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Image Processing Based Semi-Automated Target Detector and Shooter

Aniket Chopade[1], Swapnil Dasarwar[2], Raviraj Khopade[3], Prof. M. M. Narkhede[4]

[1-3]Student, Dept. of Electronics and Telecommunication Engg., At Pimpri Chinchwad College of Engineering, Pune.
[4]Professor, Dept. of Electronics and Telecommunication Engg., At Pimpri Chinchwad College of Engineering, Pune.

Abstract - *With ever-growing increase in technology everything is needed to be automated. As we know currently India is not having good foreign relations with neighboring countries like China and Pakistan. These countries continuously trying to provoke war against us wherein we are losing our soldiers. Therefore, to reduce human casualties and to improve defensive systems at borderline we must upgrade our systems. Keeping this in mind this system is designed which emphasizes on fabrication of automated target detector and shooter robot.*

The primary objective of this system is to serve a wireless automated machine which is better aesthetically. The system will be based on raspberry pi processor with pi camera and computer vision for its basic purpose and will be trained for specific object or event detection in real time video and will send the signal back to controller so that necessary actions will be taken. The appropriate processor is selected for the application so that it will handle the power requirement and processing capacity of all the necessary requirements. The greatest motivation behind this project is changing technology and greatest inspiration is Boston dynamics. This system with some advancement can be used for projectile target detection in hilly areas. By the end of the project one can use this system with very ease remotely from certain radio distance to control it and find a specified target with the help of system.

Key Words: Automation, Raspberry Pi 4B, Solenoid

1.INTRODUCTION

India is a developing country. We as a country are always trying to push our limits by technological advancements. For sustaining in this era India has to bring developments in the technology as well as its self-defense capabilities. Self-defense is the important priority of our nation in 21st century. As we know currently India is not having good foreign relations with neighboring countries like China and Pakistan. These countries continuously trying to provoke war against us wherein we are losing our soldiers. Therefore, to reduce human casualties and to improve defensive systems at borderline we must upgrade our systems. The main motive of this project is to create a system which can replace humans at battlefields, which can be used remotely and which can help our nation to defend itself from threats of neighboring countries. Which is why we are designing a system which will be a prototype of real machine that can be deployed on borders to increase our defense capabilities and to reduce the casualties on the borders. The kind of robots used widely are in industries, companies and in gaming appliances. But there are very few robots working on defense. Out there on borders all that needed is continuous lookout of any unusual movements happening nearby where very less robots are happen to be effective. But what if those robots are given vision and monitoring can be done more feasibly? This system is developed such that it can see the movements happening around and wirelessly from remote location and can work efficiently without any human casualties. We know that in near future all that human work is going to be replaced by the AI powered machineries. Taking this into consideration we came up with this idea of making computer vision-based robot which works automatically for detection of specific event and take actions accordingly.

2.PROPOSED SYSTEM

The proposed system works as a normal machine does. It takes several inputs and gives the required output. The main central processing unit of robot is Raspberry Pi 4 model B. The inputs to raspberry pi are Pi camera, Power supply and trained weights from the memory card [4]. The pi camera is used for real time image and video capture and the trained weights used are generated using machine learning which will help to identifying the target [1][2]. Power supply is connected in order to work of real time image/video processing inside the controller. The power supply provided is using Li-ion batteries. The robot after processing the input produces several outputs too. After processing the video this video is then transferred to the display for user interaction.

