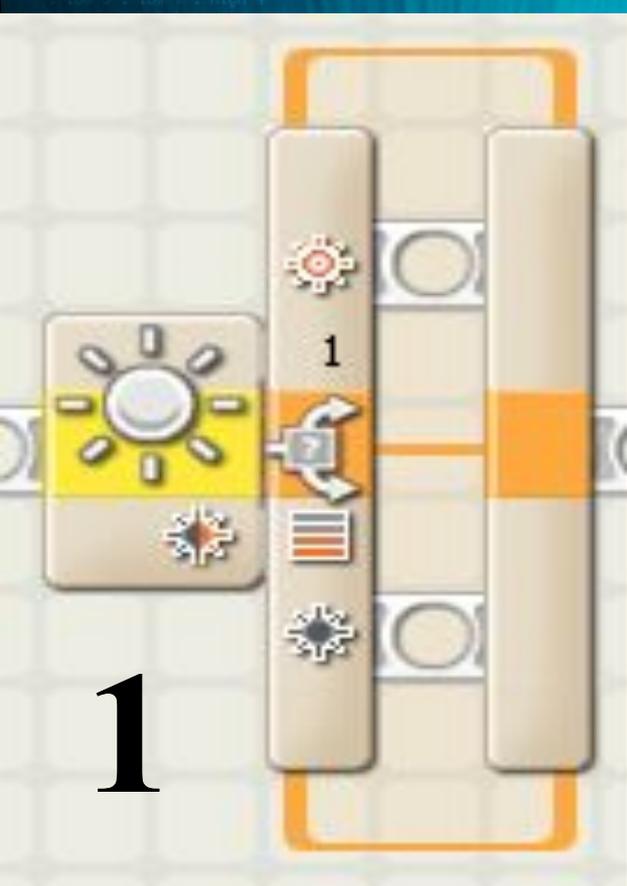
the other way:
turn = lookToAnotherSide;
servoTurn = wait for the servo to be finished turning
  < 90;
  totalWait++;
}

be careful in the better way:
do {turn}
while (true);
```

Цикл

Движение

Переключатель



totalWait = firstStop;

void stop1

```
turn1 = lookToOneSide;  
servoTurn1 = wait for the servo to be finished turning  
to 90;  
totalWait1;
```

the other way:

```
turn2 = lookToAnotherSide;  
servoTurn2 = wait for the servo to be finished turning  
to 90;  
totalWait2;
```

so which is the better way:

