

## Use Radar Scanning Function

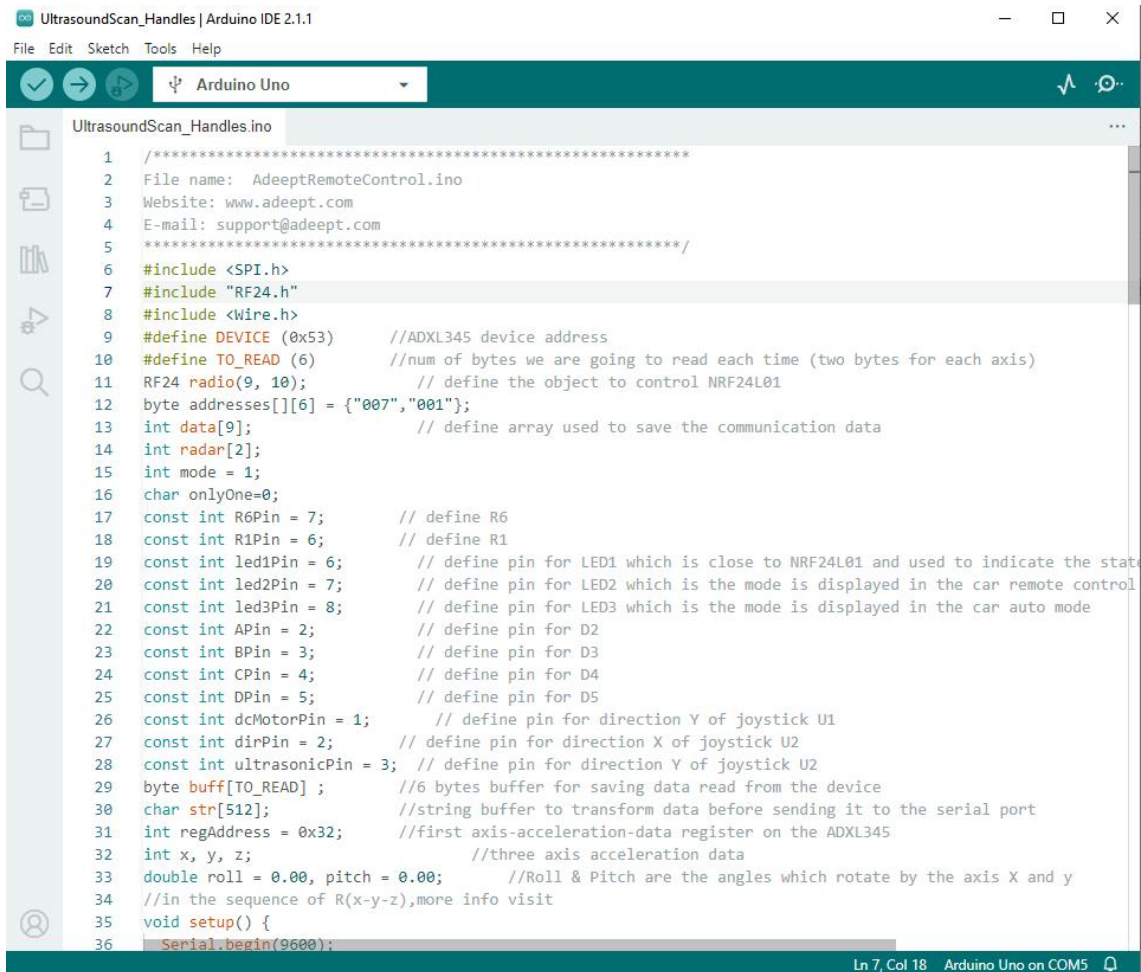
### Install an external NRF module





## Upload the program to the Handles

1. Connect your computer and Handle Controller with a Micro USB cable.
2. Open "Radar/UltrasoundScan\_Handles" folder in "[ProcessingCode](#)", double-click "[UltrasoundScan\\_Handles.ino](#)".



```

1  /*****
2  File name: AdeeptRemoteControl.ino
3  Website: www.adeept.com
4  E-mail: support@adeept.com
5  *****/
6  #include <SPI.h>
7  #include "RF24.h"
8  #include <Wire.h>
9  #define DEVICE (0x53) //ADXL345 device address
10 #define TO_READ (6) //num of bytes we are going to read each time (two bytes for each axis)
11 RF24 radio(9, 10); // define the object to control NRF24L01
12 byte addresses[][6] = {"007", "001"};
13 int data[9]; // define array used to save the communication data
14 int radar[2];
15 int mode = 1;
16 char onlyOne=0;
17 const int R6Pin = 7; // define R6
18 const int R1Pin = 6; // define R1
19 const int led1Pin = 6; // define pin for LED1 which is close to NRF24L01 and used to indicate the state
20 const int led2Pin = 7; // define pin for LED2 which is the mode is displayed in the car remote control
21 const int led3Pin = 8; // define pin for LED3 which is the mode is displayed in the car auto mode
22 const int APin = 2; // define pin for D2
23 const int BPin = 3; // define pin for D3
24 const int CPin = 4; // define pin for D4
25 const int DPin = 5; // define pin for D5
26 const int dcMotorPin = 1; // define pin for direction Y of joystick U1
27 const int dirPin = 2; // define pin for direction X of joystick U2
28 const int ultrasonicPin = 3; // define pin for direction Y of joystick U2
29 byte buff[TO_READ]; //6 bytes buffer for saving data read from the device
30 char str[512]; //string buffer to transform data before sending it to the serial port
31 int regAddress = 0x32; //first axis-acceleration-data register on the ADXL345
32 int x, y, z; //three axis acceleration data
33 double roll = 0.00, pitch = 0.00; //Roll & Pitch are the angles which rotate by the axis X and y
34 //in the sequence of R(x-y-z),more info visit
35 void setup() {
36   Serial.begin(9600);

