

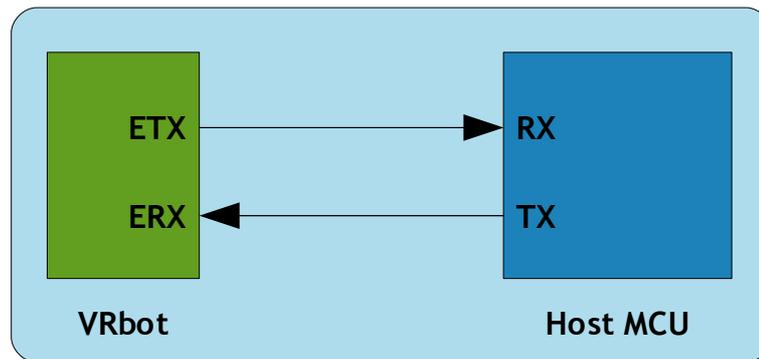
VRbot Communication Protocol

Revision 1.3

Protocol and Interface Basics

Communication with the VRbot module uses a standard UART interface compatible with 3.3-5V TTL logical levels, according to the powering voltage VCC.

A typical connection to an MCU-based host:



The initial configuration at power on is 9600 baud, 8 bit data, No parity, 1 bit stop. The baud rate can be changed later to operate in the range 9600 - 115200 baud.

The communication protocol only uses printable ASCII characters, which can be divided in two main groups:

- Command and status characters, respectively on the TX and RX lines, chosen among lower-case letters
- Command arguments or status details, again on the TX and RX lines, spanning the range of capital letters

Each command sent on the TX line, with zero or more additional argument bytes, receives an answer on the RX line in the form of a status byte followed by zero or more arguments.

There is a minimum delay before each byte sent out from the VRbot module to the RX line, that is initially set to 20 ms and can be selected later in the ranges 0 - 9 ms, 10 - 90 ms, 100 ms - 1 s. That accounts for slower or faster host systems and therefore suitable also for software-based serial communication (bit-banging).

The communication is host-driven and each byte of the reply to a command has to be acknowledged by the host to receive additional status data, using the *space* character. The reply is aborted if any other character is received and so there is no need to read all the bytes of a reply if not required.

Invalid combinations of commands or arguments are signaled by a specific status byte, that the host should be prepared to receive if the communication fails. Also a reasonable timeout should be used to recover from unexpected failures.

If the host does not send all the required arguments of a command, the command is ignored by the module, without further notification, and the host can start sending another command.

The module automatically goes to lowest power sleep mode after power on. To initiate communication, send any character to wake-up the module.

Command Details

Format of command strings accepted by the module. Please note that numeric arguments of command requests are mapped to upper-case letters (see the related section).

CMD_BREAK

'b' (62h)	Abort recognition in progress if any or do nothing
	Known issues: In firmware ID 0, any other character received during recognition will prevent this command from stopping recognition, that will continue until timeout or other recognition results.

Expected replies: [STS_SUCCESS](#), [STS_INTERR](#)

CMD_SLEEP

's' (73h)	Go to the specified power-down mode
[1]	Sleep mode (0-8): 0 = wake on received character only 1 = wake on whistle or received character 2 = wake on loud sound or received character 3-5 = wake on double clap (with varying sensitivity) or received character 6-8 = wake on triple clap (with varying sensitivity) or received character

Expected replies: [STS_SUCCESS](#)

CMD_KNOB

'k' (6Bh)	Set SI knob to specified level
[1]	Confidence threshold level (0-4): 0= loosest:more valid results 2= typical value (default) 4= tightest:fewer valid results NOTE: knob is ignored for trigger words

Expected replies: [STS_SUCCESS](#)

CMD_LEVEL

'v' (76h)	Set SD level
[1]	Strictness control setting (1-5): 1 = easy, 2 = default, 5 = hard A higher setting will result in more recognition errors.

Expected replies: [STS_SUCCESS](#)

CMD_LANGUAGE

'l' (6Ch)	Set SI language
[1]	Language (0 = English, 1 = Italian, 2 = Japanese, 3 = German)

Expected replies: [STS_SUCCESS](#)

CMD_TIMEOUT

'o' (6Fh)	Set recognition timeout
[1]	Timeout (-1 = default, 0 = infinite, 1-31 = seconds)

Expected replies: [STS_SUCCESS](#)

CMD_RECOG_SI

'i' (69h)	Activate SI recognition from specified wordset
[1]	Wordset index (0-3)

Expected replies: [STS_SIMILAR](#), [STS_TIMEOUT](#), [STS_ERROR](#)