```
do { turn1  
  servoTurn1  
} while (true);
```

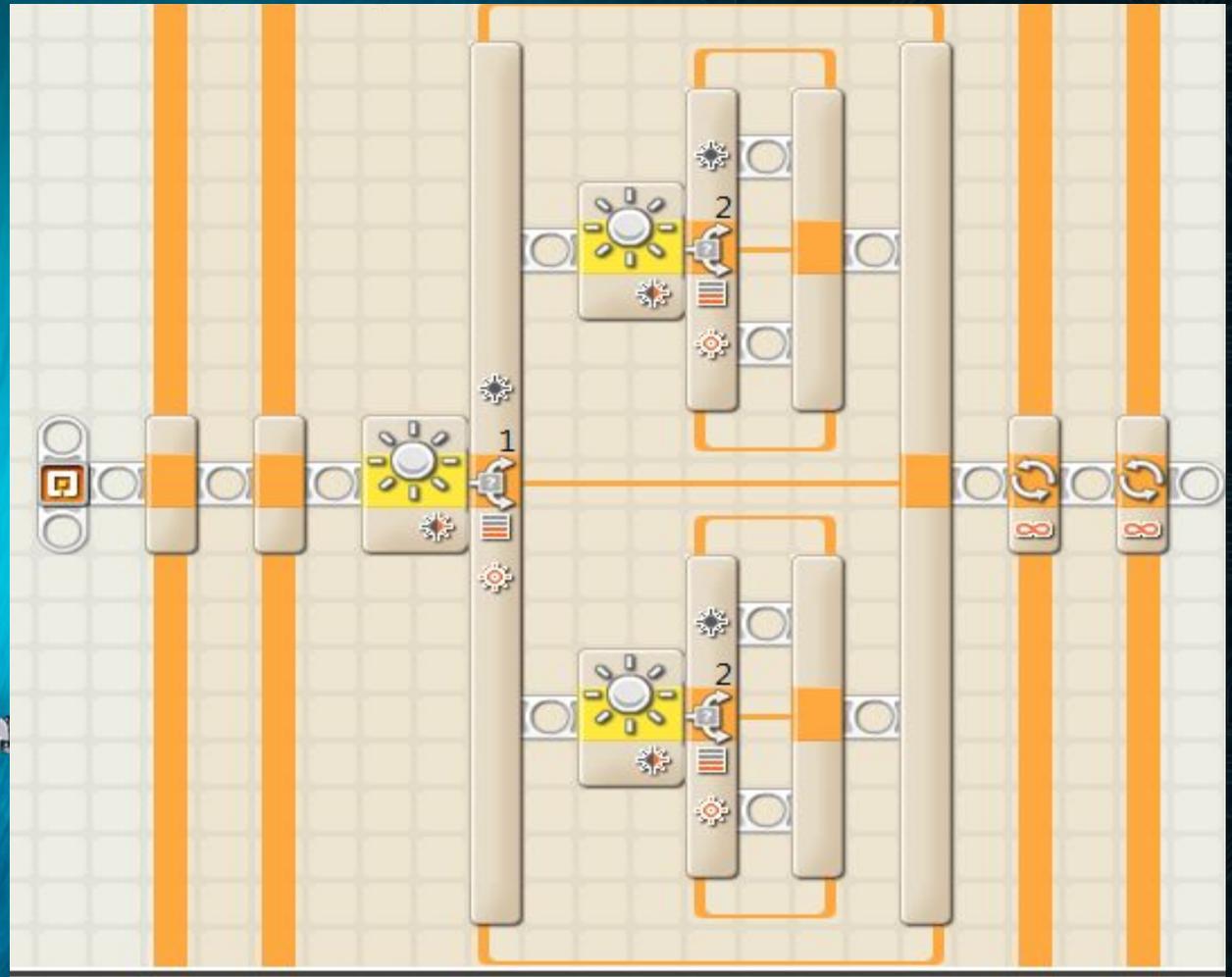
```
do { turn2  
  servoTurn2  
} while (true);
```

turn1

