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This report is compiled in L^AT_EX, originally developed by Leslie Lamport, based on Donald Knuth's T_EX. The main text is written in *Computer Modern* pt 11, designed by Donald Knuth. Flowcharts and diagrams are made using Microsoft Visio.



5th Semester

School of Information and
Communication Technologies
Electronics and IT

Fredrik Bajers Vej 7B
9220 Aalborg

<http://www.sict.aau.dk/electronics-and-it>

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??

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Interacting with the Surroundings

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Project Group:

??

Synopsis

Participants:

Amalie V. Petersen
Julien Brehin
Mads R. Gotthardsen
Niels Skov Vestergaard
Romaric Destremau
Thomas Rasmussen

??

Supervisor:

??

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Pages: ??

Appendices: ??

Concluded: 17/12/2015

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Preface

Preface Here

Text by:

Amalie V. Petersen

Julien Brehin

Mads Gotthardsen

Niels Skov Vestergaard

Romaric Destremau

Thomas Rasmussen



Part I

Preanalysis



1 | Introduction

More and more robots appear in everyday life. Automatic vacuum cleaners and floor washers are getting widespread, as the technology is becoming cheaper and better. The vacuum cleaners have matured to a level, where they are been considered for saving man-hours in the elderly care sector.

Outside the walls of our homes lays the next weekly hurdle: Mowing the lawn. A known way to handle this, is to pay the neighbour's teenager to do it. Unfortunately they grow up and move out, leaving the lawns in the residential neighbourhoods behind.

Luckily engineers have stepped in, and provided a more long-term solution: Robotic lawn mowers.

1.1 Robotic lawn mowers

Several manufacturers of electrical gardening machines have started selling robotic lawn mowers in the recent years. In general they use one of two strategies when cutting the lawn:

- Random direction mowers
- Parallel line mowers

Mowers using the random direction strategy will drive in a straight line until a guard wire or an obstacle is detected. They will then turn in a random direction, and continue. See *Figure: ??*

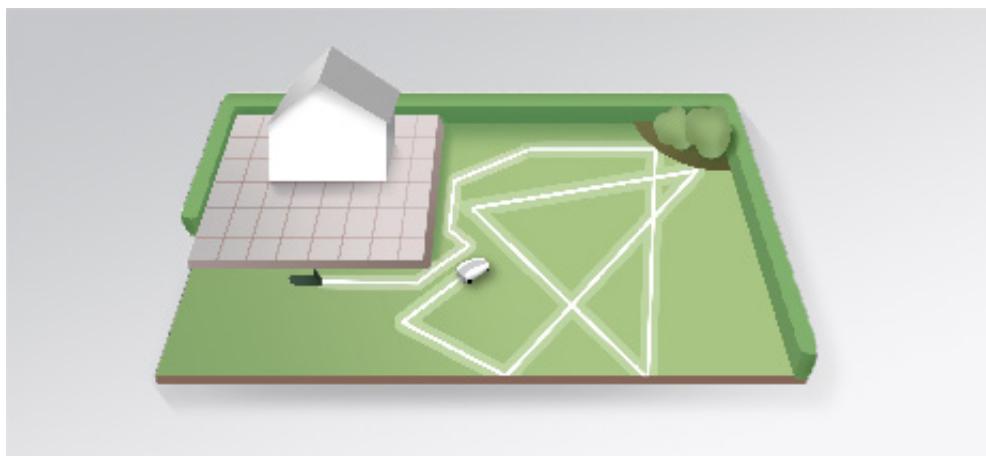


Figure 1.1: Random cut system [source:Bosch]



When the battery is nearly discharged, the mower will follow the guard wire back to the base station for recharging.

Parallel line mowers use a more intelligent control algorithm to optimize the mowing. After an initial learning run, following the guard wire around the lawn to be mowed, it will map the lawn, and cut in parallel lines, see *Figure: ??*. The advantage of this strategy efficiency, as the lawn mower will not run over the same spots more than once. According to Bosch, a given lawn can be mowed up to 30% faster with their Logicut system.

