

Compiling and Loading the Program to the Robot

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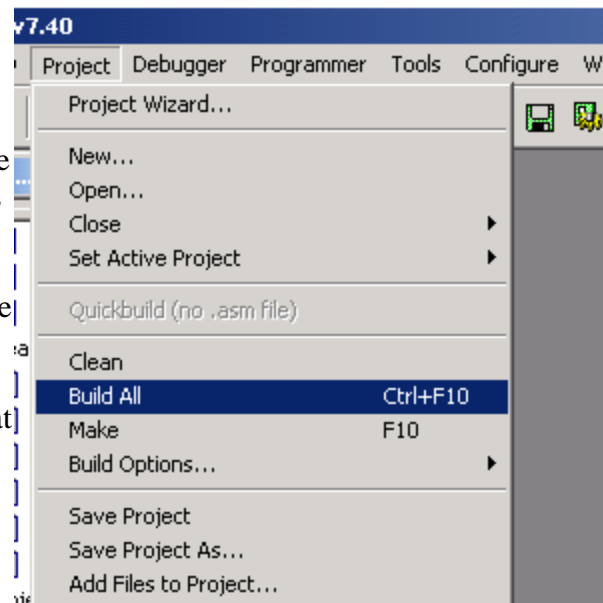
So once you have something you feel is done and is ready to load to the robot you are going to need 2 things:

Mplab

IFI_loader (<http://ifirobotics.com/docs/ifi-loader-v1-1-0.zip>)

so open up your project in mplab and go to Project -> build all

now if there is an error about how it cannot find certain libraries, this is not your fault, just go to build options (the thing circled in red) and fill in or modify the include path, the lib path and the linker path to where mcc holds them. So if the mcc folder was in the C:\ directory the include path would be C:\mcc18\include , the library path would be C:\mcc18\lib and the linker path would be C:\mcc18\lkr. If there is an error about something not being right in the code, check it out, you probably missed a semicolon or something. If there is an error that u don't know how to solve, just ask somebody or search chiefdelphi.com and search the forum to see if others have had that same error and how they fixed it.



Now once it has compiled, make sure there are NO errors. And make sure that a hex file is created. This hex file is what is going to be loaded onto the robot. So once you have the hex file, we will use to put our program onto the robot. Remember though the computer that you transfer the code from needs to have a serial port, or you need to have a usb to serial converter.

Ok, so using IFI loader, find your recently made hex file, it should be in with the rest of the project files. Turn the robot on, and press the program button, a light on the robot controller should turn orange. Now press the download button in IFI Loader, and if everything goes right, the program should be downloading to the robot. When it is done a terminal window should pop up. This is used if you have anything being printed to the screen in your code (using the command printf(“ “);). Once the program is done downloading, and the cable is unplugged, the robot will be in the user controlled mode. To test autonomous mode you need a dongle that will connect to the user controller and tell the robot to execute the autonomous commands like they would be in competition.

Now the robot is ready to be tested by the drivers of the robot.

If there are any questions about compile errors please check chief delphi's forums or ask me.