```

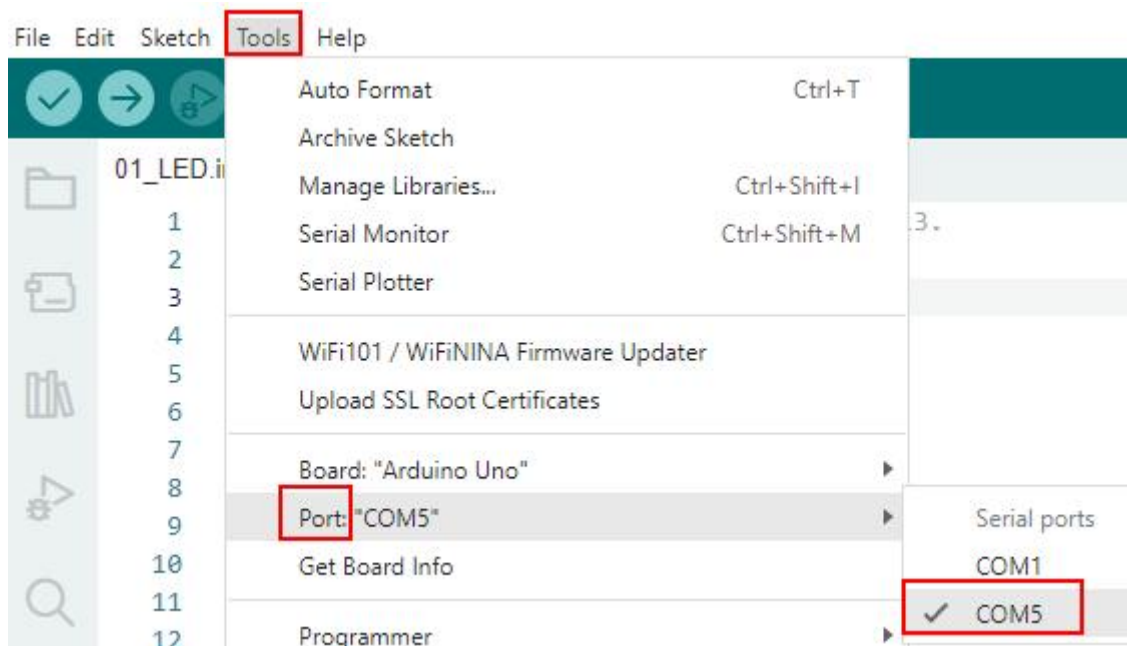
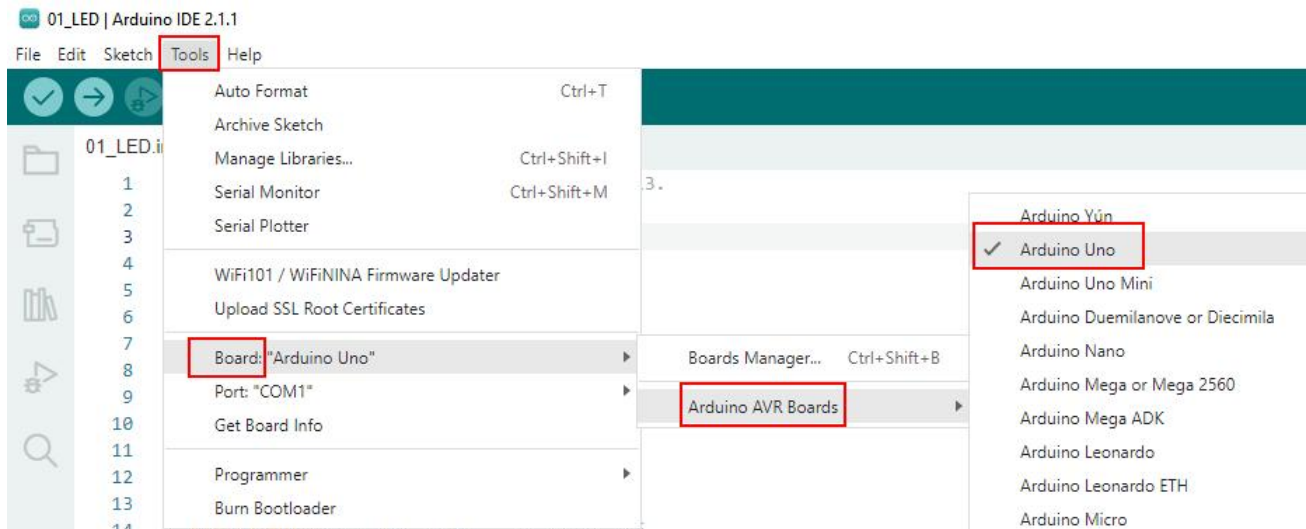
3. Select development board and serial port.