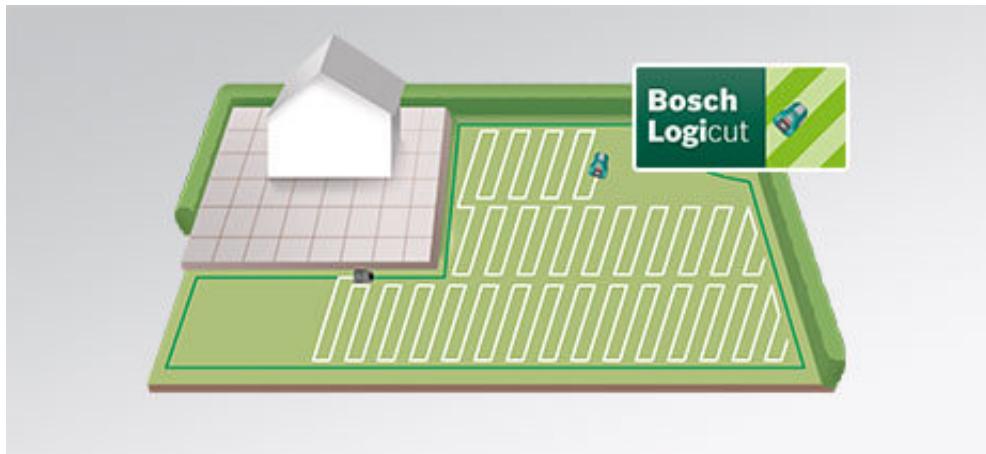


Figure 1.2: Bosch Logicut system [source:Bosch]

Common for both systems is the guard wire, which has to be placed around the lawn and anywhere the lawn mower is not allowed to go, like flower beds, swimming pools, etc.

This brings us to the problem with existing products.

1.2 Problems with existing robotic lawn mowers

All commercially available robotic lawn mowers require a guard wire placed around the lawn. This can either be placed at the surface, and be held in place by pegs, or dug down below the surface. The guard wire must be routed around flower beds, etc. as well, see *Figure: ??*

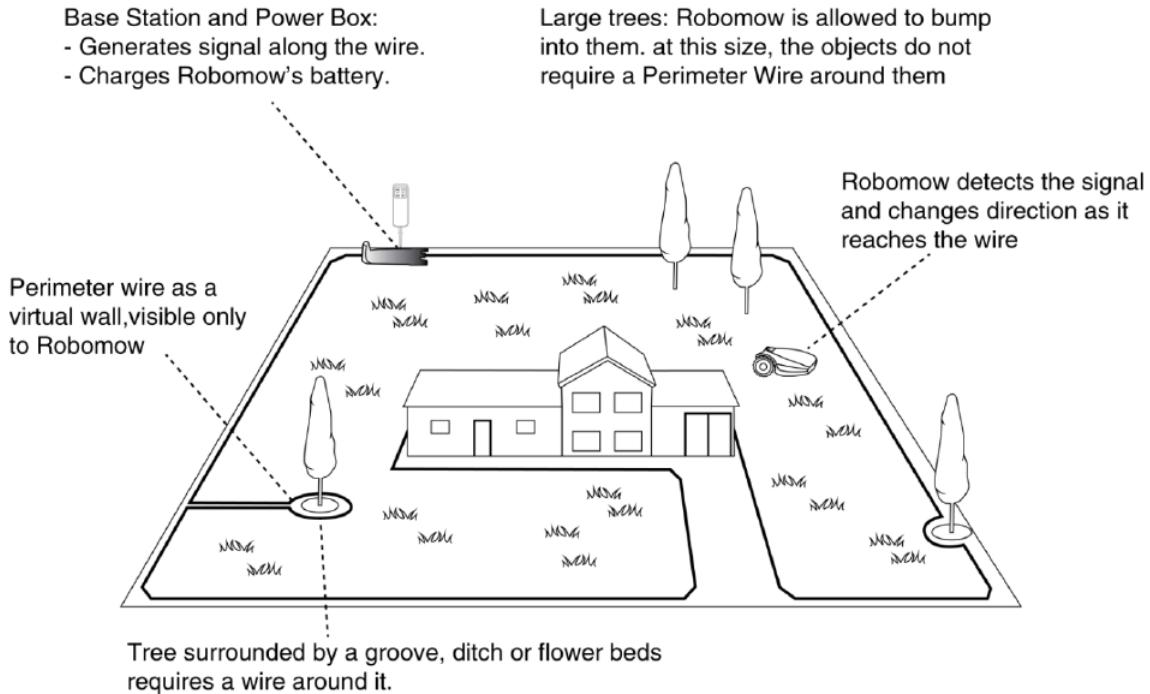


Figure 1.3: Guard wire installation [source:Robomow]

The use of the guard wire for guiding the mower back to the charging station presents another potential problem: in a garden with many restricted areas, the guard wire could get very long. This could therefore make the journey home long, compared to a more direct route. This again uses more battery power, that instead could have been used for actually mowing the lawn.