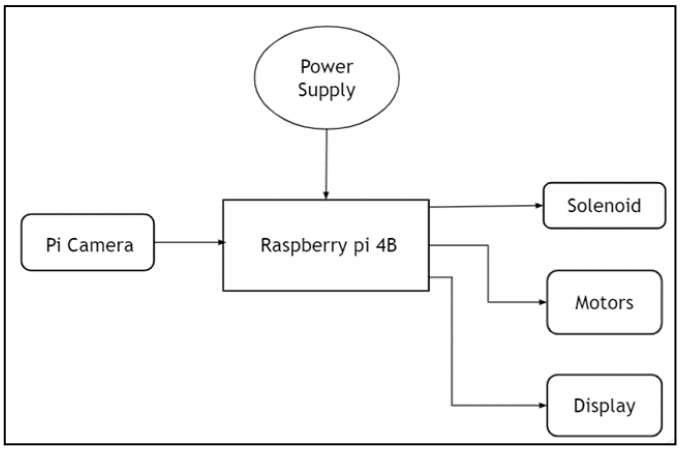

Fig -2.1: System Block Diagram

Another output is in terms of motor actuation which is used for robot to align itself such that it aligns with the target. After aligning itself with target and having proper actuation with help of push pull solenoid to shoot target.

3.METHODOLOGY

The robot starts taking manual control action and starts tracing the target in camera as soon as it turns on. The robot keeps on searching the target until it detects target into the camera screen, as soon as the target is found anywhere in pi camera the robot performs following operations in order.

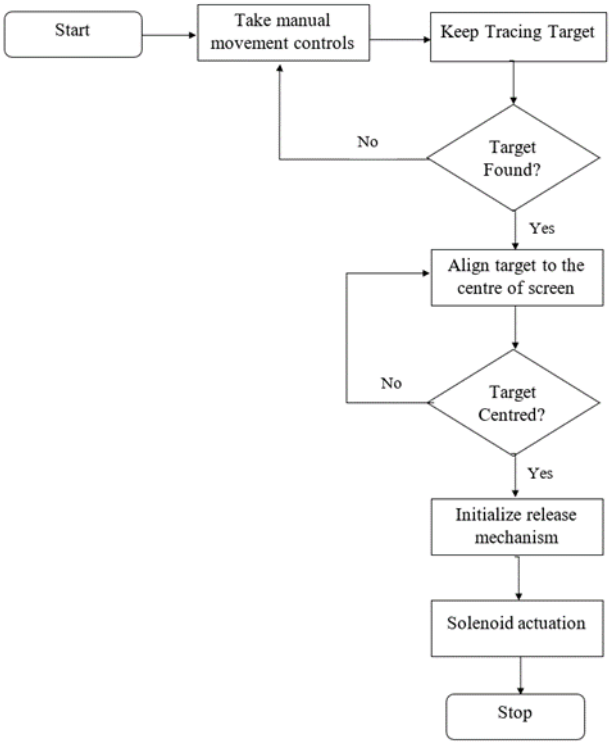

Fig -3.1: System Flowchart

- Identify the target.
- Aligning robot such that the target is centred.
- Give feedback to controller and wait for further instructions.

When controller confirms the target and releases shoot command then the power is applied to the shooter through pneumatic actuator and target is been hit.

During the target tracing the system will take actions as per the image processing algorithm. As we are using YOLOv4-tiny as our processing algorithm. System will perform following steps.

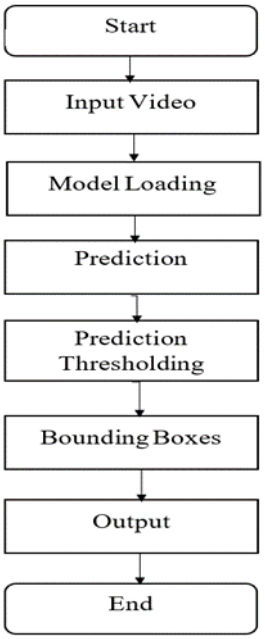

Fig -3.2: Target Detection Flowchart

- As per the Fig -3.2 as soon as system starts tracing target it will take input video for processing via Pi Camera.
- It will then load the model which we have trained to detect the particular target. These model loading consists of weights and cfg(configuration) file.
- After model loading system starts prediction. It starts to predict whether the input video has the target/object which is to be traced.
- There is a prediction thresholding which should be set so that if the prediction rate crosses the threshold, then system can be sure if that is the required target.
- After crossing threshold value, it creates bounding boxes around the target with certain amount of confidence level so that target will be easily visible on the display.
- These bounding boxes will act as an output which will be provided to the user. This real time processing of video makes it easier to identifying potential threats.