Board: **Tools**--->**Board**--->**Arduino AVR Boards**--->**Arduino Uno**

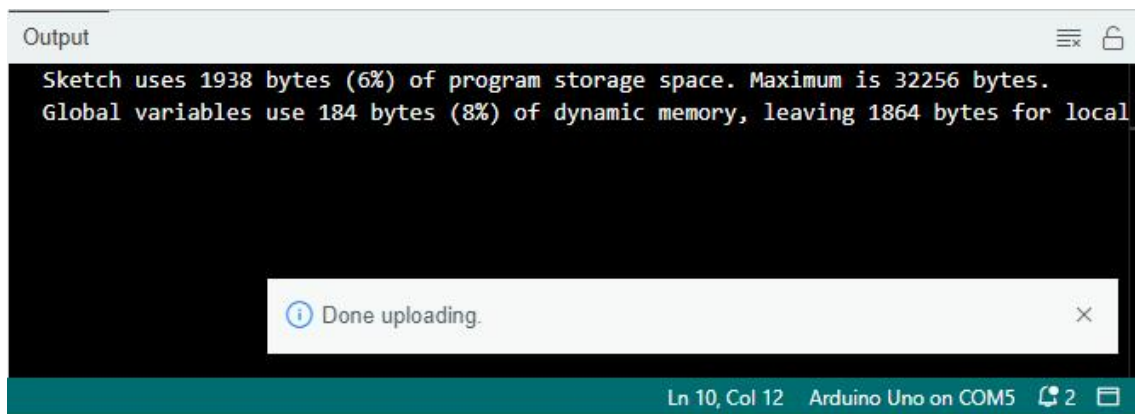
Port: **Tools** --->**Port**--->**COMx**

Note: The port number will be different in different computers.

Please remember the **COMx** used, it will be used later in the Processing IDE.

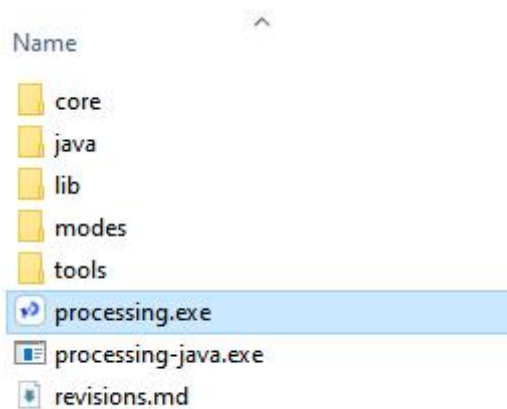


4. After opening, click  to upload the code program to the Arduino. If there is no error warning in the console below, it means that the Upload is successful.