This will be the motivation for the project: to avoid the work routing a wire around the garden, and as a bonus get more work done on a battery charge, by not wasting power following the wire home.

Then, the question is: What other solutions could be used to get the lawn mower to go where it has to go?

One first step could be to keep track of where it is in real-time.

1.3 The Games on Track (GoT) system

We were provided with the *Games on Track GT-Position* system as a start to be able to determine the lawn mower's position in space.



Figure 1.4: Games on Track GT-Position package [source:Games on Track]

It is composed of four different parts both hardware and software :

- A tracked module, which emits ultra-sound waves. It should be placed on the lawn mower itself while taking care, that the emitting cell is not obstructed by anything.
- Beacons or receivers, placed around the area the lawn mower will move in. Depending on the terrain, anywhere from 2 to more than 20 of these can be used: The more is placed, the more accuracy can be obtained to fight against any ambient noise.
- The central system, which calculates the distance of the tracked module to each beacon, and transmits it to the computer via USB in regular intervals.
- The GoT software aggregates the received positions throughout time, and can be used to draw a map of the terrain (the lawn), and to determine the absolute position of the tracked module.

-Resolved- is t
enough? Answe
It is according
the GoT site (s
reference in La
comments)

GoT was originally designed for train modelling, but it is easily adaptable for any use of position tracking and seems a good choice, at first, for our autonomous lawn mower. But, why not use a satellite based positioning system ?

1.4 Satellite based positioning systems vs GoT

The reasons why satellite positioning system won't be used in our project are mainly related to accuracy over price ratios and to energy consumption.

Wrong reasons
GPS vs GoT, e
rated below

Indeed, these kinds of system like GPS or GLONASS would require a dedicated chip to put on the final system. The problem then would be the lack of precision. Although, there are some

-To be reviewed
again- GPS use
very little power
depending on t
accuracy needed



cheap standard GPS chips (around USD 10), these only reach around 1 meter of precision in the most ideal situations. On the other hand, the best GPS chips can achieve precisions up to a few millimeters when combined with different augmentation systems (algorithms for instance), but they end up being highly expensive (usually thousands of dollars). They are not generally intended for public use.

be reviewed
- Only applies
to cheap solutions,
standard GPS can
achieve mm level, but
is relatively expensive.
This is what
we are trying to re-
place with GoT, as
it is a lot cheaper
than diff-GPS

be reviewed
- nope, it's just
a radio receiver, uses
very little power

Moreover, if we add up the slow bit rates satellites can achieve, the signal amplifiers on the receiver, plus all the position calculations and possible augmentation systems, the total energy consumption would quickly rise, thus reducing the lawn mower autonomy, which is not desirable.

Indeed, the design of a product has no real value if no one is interested in using it. This is why choices made during this project have to be made in accordance with the final user's expectations.

1.5 Potential consumer expectations

Usually, we can think of a few priorities consumers will have when buying a product, whatever it is, and some more specific to technical products.

Here for instance, the autonomy of the vehicle (both in energy and for the navigation), and the overall cost should be considered. The GoT system itself has a cost (USD 606.00 for a basic package) beyond anything a normal customer would probably pay for a lawn mower. But despite that, it appears, at first, to be a good solution for us in terms of accuracy and energy consumption compared to GPS-like systems which are even more expensive for the same accuracy.

These are the types of preliminary considerations that will influence this design process for an autonomous lawn mower.



2 | Design Consideration

In this chapter the system is designed with a top-down approach. First a use-case of the functionalities in the system is described, in order to give an overall view of what the system must be able to do. Hereafter, constraints set by time limitations as well as a focus on the main scope of the project, in regards to the prototype, is considered. Based on the use-case description and the prototype constraints the requirements for the systems prototype are listed.

2.1 Use-case design

To give an overall view of what the system should be able to do, a UML use-case diagram is used to consider and describe the main functionalities and operators in the system, see *Figure: 2.1*.