CMD_TRAIN_SD

't' (74h)	Train specified SD/SV command
[1]	Group index (0 = trigger, 1-15 = generic, 16 = password)
[2]	Command position (0-31)

Expected replies: [STS_SUCCESS](#), [STS_RESULT](#), [STS_SIMILAR](#), [STS_TIMEOUT](#), [STS_ERROR](#)

CMD_GROUP_SD

'g' (67h)	Insert new SD/SV command
[1]	Group index (0 = trigger, 1-15 = generic, 16 = password)
[2]	Position (0-31)

Expected replies: [STS_SUCCESS](#), [STS_OUT_OF_MEM](#)

CMD_UNGROUP_SD

'u' (75h)	Remove SD/SV command
[1]	Group index (0 = trigger, 1-15 = generic, 16 = password)
[2]	Position (0-31)

Expected replies: [STS_SUCCESS](#)

CMD_RECOG_SD

'd' (64h)	Activate SD/SV recognition
[1]	Group index (0 = trigger, 1-15 = generic, 16 = password)

Expected replies: [STS_RESULT](#), [STS_SIMILAR](#), [STS_TIMEOUT](#), [STS_ERROR](#)

CMD_ERASE_SD

'e' (65h)	Erase training of SD/SV command
[1]	Group index (0 = trigger, 1-15 = generic, 16 = password)
[2]	Command position (0-31)

Expected replies: [STS_SUCCESS](#)

<i>CMD_NAME SD</i>	
'n' (6Eh)	Label SD/SV command
[1]	Group index (0 = trigger, 1-15 = generic, 16 = password)
[2]	Command position (0-31)
[3]	Length of label (0-31)
[4-n]	Text for label (ASCII characters from 'A' to '`')
Expected replies: STS_SUCCESS	

<i>CMD_COUNT SD</i>	
'c' (63h)	Request count of SD/SV commands in the specified group
[1]	Group index (0 = trigger, 1-15 = generic, 16 = password)
Expected replies: STS_COUNT	

<i>CMD_DUMP SD</i>	
'p' (70h)	Read SD/SV command data (label and training)
[1]	Group index (0 = trigger, 1-15 = generic, 16 = password)
[2]	Command position (0-31)
Expected replies: STS_DATA	

<i>CMD_MASK SD</i>	
'm' (6Dh)	Request bit-mask of non-empty groups
Expected replies: STS_MASK	

<i>CMD_RESETALL</i>	
'r' (72h)	Reset all commands and groups
'R' (52h)	Confirmation character
Expected replies: STS_SUCCESS	

<i>CMD_ID</i>	
'x' (78h)	Request firmware identification
Expected replies: STS_ID	

<i>CMD_DELAY</i>	
'y' (79h)	Set transmit delay
[1]	Time (0-10 = 0-10 ms, 11-19 = 20-100 ms, 20-28 = 200-1000 ms)
Expected replies: STS_SUCCESS	

<i>CMD_BAUDRATE</i>	
'a' (61h)	Set communication baud-rate
[1]	Speed mode (1 = 115200, 2 = 57600, 3 = 38400, 6 = 19200, 12 = 9600)
Expected replies: STS_SUCCESS	

Status Details

Replies to commands follow this format. Please note that numeric arguments of status replies are mapped to upper-case letters (see the related section).

<i>STS_MASK</i>	
'k' (6Bh)	Mask of non-empty groups
[1-8]	4-bit values that form 32-bit mask, LSB first
In reply to: CMD_MASK_SD	

<i>STS_COUNT</i>	
'c' (63h)	Count of commands
[1]	Integer (0-31)
In reply to: CMD_COUNT_SD	

<i>STS_AWAKEN</i>	
'w' (77h)	Wake-up (back from power-down mode)
In reply to: Any character after power on or sleep mode	

<i>STS_DATA</i>	
'd' (64h)	Provide command data
[1]	Training information (0-7 = training count, +8 = SD/SV conflict, +16 = SI conflict)
[2]	Conflicting command position (0-31)
[3]	Length of label (0-31)
[4-n]	Text of label (ASCII characters from 'A' to '`')
In reply to: CMD_DUMP_SD	

<i>STS_ERROR</i>	
'e' (65h)	Signal recognition error
[1-2]	Two 4-bit values that form 8-bit error code (80h = NOTA, otherwise see FluentChip error codes)
In reply to: CMD_RECOG_SI , CMD_RECOG_SD , CMD_TRAIN_SD	

<i>STS_INVALID</i>	
'v' (76h)	Invalid command or argument
In reply to: Any invalid command or argument	