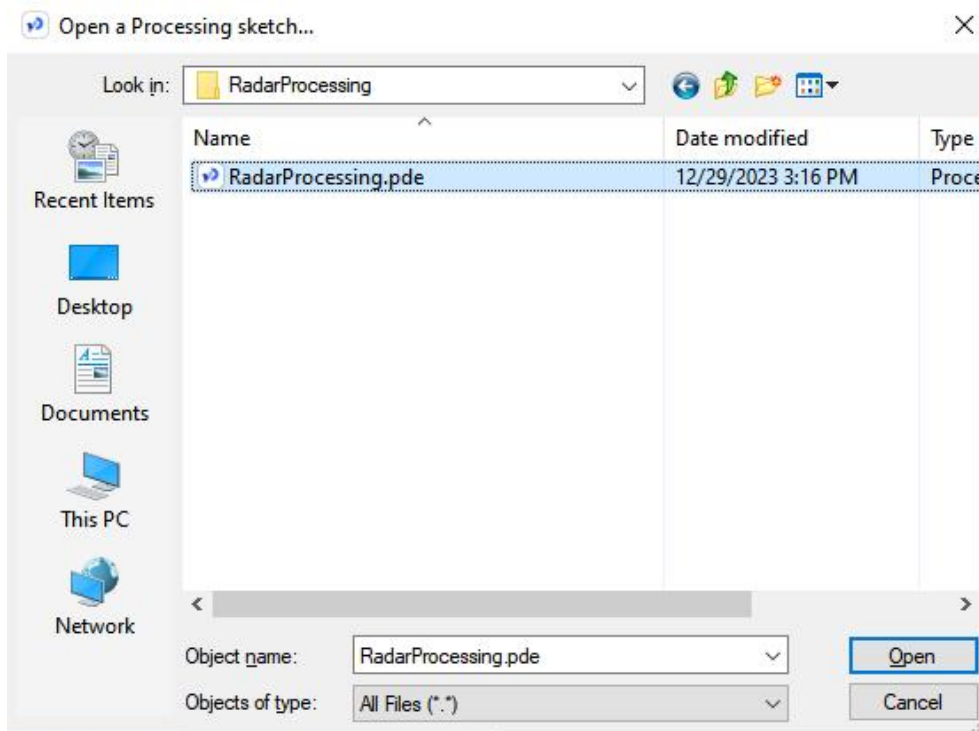
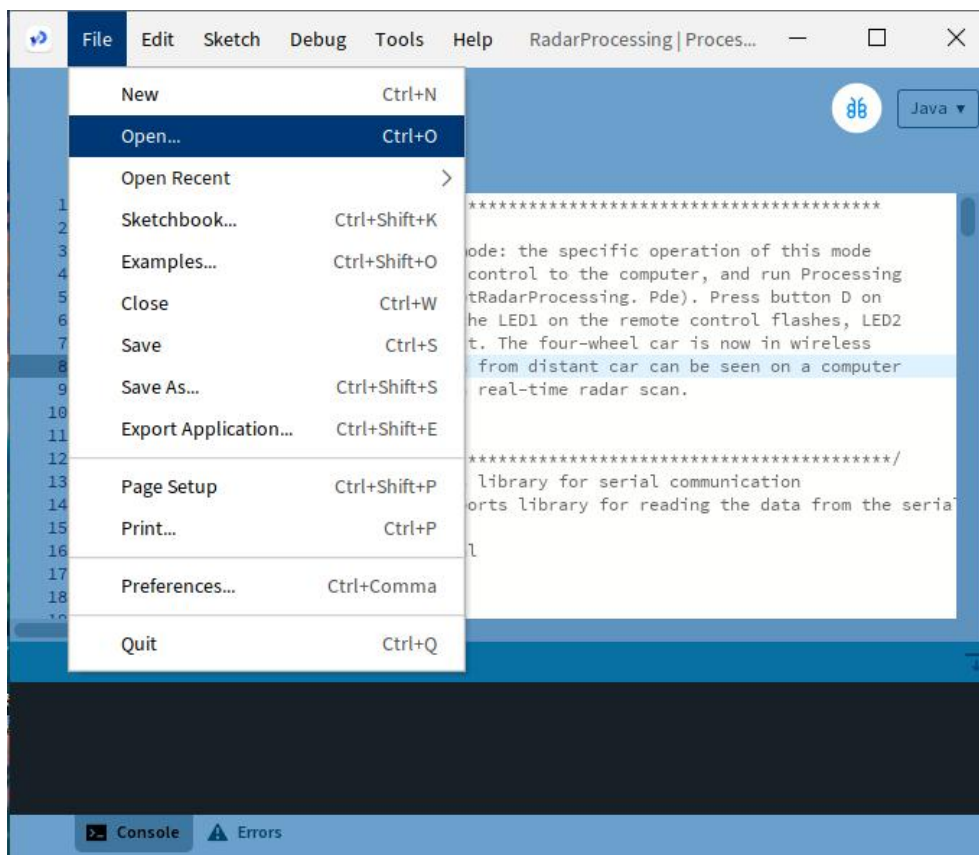
## Use Processing

Click "[processing.exe](#)" as the figure below to run Processing IDE.



Open the [RadarProcessing.pde](#) in the "Adeept\_UnoCar-B Car Tutorial\Code\RadarScan\RadarProcessing" folder .

Here we take Windows as an example. Click to open **RadarProcessing.pde**.







```

1  /*****
2  File name: RadarProcessing.pde
3  Description: Wireless radar scanning mode: the specific operation of this mode
4               is to connect the remote control to the computer, and run Processing
5               program we provide (AdeeptRadarProcessing. Pde). Press button D on
6               the remote control, and the LED1 on the remote control flashes, LED2
7               goes out and LED3 goes out. The four-wheel car is now in wireless
8               radar scanning mode. Data from distant car can be seen on a computer
9               screen and displayed as a real-time radar scan.
10 Website: www.adeept.com
11 E-mail: support@adeept.com
12 *****/
13 import processing.serial.*; // imports library for serial communication
14 import java.awt.event.KeyEvent; // imports library for reading the data from the serial
15 import java.io.IOException;
16 Serial myPort; // defines Object Serial
17 // defines variables
18 String angle="";
19 String distance="";

