

Chapter 4

Serial Communication with Robot

On successful completion of this course, students will be able to:

- Explain principle of serial communication for robotics.
- Program the mobile robot using serial and wireless communication.
- Develop an interface program using Visual Basic/C# .Net.

Introduction

We need data communication to sending and receiving serial data using RS-232 Communication or wirelessly between microcontrollers or to a PC. 433 MHz RF Transceiver with Low power consumption makes it ideal for use in battery-powered applications. Data is sent and received by AM or CPCA modulation, thus offering a higher average output power which extends the range. Digi XBee 802.15.4 modules are the easiest-to-use, most reliable and cost-effective RF devices we've experienced. The 802.15.4 XBee modules provide two friendly modes of communication – a simple serial method of transmit/receive or a framed mode providing advanced features. XBee are ready to use out of the package, or they can be configured through the X-CTU utility or from your microcontroller.

Serial Interface Using Microsoft Visual Basic/C# .Net

RS-232 stands for Recommend Standard number 232 and C is the latest revision of the standard. The serial ports on most computers use a subset of the RS-232C standard. The full RS-232C standard specifies a 25-pin "D" connector of which 22 pins are used. Most of these pins are not needed for normal PC communications, and indeed, most new PCs are equipped with male D type connectors having only 9 pins. The baud unit is named after Jean Maurice Emile Baudot, who was an officer in the French Telegraph Service. He is credited with devising the first uniform-length 5-bit code for characters of the alphabet in the late 19th century. What baud really refers to is modulation rate or the number of times per second that a line changes state. This is not always the same as bits per second (BPS). If you connect two serial devices together using direct cables then baud and BPS are in fact the same. Thus, if you are running at 19200 BPS, then the line is also changing states 19200 times per second.

There are two basic types of serial communications, synchronous and asynchronous. With Synchronous communications, the two devices initially synchronize themselves to each other, and then continually send characters to stay in sync. Even when data is not really being sent, a constant flow of bits allows each device to know where the other is at any given time. That is, each character that is sent is either actual data or an idle character. Synchronous communications allows faster data transfer rates than asynchronous methods, because additional bits to mark the beginning and end of each data byte are not required. The serial ports on IBM-style PCs are asynchronous devices and therefore only support asynchronous serial communications.

Asynchronous means "no synchronization", and thus does not require sending and receiving idle characters. However, the beginning and end of each byte of data must be identified by start and stop bits. The start bit indicate when the data byte is about to begin and the stop bit signals when it ends. The requirement to send these additional two bits causes asynchronous communications to be slightly slower than synchronous. When transmitting a byte, the UART (serial port) first sends a START BIT which is a positive voltage (0), followed by the data (general 8 bits, but could be 5, 6, 7, or 8 bits) followed by one or two STOP BITs which is a negative(1) voltage. The sequence is repeated for each byte sent. Figure 4.1 shows a diagram of a byte transmission would look like.

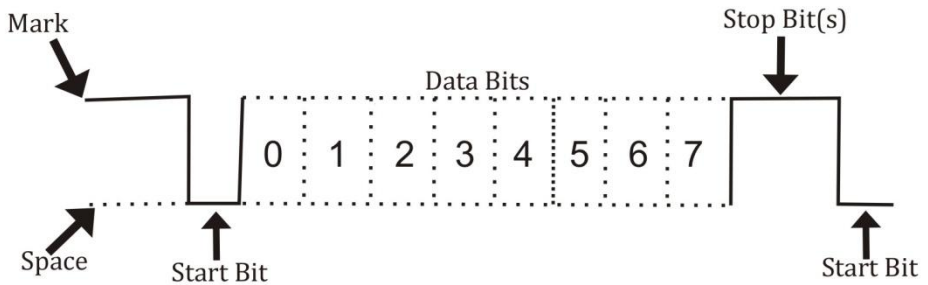


Figure 4.1 Serial communication format[1].