<i>STS_TIMEOUT</i>	
't' (74h)	Timeout expired
In reply to: CMD_RECOG_SI , CMD_RECOG_SD , CMD_TRAIN_SD	

<i>STS_INTERR</i>	
'i' (69h)	Interrupted recognition
In reply to: CMD_BREAK while in training or recognition	

STS SUCCESS

'o' (6Fh)	OK or no errors status
In reply to: CMD_BREAK , CMD_DELAY , CMD_BAUDRATE , CMD_TIMEOUT , CMD_KNOB , CMD_LEVEL , CMD_LANGUAGE , CMD_SLEEP , CMD_GROUP_SD , CMD_UNGROUP_SD , CMD_ERASE_SD , CMD_NAME_SD , CMD_RESETALL	

STS RESULT

'r' (72h)	Recognised SD/SV command or Training similar to SD/SV command
[1]	Command position (0-31)
In reply to: CMD_RECOG_SD , CMD_TRAIN_SD	

STS SIMILAR

's' (73h)	Recognised SI word or Training similar to SI word
[1]	Word index (0-31)
In reply to: CMD_RECOG_SI , CMD_RECOG_SD , CMD_TRAIN_SD	

STS OUT OF MEM

'm' (6Dh)	Memory full error
In reply to: CMD_GROUP_SD	

STS ID

'x' (78h)	Provide firmware identification
[1]	Version identifier (0)
In reply to: CMD_ID	

Arguments Mapping

These are the characters used to represent integer values in the range -1 to 31 for command or status arguments.

ARG MIN

'@' (40h)	Minimum argument value (-1)
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ARG MAX

'`' (60h)	Maximum argument value (+31)
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ARG ZERO

'A' (41h)	Zero argument value (0)
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ARG ACK

' ' (20h)	Read more status arguments
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Communication Examples

These are some examples of actual command and status strings exchanged with the VRbot module by host programs and the expected program flow with pseudo-code sequences.

The pseudo-instruction `SEND` transmits the specified character to the module, while `RECEIVE` waits for a reply character (a timeout is not explicitly handled for simple commands, but should be always implemented if possible).

Also, the `OK` and `ERROR` routines are not explicitly defined, since they are host and programming language dependent, but appropriate code should be written to handle both conditions.

Lines beginning with a `#` (sharp) character are comments.

Please note that in a real programming language it would be best to define some constants for the command and status characters, as well as for mapping numeric arguments, that would be used throughout the program, to minimize the chance of repetition errors and clarify the meaning of the code.

See the header file *protocol.h* for sample definitions that can be used in a C language environment.

Here below all the characters sent and received are written explicitly in order to clarify the communication protocol detailed in the previous sections.

(1) Recommended wake up procedure:

```
# wake up or interrupt recognition or do nothing
# (use a timeout or max repetition count)
DO
    SEND 'b'
LOOP UNTIL RECEIVE = 'o'
```

(2) Recommended setup procedure:

```
# ask firmware id
SEND 'x'
IF NOT RECEIVE = 'x' THEN ERROR

# send ack and read status (expecting id=0)
SEND ' '
IF RECEIVE = 'A' THEN OK ELSE ERROR

# set language for SI recognition (Japanese)
SEND 'l'
SEND 'C'
IF RECEIVE = 'o' THEN OK ELSE ERROR

# set timeout (5 seconds)
SEND 'o'
SEND 'F'
IF RECEIVE = 'o' THEN OK ELSE ERROR
```

(3) Recognition of a built-in SI command:

```
# start recognition in wordset 1
SEND 'i'
SEND 'B'
# wait for reply:
```

```

# (if 5s timeout has been set, wait for max 6s then abort
# otherwise trigger recognition could never end)
result = RECEIVE

IF result = 's' THEN
    # successful recognition, ack and read result
    SEND ' '
    command = RECEIVE - 'A'
    # perform actions according to command
ELSE IF result = 't' THEN
    # timed out, no word spoken
ELSE IF result = 'e' THEN
    # error code, ack and read which one
    SEND ' '
    error = (RECEIVE - 'A') * 16
    SEND ' '
    error = error + (RECEIVE - 'A')
    # perform actions according to error
ELSE
    # invalid request or reply
    ERROR
END IF