```

## Radar Scan Function

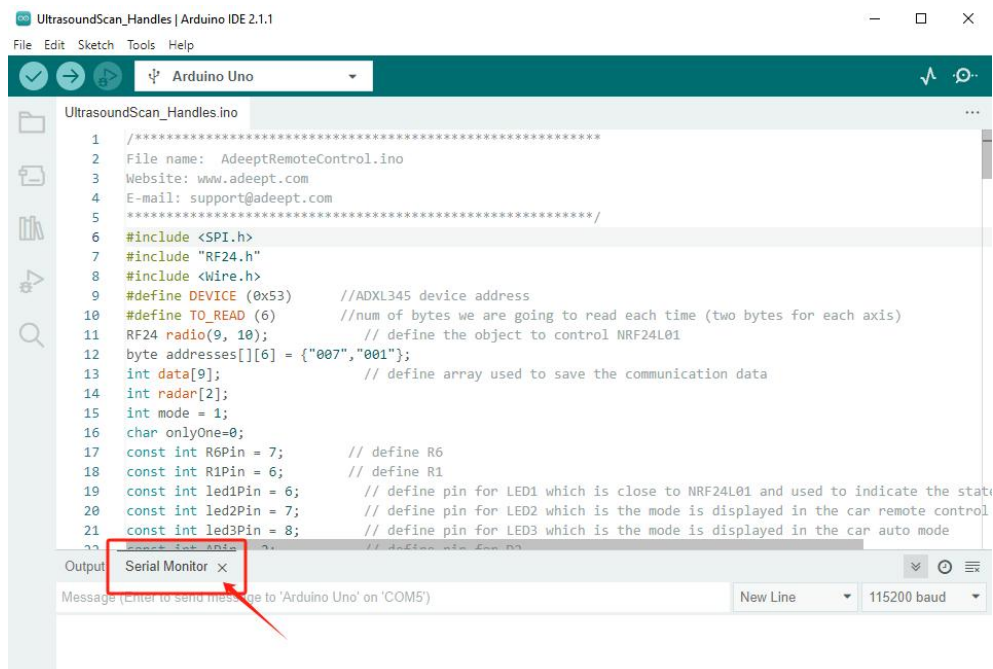
1. Make sure that the corresponding programs are successfully uploaded to both the handle and the car.
2. Connect the handle to the computer via USB cable, and remember COMx, such as COM5.
3. Change COM5 in line 37 of the [RadarProcessing.pde](#) file to COMx occupied by the handle.

Please note that COMx will change if connected to another USB port in the computer. Similarly, the COMx port in the program also needs to be modified.

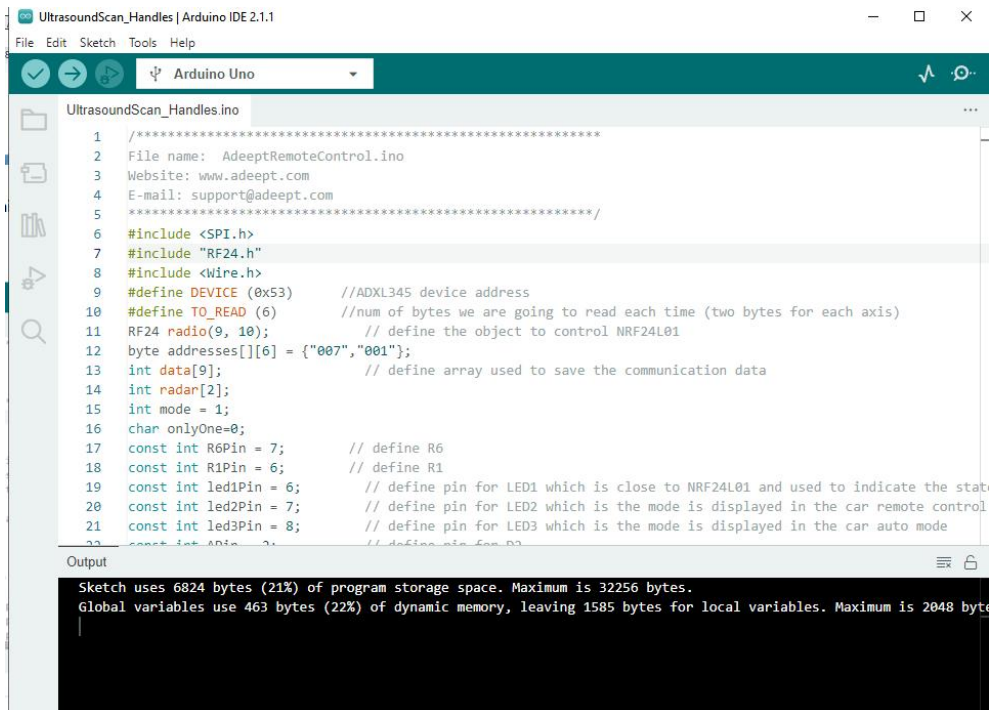
modified.

```
RadarProcessing
25 int index2=0;
26 PFont orcFont;
27 void setup() {
28
29   size (1200, 700); // ***CHANGE THIS TO YOUR SCREEN RESOLUTION***
30   size (1300, 700); // ***CHANGE THIS TO YOUR SCREEN RESOLUTION***
31   smooth();
32   // List all the available serial ports:
33   printArray(Serial.list());
34
35   // Open the port you are using at the rate you want:
36   //myPort = new Serial(this, Serial.list()[0], 9600);
37   myPort = new Serial(this, "COM5", 9600); // starts the serial communication
38   myPort.bufferUntil(' '); // reads the data from the serial port up to the character '
39 }
40 void draw() {
41
42   fill(98,245,31);
43   // simulation radar blue and glow fade of the moving line
```