4. SPECIFICATIONS

4.1 Raspberry Pi 4 Model B

Fig -4.1: Raspberry Pi 4Model B

Fig -4.1 shows Raspberry Pi 4 Model B which is advanced version of Raspberry Pi 4 series. It is basically the CPU of our robot which will carry out all the necessary actions required for object detection and motor actuation. It also supports dual band 2.4GHz and 5GHz which will be used for signal transfer to and from the Raspberry Pi to user interface such as signaling motor actuation and retrieving the live camera footage. The I/O port of Raspberry Pi is used for interfacing the Pi camera which is compatible with Raspberry Pi. For memory storage purpose it has been given Micro SD port in which OS and necessary code and weights can be store.

4.2 Pi Camera

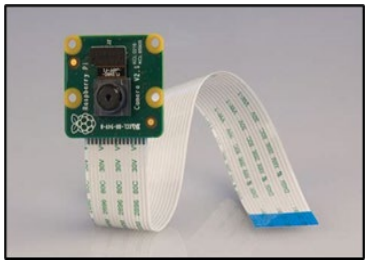

Fig -4.2: Pi Camera

Fig -4.2 shows Pi camera which is used to identify the target using image processing algorithm. So, the pi camera is used for providing the source of images to the Raspberry Pi. Pi camera of 5MP is used to capture better image.

4.3 DC and Servo Motors

Fig -4.3.1: DC Motor

Simple DC motors which convert electrical energy into mechanical energy are used to drive the robot. These motors are taken in application considering the power requirement by the motors and the power source used in the project. The power source used is sufficient to drive DC motors. 4 DC motors are used as 4 different wheels of the robot which will be having 4-wheel drive mechanism.

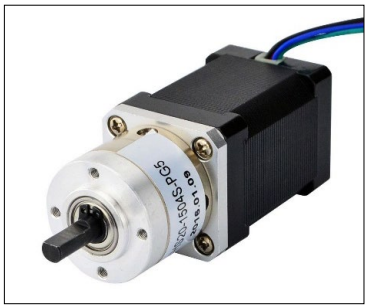

Fig -4.3.2: Servo Motor

A stepper motor acts in steps and hence can provide very precise movement. Also, the motors position can be commanded and hold at one step using the magnetic locking mechanism which provide high torque for stability purpose. To carry out the vertical movement of robot body to align itself towards the target stepper motor is used.

4.4 Push-Pull Solenoid

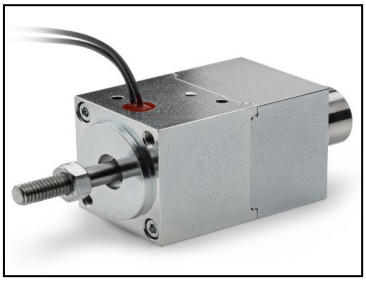

Fig -4.4: Push-Pull Solenoid

Fig -4.4 shows a Push – Pull Solenoid which is an Electro-mechanical device which is used to hit the shooting material giving an impulse to it in the forward direction to hit the target.

4.5 Power Supply Batteries

Fig -4.5: Power Supply Batteries

Fig -4.5 shows Lithium-ion batteries or Li-ion batteries. These batteries are commonly used because of its low density and better efficiency as compared to Lead acid batteries which are heavy and more hazardous to nature. Li-ion batteries are used as the base power supply for the robot system and Raspberry Pi controller.

5. ADVANTAGES

- System can replace Humans on the battlefield and therefore helps in reducing the human casualties on borders.
- Detection is improved due to real time image processing capabilities.
- Accuracy of hitting the target is increased.
- Human error can be reduced due to human-machine interface.
- System can be controlled over long distance.

6. CONCLUSION

The proposed system can be able to detect specific target objects with the help of video processing algorithm. Once the target object is detected, system controller shoots aiming at the same targeted object. Maximum accuracy is achieved by using solenoid-based subsystem. This proposed system consisting of wireless communication provides long range contactless operability to the users. Hence, this system in future can replace human- beings and therefore help in reducing human casualties on the border.

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