```

(4) Adding a new SD command:

```

# insert command 0 in group 3
SEND 'g'
SEND 'D'
SEND 'A'
IF RECEIVE = 'o' THEN OK ELSE ERROR

# set command label to "ARDUINO_2009"
SEND 'g'
SEND 'D'
SEND 'A'
SEND 'M' # name length (12 characters)
SEND 'A'
SEND 'R'
SEND 'D'
SEND 'U'
SEND 'I'
SEND 'N'
SEND 'O'
SEND '_'
# encode each digit with a ^ prefix
# followed by the digit mapped to upper case letters
SEND '^'
SEND 'C'
SEND '^'
SEND 'A'
SEND '^'
SEND 'A'
SEND '^'
SEND 'J'
IF RECEIVE = 'o' THEN OK ELSE ERROR

```

(5) Training an SD command:

```
# repeat the whole training procedure twice for best results
# train command 0 in group 3
SEND 't'
SEND 'D'
SEND 'A'
# wait for reply:
# (default timeout is 3s, wait for max 1s more then abort)
result = RECEIVE

IF RECEIVE = 'o' THEN
    # training successful
    OK
ELSE IF result = 'r' THEN
    # training saved, but spoken command is similar to
    # another SD command, read which one
    SEND ' '
    command = RECEIVE - 'A'
    # may notify user and erase training or keep it
ELSE IF result = 's' THEN
    # training saved, but spoken command is similar to
    # another SI command (always trigger, may skip reading)
    SEND ' '
    command = RECEIVE - 'A'
    # may notify user and erase training or keep it
ELSE IF result = 't' THEN
    # timed out, no word spoken or heard
ELSE IF result = 'e' THEN
    # error code, ack and read which one
    SEND ' '
    error = (RECEIVE - 'A') * 16
    SEND ' '
    error = error + (RECEIVE - 'A')
    # perform actions according to error
ELSE
    # invalid request or reply
    ERROR
END IF
```

(6) Read used command groups:

```
# request mask of groups in use
SEND 'm'
IF NOT RECEIVE = 'k' THEN ERROR
# read mask to 32 bits variable
# in 8 chunks of 4 bits each
SEND ' '
mask = (RECEIVE - 'A')
SEND ' '
mask = mask + (RECEIVE - 'A') * 24
SEND ' '
mask = mask + (RECEIVE - 'A') * 28
...
SEND ' '
mask = mask + (RECEIVE - 'A') * 224
```

(7) Read how many commands in a group:

```
# request command count of group 3
SEND 'c'
SEND 'D'
IF NOT RECEIVE = 'c' THEN ERROR
# ack and read count
SEND ' '
count = RECEIVE - 'A'
```

(8) Read a user defined command:

```
# dump command 0 in group 3
SEND 'p'
SEND 'D'
SEND 'A'
IF NOT RECEIVE = 'd' THEN ERROR
# read command data
SEND ' '
training = RECEIVE - 'A'
# extract training count (2 for a completely trained command)
tr_count = training AND 7
# extract flags for conflicts (SD or SI)
tr_flags = training AND 24
# read index of conflicting command (same group) if any
SEND ' '
conflict = RECEIVE - 'A'
# read label length
SEND ' '
length = RECEIVE - 'A'
# read label text
FOR i = 0 TO length - 1
  SEND ' '
  label[i] = RECEIVE
  # decode digits
  IF label[i] = '^' THEN
    SEND ' '
    label[i] = RECEIVE - 'A' + '0'
  END IF
NEXT
```

Built-in Command Sets

In the tables below a list of all built-in commands for each supported language, along with group index (trigger or wordset), command index and language identifier to use with the communication protocol.

Trigger/Wordset	Command Index	Language			
		0	1	2	3
		English (US)	Italian	Japanese	German

0	0	robot	robot	ロボット	roboter
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1	0	action	azione	アクション	aktion
	1	move	vai	ススメ	gehe
	2	turn	gira	マガレ	wende
	3	run	corri	ハシレ	lauf
	4	look	guarda	ミロ	schau
	5	attack	attacca	コーゲキ	attacke
	6	stop	fermo	トマレ	halt
	7	hello	ciao	こんにちは	hallo

2	0	left	a sinistra	ヒダリ	nach_links
	1	right	a destra	ミギ	nach_rechts
	2	up	in alto	ウエ	hinauf
	3	down	in basso	シタ	hinunter
	4	forward	avanti	マエ	vorwärts
	5	backward	indietro	ウシロ	rückwärts

3	0	zero	zero	ゼロ	null
	1	one	uno	いち	eins
	2	two	due	ニ	zwei
	3	three	tre	サン	drei
	4	four	quattro	ヨン	vier
	5	five	cinque	ゴ	fünf
	6	six	sei	ロク	sechs
	7	seven	sette	ナナ	sieben
	8	eight	otto	ハチ	acht
	9	nine	nove	キュー	neun
	10	ten	dieci	ジュー	zehn