4. Close all "Serial Monitor" in Arduino IDE.







```

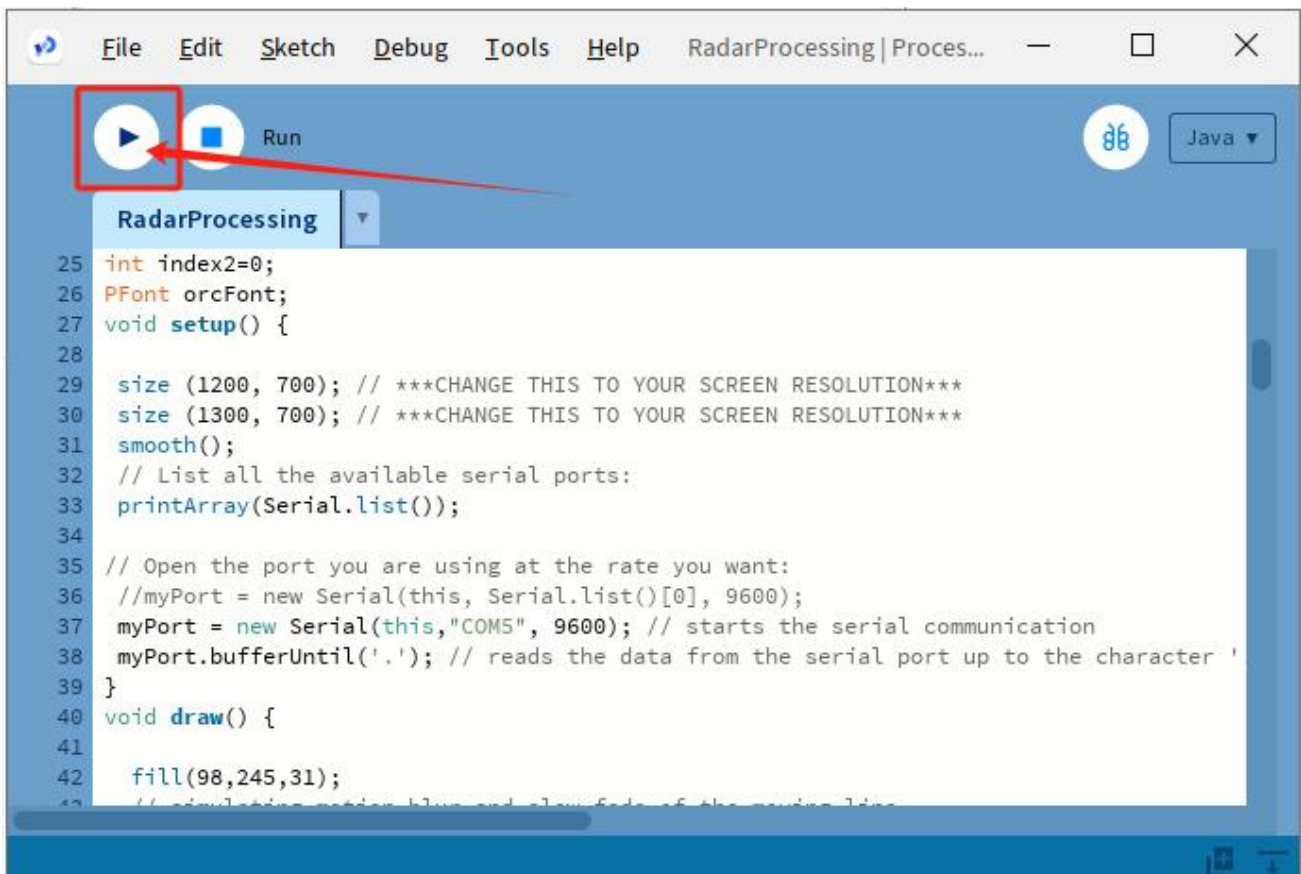
1  /*****
2  File name: AadeptRemoteControl.ino
3  Website: www.aadept.com
4  E-mail: support@aadept.com
5  *****/
6  #include <SPI.h>
7  #include "RF24.h"
8  #include <Wire.h>
9  #define DEVICE (0x53) //ADXL345 device address
10 #define TO_READ (6) //num of bytes we are going to read each time (two bytes for each axis)
11 RF24 radio(9, 10); // define the object to control NRF24L01
12 byte addresses[][6] = {"007", "001"};
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15 int mode = 1;
16 char onlyOne=0;
17 const int R6Pin = 7; // define R6
18 const int R1Pin = 6; // define R1
19 const int led1Pin = 6; // define pin for LED1 which is close to NRF24L01 and used to indicate the statu
20 const int led2Pin = 7; // define pin for LED2 which is the mode is displayed in the car remote control
21 const int led3Pin = 8; // define pin for LED3 which is the mode is displayed in the car auto mode
22 const int ADXPin = 9; // define pin for ADXL345