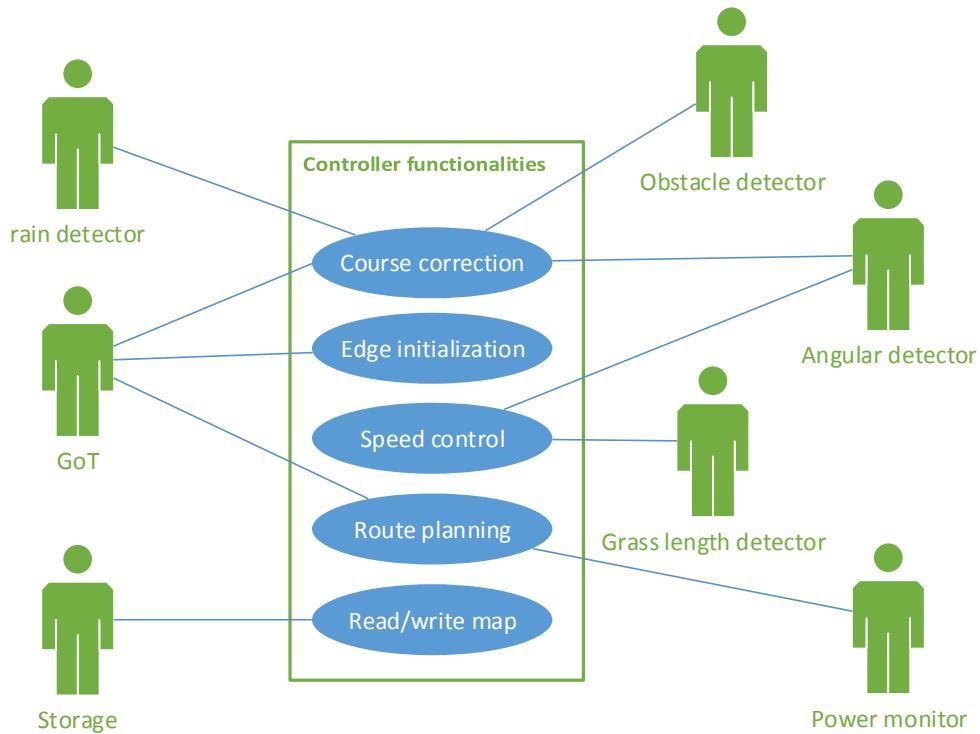


Figure 2.1: Use-Case Diagram

The main purpose of the system is to automatically navigate in a specific area which is confined by the *edge initialization* functionality. This functionality handles the marking of the areas edges. The functionality is only used in the initialization process of the system. The concept is to only use the functionality after the GoT system has been positioned in the area. The consumer then takes the system around the edges of the grass, while the GoT system tracks its positions. It is therefore only necessary to reinitialize the system, if the GoT satellites has been moved. While the edge is being tracked, the *edge initialization* uses the *read/write map*



functionality to store the information collected, in storage.

The route in which the lawn mower is to navigate, in the specified area, is provided by the functionality *route planning*. *Route planning* uses the information, about the specific area, which is collected from the storage, to plan the most optimal route. Furthermore the *route planning* needs information about the systems power level to insure the functionality is considering if the system needs charging and therefore have to return to the charging station at some point on the route.

The *read/write map* functionality as described earlier, handles the communication with storage. Hence it stores information, received from the *edge initialization* and collects information from storage when the functionality *route planning* needs it.

To insure the system is moving with a desired speed (in a straight line and in a turn) or a speed which is fitted to the height of the grass, detected with the *grass length detector*, a *speed control* functionality is necessary in the system to control the motors. To insure the *speed control* can deliver the desired speed an *angular sensor* is utilized.

The last functionality, *course correction* is used when the system strays of the path calculated by *route planning* or if the path gets blocked. The obstacle which is blocking the route is detected by the sensor *obstacle detector*. Furthermore the GoT system and the *angular detector* will detect if the system is not on the desired path, or if the system starts to slip. Also, if it starts to rain, which is detected by the *rain detector*, the system has to return to the charging station. Finally, the *course correction* sends the calculated data to the functionality *speed control*.

The overall functionalities of what the system must be able to do has been described. Now the different constraints on the system will be considered and the project prototype should be established.



2.2 Prototype Constraints

Before the prototype can be established, some considerations has to be made in respect to the time limitations and the main scope of this semester. The aim of the project is to create a functional proof of concept prototype of an automated lawn mower. The following section includes a brief description of the technology on which the prototype is constructed, along with argumentation for eliminated functionalities.

2.2.1 Technology Base

The technology which has been provided for the prototype is a tracked vehicle, seen on *Figure: 2.2*. The vehicle comes with a brushed DC motor which provides power for rotation of the wheels, connected with the belts, and a servo motor which utilize breaks, connected to the wheels, to control the ratio of the differential steering. Furthermore the tracked vehicle includes two hall sensors, one by each belt, which keeps track of the speed, of the belts, by measuring pulses from magnets mounted on the front wheels. The testing will take place in Aalborg University Vicon Room, where the GoT system is installed and calibrated with the appurtenant transmitter, which is mounted on the tracked vehicle during test.

