How Does a C Program Talk to a Scribbler Robot?

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**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**

```c
/* 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;
}
```

**Bluetooth Protocol**

The robot gives out a signal to the workstation every 5 milliseconds. The rConnect() command uses Bluetooth to identify the robot’s 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.

**How Does it Work?**

**Workstation**

1. The robot periodically sends out a Bluetooth beacon. This beacon establishes the robot's proximity and name.
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.
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 sever the connection between the robot and the workstation.
10. The robot disconnects.

**Robot**