```

Output

Sketch uses 6824 bytes (21%) of program storage space. Maximum is 32256 bytes.  
Global variables use 463 bytes (22%) of dynamic memory, leaving 1585 bytes for local variables. Maximum is 2048 bytes.

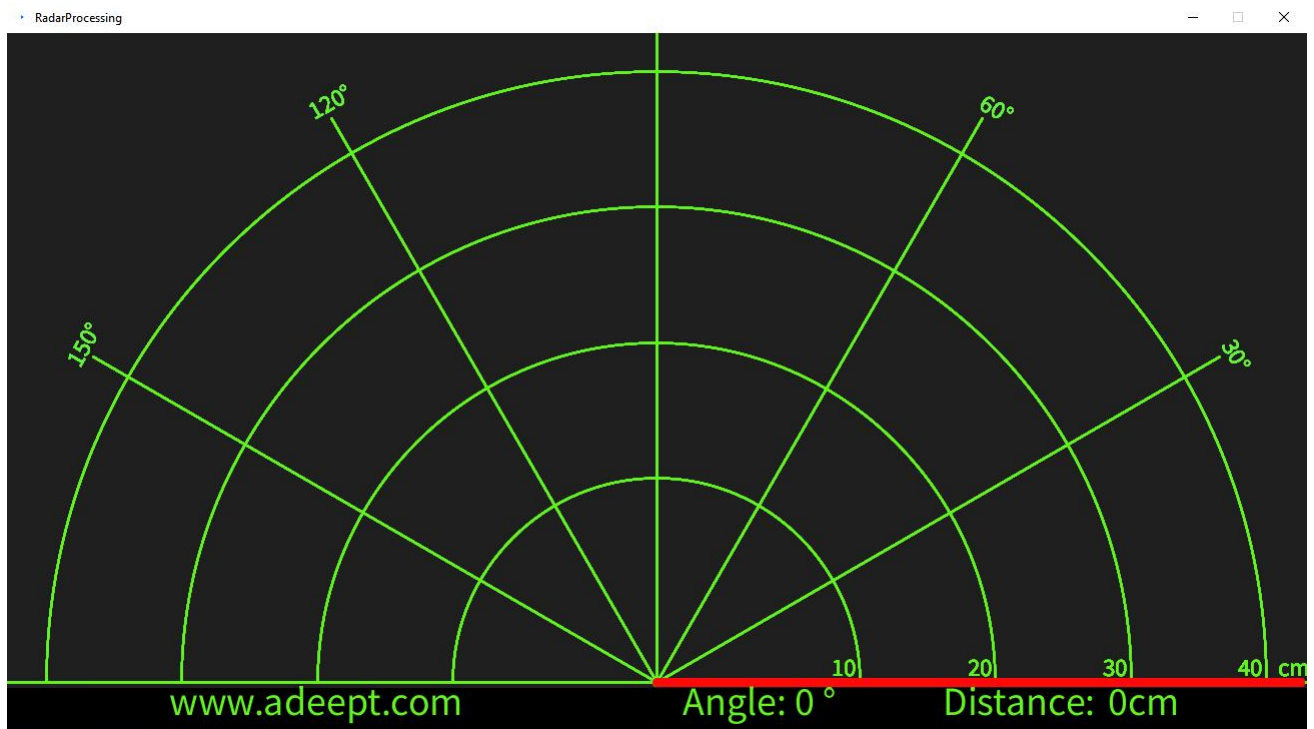
5. Click **"Run"**.