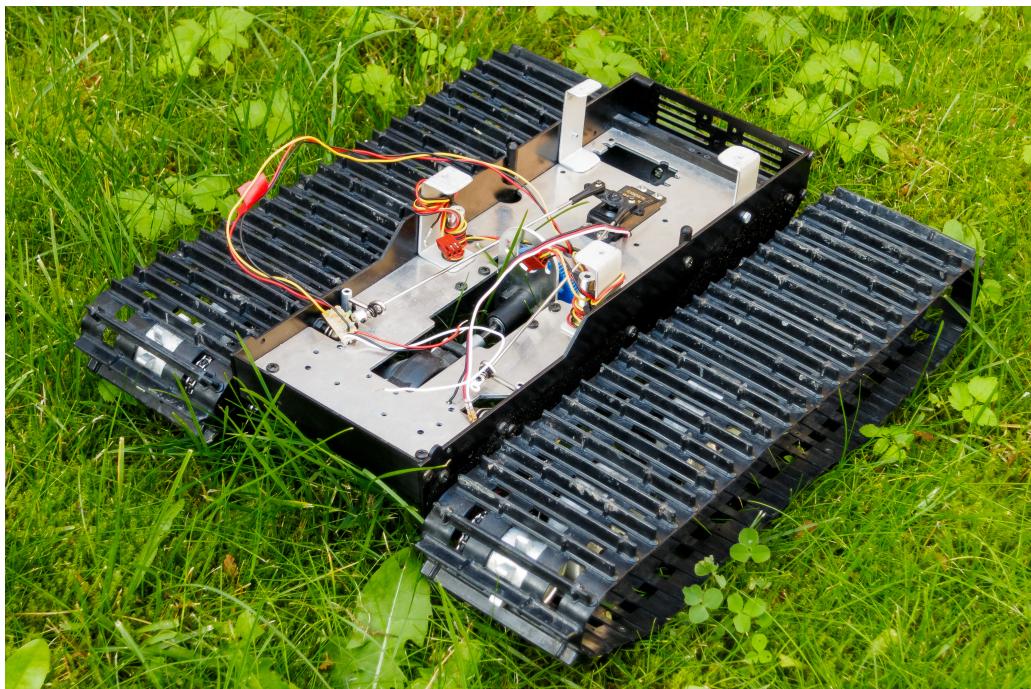


Figure 2.2: The provided belt vehicle

[datasheet of the vehicle](#)



2.2.2 Grass Length Detection

Detection of the grass length to control the speed of the lawn mower thus ensuring an evenly cut lawn, is a submodule which can be added at any time. Since it is not fatal for a working system and might even be unnecessary depending on time between each mowing of the lawn, it is decided to exclude this functionality from the initial design.

2.2.3 Rain Sensor

As the lawn mower is supposed to work outside, it is important to consider that it may be raining, and that an electronic device can be affected by those environmental issues. Even if the electrical part is waterproofed, there is a mechanical threat, a rain sensor could then warn the system to order the vehicle to get back in time. It is possible to build the vehicle aware of those issues and add mechanical modules to secure it. However, the prototype will only be tested indoor, so this type of sensor will not be necessary in a prototype design.

2.2.4 Obstacle Avoidance

The lawn movers path might not always be clear, there could be some garden tools, tables or chairs, or people walking in it. The vehicle should be aware of what is in front of it at any time, to correct its path and get around the obstacle if necessary. To avoid this the sensor could be a pushing button to detect a solid strong object, or an ultrasound detector if the object is breakable. As the aim of the project is to control the path of the vehicle by using angular positioning sensors, a proximity sensor will not be included. Static objects could be registered on the map to avoid these issues.

Furthermore the edge mapping functionality will not be included in the project which instead will focus on a quadratic map predefined in the test room.

2.2.5 Power Monitoring

Power monitoring could be implemented by measuring the voltage across the batteries, to ensure that the lawn mower is not running out of power, and to ensure the vehicles calculated route passes the charging station before the power runs too low. This and the charging station will not be in the prototype, since it is beyond the scope of the project this semester and is not crucial for a working prototype.

2.2.6 Prototype

(to be continued)



Part II

Design & implementation



Part III

Test & conclusion

Appendix

A | The Games on Track GT-position system

The Games on Track GT-Position system, shortened GoT, is a position system which uses radio-waves and ultrasound to locate the object. The system is build up by three types of hardware components: the transmitter, the satellites and the master. The transmitter and the satellites send the information in all directions, with a 360 degree signal.