```
low 5 : low 7 : high 4  
turn1 = servo1 totalWait1;
```

turn2

```
low 6 : low 9 : high 7  
turn2 = servo2 totalWait2;
```



totalWait = firstStop;

void turn1

{turn = lookToOppositeSide;

servoTurn; // wait for the servo to be finished turning
// by pg

totalWait++;

the other way:

turn = lookToAnotherSide;

servoTurn; // wait for the servo to be finished turning
// by pg

totalWait++;

so which is the better way:

pg: turn

lookToOppositeSide

lookToAnotherSide

turn1

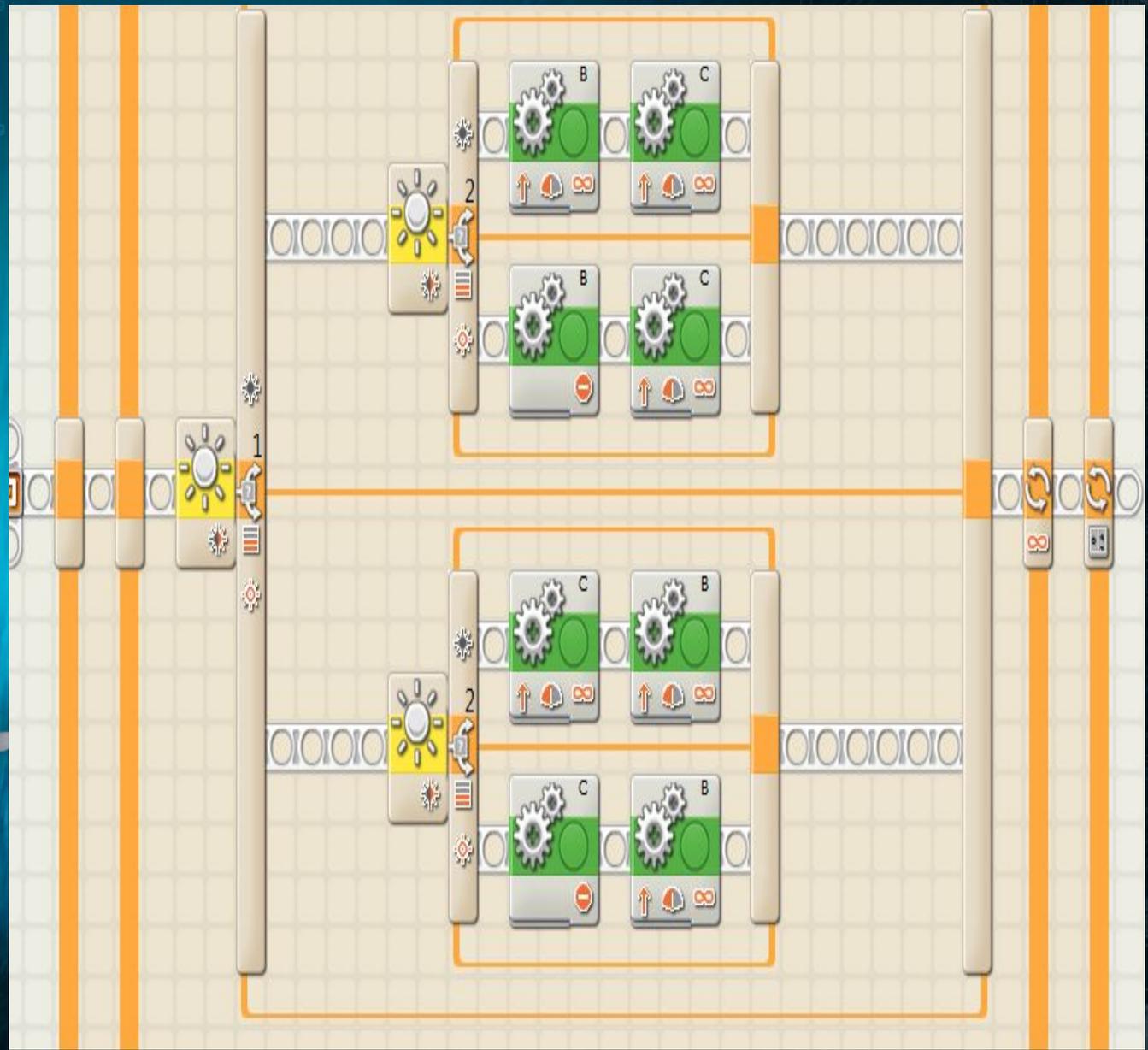
1: low 0, 1: low 1, 2: high 4

turn 2: servo1 totalWait

turn2

2: low 0, 1: low 1, 2: high 7

turn 3: servo2 totalWait



Загружаем программу



```
totalWait = firstStop;
```

```
void loop() {  
  turn = lookToOneSide;  
  servoTurn = wait for the servo to be finished turning  
  & n; // //  
  totalWait;  
}
```

```
the other way:  
void loop() {  
  servoTurn = wait for the servo to be finished turning  
  & n; // //  
  totalWait;  
}
```