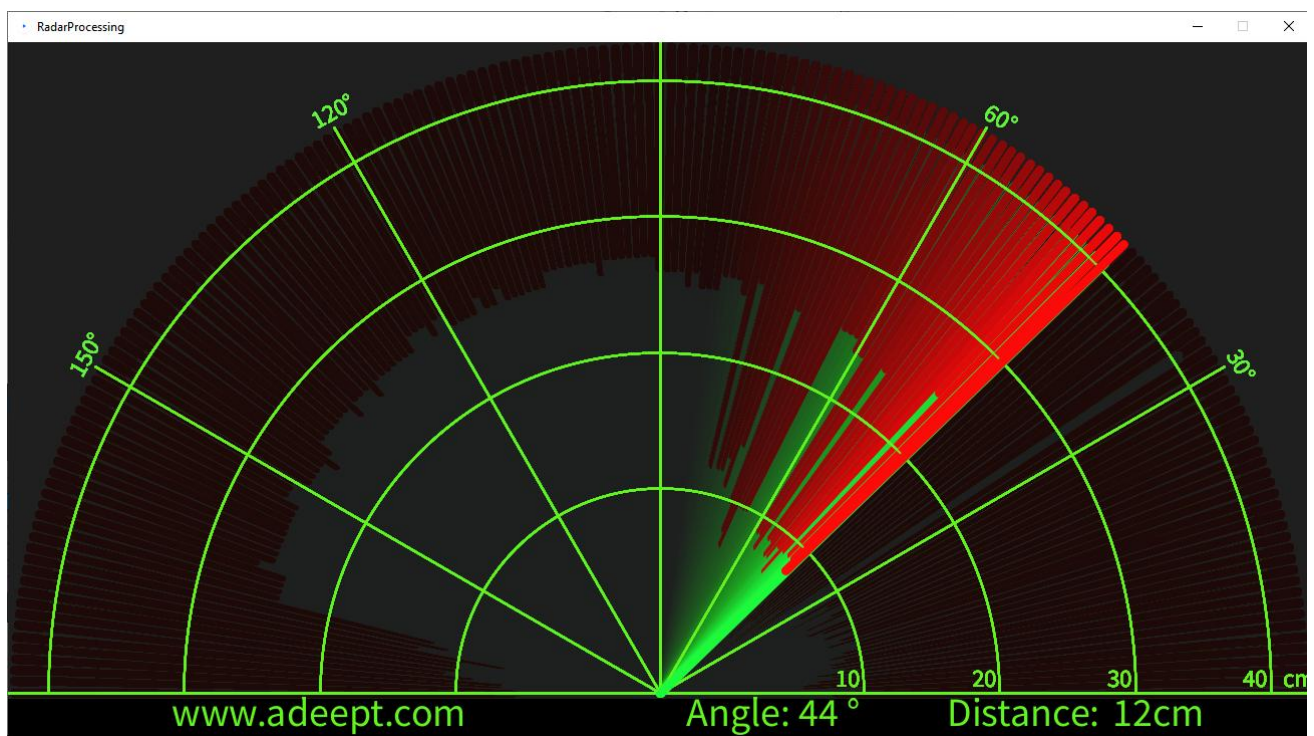
```

25 int index2=0;
26 PFont orcFont;
27 void setup() {
28
29   size (1200, 700); // ***CHANGE THIS TO YOUR SCREEN RESOLUTION***
30   size (1300, 700); // ***CHANGE THIS TO YOUR SCREEN RESOLUTION***
31   smooth();
32   // List all the available serial ports:
33   printArray(Serial.list());
34
35   // Open the port you are using at the rate you want:
36   //myPort = new Serial(this, Serial.list()[0], 9600);
37   myPort = new Serial(this,"COM5", 9600); // starts the serial communication
38   myPort.bufferUntil('.'); // reads the data from the serial port up to the character '
39 }
40 void draw() {
41
42   fill(98,245,31);
43   // calculating center blue and glow fade of the moving line

```



6. Press the D button on the handle to display the data scanned by the ultrasonic module through radar scanning.



Note: After pressing the D button in the handle, there may be a problem that the servo rotates twice and then stops, and there is no data transmission.

This is likely due to data loss during wireless data transfer. Please try pressing the D button on the controller multiple times.

If the following error message appears on the Processing IDE.



```
File Edit Sketch Debug Tools Help RadarProcessing | Proces...
RadarProcessing
25 int index2=0;
26 PFont orcFont;
27 void setup() {
28
29 size (1200, 700); // ***CHANGE THIS TO YOUR SCREEN RESOLUTION***
30 size (1300, 700); // ***CHANGE THIS TO YOUR SCREEN RESOLUTION***
31 smooth();
32 // List all the available serial ports:
33 printArray(Serial.list());
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35 // Open the port you are using at the rate you want:
36 //myPort = new Serial(this, Serial.list()[0], 9600);
37 myPort = new Serial(this,"COM5", 9600); // starts the serial communication
38 myPort.bufferUntil('.'); // reads the data from the serial port up to the character '
39 }
40 void draw() {
41
42 fill(98,245,31);
43 // simulation radar blue and grey fade of the radar face
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