To create a serial interface program for PC, we can use many programming languages such as Visual Basic, Visual C # or Borland Delphi. Ms. Visual C #. Net 2010/2013 is one of the programming languages that allow us to create GUI applications for communication with the robot. There SerialPort class can be used to access serial port. Program for serial communication on propeller is quite easy because it uses objects, such as Parallax Serial Terminal, for example:

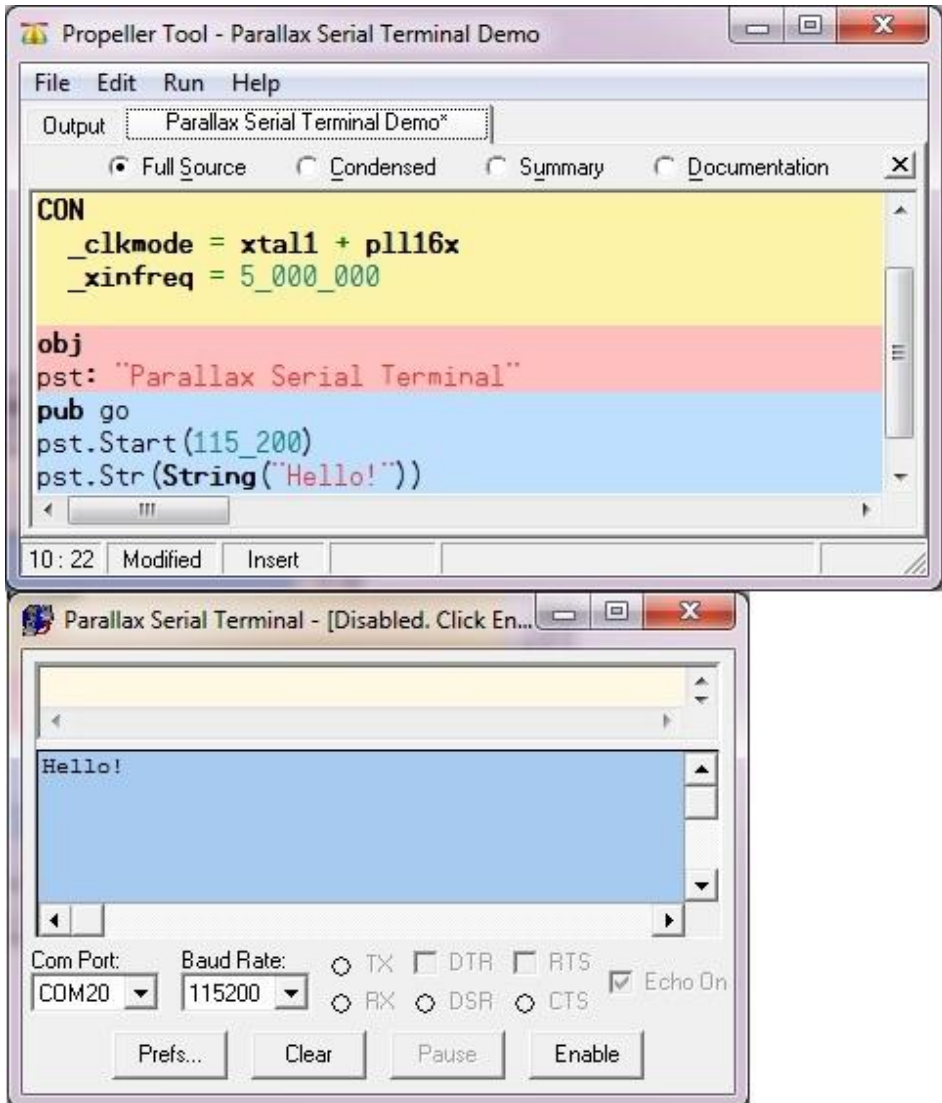


Figure 4.2 Serial communication between PC and the Propeller Microcontroller.

You can download Ms. Visual Studio 2013 Express edition to use this program. Once installed, create a form like the following by putting 2 button,

combobox, richtextbox, label and textbox. The program will connect to the microcontroller as a robot controller.