```
is which is the better way:  
// //  
void loop() {
```

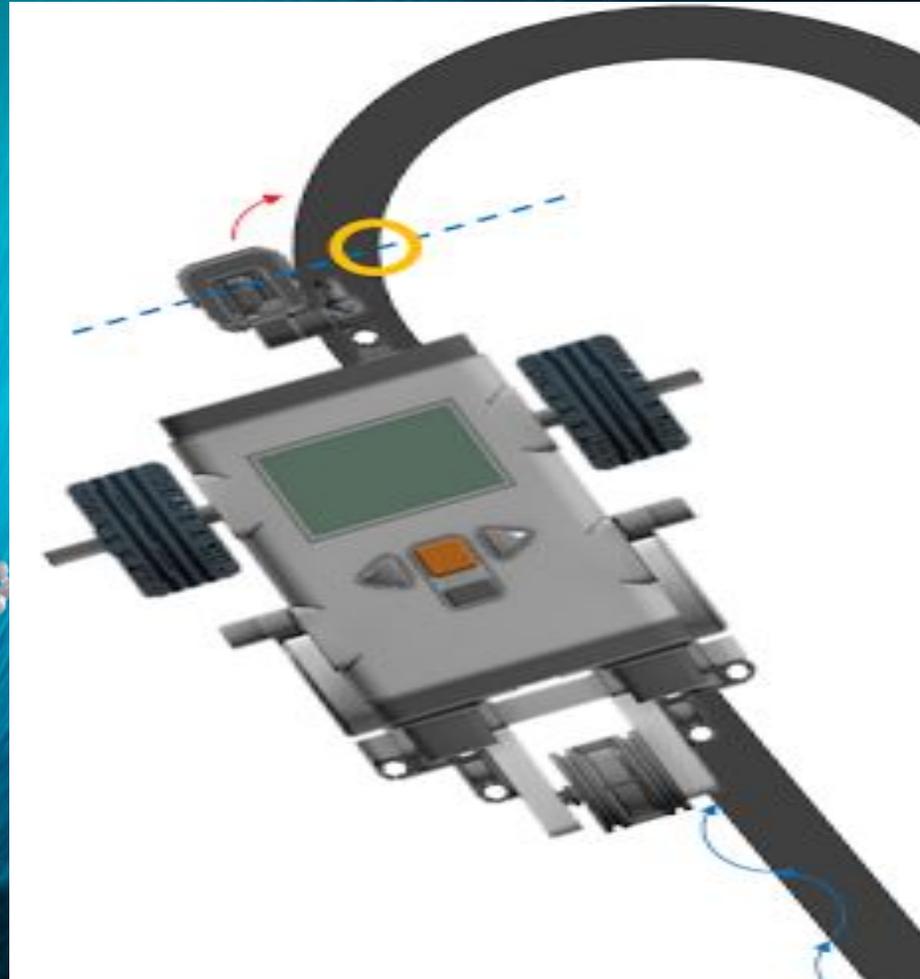
```
  // //
```

```
turn = lookToOneSide;  
  servoTurn = wait for the servo to be finished turning  
  & n; // //
```

```
turn = lookToAnotherSide;  
  servoTurn = wait for the servo to be finished turning  
  & n; // //
```



Тестирование



```
totalWait = firstStop;
void stop() {
  digitalWrite(LED_BUILTIN, HIGH); // look to one side
  servoTurn & wait for the servo to be finished turning
  digitalWrite(LED_BUILTIN, LOW);
}
totalWait;
```

```
the other way:
void stop() {
  digitalWrite(LED_BUILTIN, HIGH); // look to another side
  servoTurn & wait for the servo to be finished turning
  digitalWrite(LED_BUILTIN, LOW);
}
totalWait;
```

```
the which is the better way:
void stop() {
  digitalWrite(LED_BUILTIN, HIGH);
}
totalWait;
```

```
void stop() {
  digitalWrite(LED_BUILTIN, HIGH); // look to one side
  servoTurn & wait for the servo to be finished turning
  digitalWrite(LED_BUILTIN, LOW);
}
totalWait;
```

```
void stop() {
  digitalWrite(LED_BUILTIN, HIGH); // look to the other side
  servoTurn & wait for the servo to be finished turning
  digitalWrite(LED_BUILTIN, LOW);
}
totalWait;
```

Спасибо за

продуктивную работу!!!