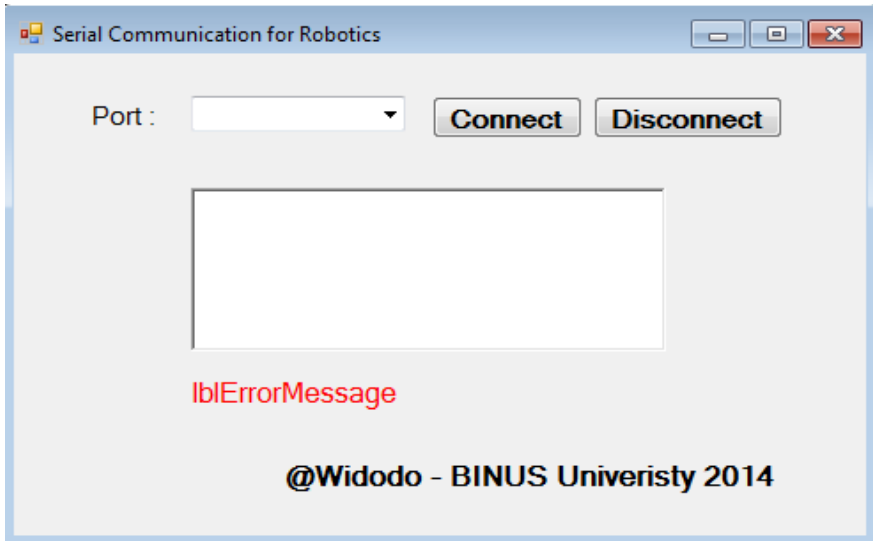


Figure 4.3 Form design for interfacing between PC and Robot.

The program will read a text file and then its value will be used to issue serial data to the robot with the following code:

```

If (txtData.Text = "1") Then
    lblAksi.Text = "forward"
    serialPort.Write("a") 'forward
End If

If (txtData.Text = "0") Then
    lblAksi.Text = "backward"
    serialPort.Write("b") 'backward
    
```

Here is the complete code for serial interface to program the robot:

SerialInterface.vb

```

imports System.IO
Public Class Form1
    Dim WithEvents serialPort As New IO.Ports.SerialPort
    
```

```

Private Sub Form1_Load(ByVal sender As System.Object, ByVal e
As System.EventArgs) Handles MyBase.Load
    displayPort()
    cbComPorts.SelectedIndex = 1

End Sub

Private Sub btnConnect_Click(ByVal sender As System.Object,
ByVal e As System.EventArgs) Handles btnConnect.Click
    If serialPort.IsOpen Then
        serialPort.Close()
    End If
    Try
        With serialPort                                'configuring port
            .PortName = cbComPorts.Text
            .BaudRate = 9600
            .Parity = IO.Ports.Parity.None
            .DataBits = 8
            .StopBits = IO.Ports.StopBits.One
        End With
        serialPort.Open()
        lblMessage.Text = cbComPorts.Text & " Connected"
        btnConnect.Enabled = False
        btnDisconnect.Enabled = True
    Catch ex As Exception
        MsgBox(ex.ToString)
    End Try
    Timer1.Enabled = True
    Timer1.Interval = 100
End Sub

Private Sub datareceived(ByVal sender As Object, ByVal e As
System.IO.Ports.SerialDataReceivedEventArgs) Handles
serialPort.DataReceived
    'RichTextBox1.Invoke(New myDelegate(AddressOf updateTextBox),
New Object() {})
End Sub

Public Sub updatetextbox()
    RichTextBox1.Text = ""

```

```
With RichTextBox1
    .AppendText(serialPort.ReadExisting)
End With
End Sub

Private Sub btnDisconnect_Click(ByVal sender As System.Object,
ByVal e As System.EventArgs) Handles btnDisconnect.Click
    Try
        serialPort.Close()
        lblMessage.Text = serialPort.PortName & " Disconnected ."
        btnConnect.Enabled = True
        btnDisconnect.Enabled = False
    Catch ex As Exception
        MsgBox(ex.ToString)
    End Try
End Sub

Private Sub Timer1_Tick(ByVal sender As System.Object, ByVal e
As System.EventArgs) Handles Timer1.Tick

    Try
        Dim fs As New FileStream("c:/position.txt", FileMode.Open,
FileAccess.Read)
        txtData.Text = ""
        Dim d As New StreamReader(fs)
        d.BaseStream.Seek(0, SeekOrigin.Begin)
        While d.Peek() > -1
            txtData.Text &= d.ReadLine()
        End While
        d.Close()

        If (txtData.Text = "1") Then
            lblAksi.Text = "forward"
            serialPort.Write("a") 'forward
        End If

        If (txtData.Text = "0") Then
            lblAksi.Text = "backward"
            serialPort.Write("b") 'backward
        End If
    End Try
End Sub
```



```

    Catch ea As Exception
        'MessageBox.Show(ea.Message)
    End Try
End Sub
End Class

```

The following programs are used in the Propeller to receive serial data from a PC:

File: SerialPCRobot.spin

```

CON
    _clkmode = xtall + pll16x
    _xinfreq = 5_000_000

OBJ
    Debug: "FullDuplexSerialPlus

PUB TestMessages| c
    c:="S"

        dira[8] := 1
        dira[9] := 1
        dira[10] := 1
        outa[8] := 0
        outa[9] := 0
        outa[10] := 0

    'Send test messages to Parallax Serial Terminal.
    Debug.start(31, 30, 0, 9600)
    Debug.str(string("Demo!", 13))
    repeat until c == "Q" or c == "q"
        c := Debug.rx
        case c
            "A", "a":
                Debug.Str(String("forward"))
                outa[8] := 1
                outa[9] := 0
                outa[10] := 0
                waitcnt(clkfreq/10 + cnt)
        case c

```

```
"B", "b":
    Debug.Str(String("backward"))
    outa[8] := 0
    outa[9] := 1
    outa[10] := 0
    waitcnt(clkfreq/10 + cnt)
"C", "c":
    Debug.Str(String("turn left"))
    outa[8] := 0
    outa[9] := 0
    outa[10] := 1
    waitcnt(clkfreq/10 + cnt)
"Q", "q": quit
```

Wireless Communication for Robot

433 MHz Transceiver

433 MHz Transceiver is an easy-to-use module is capable of sending and receiving serial data wirelessly between microcontrollers or to a PC. Low power consumption makes it ideal for use in battery-powered applications. Data is sent and received by AM or CPCA modulation, thus offering a higher average output power which extends the range. This module is equipped with an RSSI feature that can be utilized to improve power efficiency by waking up circuitry only when an external signal is detected.



Figure 4.4 Wireless communication using 433 MHz Transceiver.

XBee Transceiver

XBee 1 mW Wire Antenna 802.15.4 modules are the easiest-to-use, most reliable and cost-effective RF devices we've experienced. The 802.15.4 XBee modules provide two friendly modes of communication – a simple serial method of transmit/receive or a framed mode providing advanced features. XBees are ready to use out of the package, or they can be configured through the X-CTU utility or from your microcontroller. These modules can communicate point to point, from one point to a PC, or in a mesh network.

You only need to choose an antenna style (PCB or wire) and power level (1 mW for up to 300 ft and 60 mW for up to 1 mile). The PCB antenna version provides a lower profile footprint for applications with limited space while the

wire antenna version allows for more flexibility in adjusting for optimal range at the same output power. XBee 802.15.4 modules are cross-compatible with other 802.15.4 XBee modules, regardless of antenna type or power rating.

Key Features:

- Outdoor range up to 300 feet (90 m) line of sight.
- Indoor range up to 100 feet (30 m).
- Data rate up to 250 Kbps.
- 2.4 GHz frequency band (accepted world-wide).



Figure 4.5 Wireless communication using XBee.

XBee Transceiver AT-API Object is an object for communicating with Digi's XBee (designed/tested with Series 1 - 802.15.4) transceivers in both transparent (AT) and API mode. API mode involves framed data with information such as sender's address and RSSI levels.

RN-42 Bluetooth Module

The RN-42 Bluetooth Module provides a reliable method for creating a wireless serial communication interface between two devices such as a microcontroller, PC, cell phone, or another module for robotics application. This module can pair up with devices supporting Bluetooth SPP (Serial Port Profile) to establish a serial interface. The RN-42 Bluetooth Module is breadboard-friendly and is compatible with all 5 V and 3.3 V microcontroller platforms.

Key Features:

- Fully qualified Bluetooth 2.1/2.0/1.2/1.1 module provides compatibility with many devices.
- Low power consumption for long-lasting battery-powered projects.
- Auto-connect/discovery/pairing modes make connecting to other modules easy.
- LED indicators provide visual status of connection/mode.
- Voltage jumper selects for use with 5 V and 3.3 V microcontrollers.

When pairing the RN-42 with another device such as a laptop or cell phone the default passkey is “1234”. The device is discovered as RN42-xxxx (where xxxx is the last 4 digits of the device MAC address). On a PC with Bluetooth the device will have a COM port assigned to it. When this COM port is opened the PC should reconnect to the module (the Blue LED should light up). At this point you can send/receive serial data.

Exercises

- 1) Write an interface using C# to control robot using PC.
- 2) Write wireless program to control robot using PC.

References

- [1] Stallings W., Data and Computer Communications, Prentice Hall Publisher, 2011.
- [2] www.parallax.com.