The GoT System does not work if it is not close enough of the satellites, or if the battery runs low, or if there is some interference by another signal or by an object between them.

Transmitter

The transmitter component is placed on the object, which needs to be located. The time at which each ultrasound bursts are sent from the transmitter to the satellites, is transmitted by radiowaves to the master. The frequency of the bursts is .

The transmitter component runs on 2 AA-batteries and therefore does not need an external power-source.

Note: The transmitter does not receive any information.

what is the frequency?

Satellites

The satellites components are placed around the area where the object, with the transmitter on it, has to be located. The satellites assignment is to search for the ultrasound waves, which the transmitter is emitting, and send a radiowave signal to the master as soon as they receive the burst. To be able to calculate the exact position of the transmitter and then the object, a minimum of three satellites is necessary. However, more can be added to the system for more reliability or to cover a larger area. To work at a high efficiency, they should be placed 1 to 2 meters apart and not on a single line. But to cover a bigger area, they can be placed up to a distance of 5 meters between them, although this would affect the measurement and thereby make it less reliable. Each satellite have a maximum range of 8 meters and as seen on *Figure: 2.3*, the three satellites should be placed in each others reach. The satellites needs between 14 to 20 volt DC. Thus, making the satellites able to be powered through a computer charger or by a panel solar for example is necessary.

What kind of "radio-waves" does the satellite transmit data to the master?

Appendix A. The Games on Track GT-position system

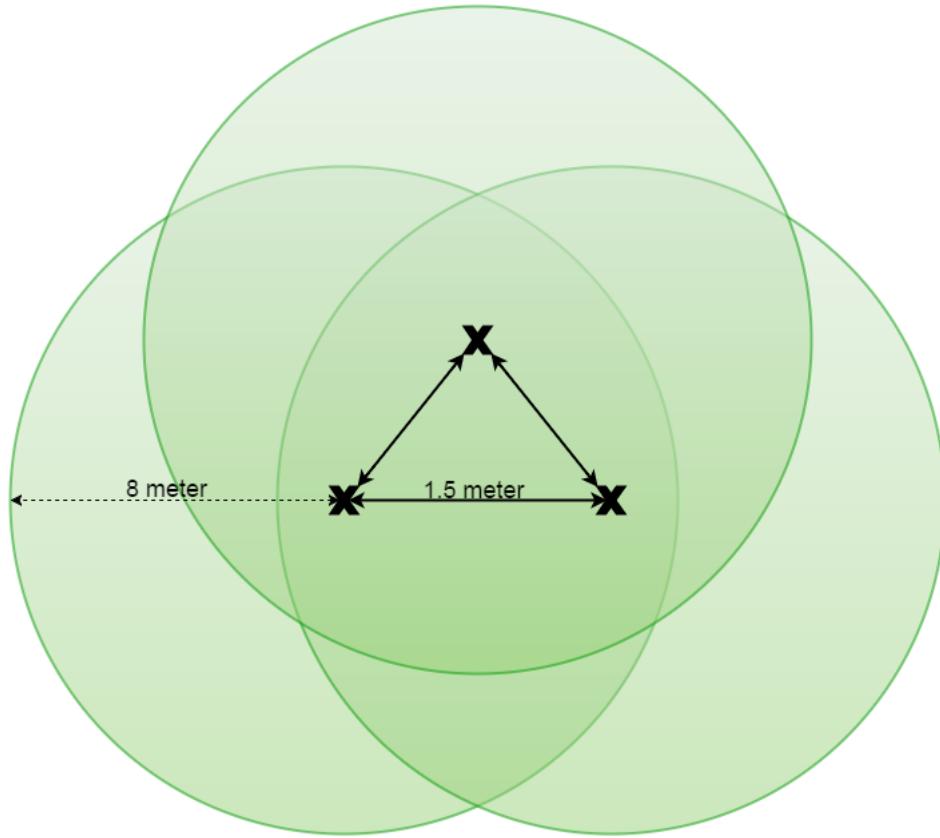


Figure 2.3: Example on a standard setup for the satellites (increase size of text in figure)

Master

The master is a receiver which should be connected to a computer. The masters assignment is to receive the data transmitted from the individual satellites and the transmitter, and relay it directly to the connected computer. The master is powered through a USB cable, between the master and the computer.

The information is transmitted back by another system, called Xbee.

Computer

The program on the computer, which handles the information received from the master, uses the data to calculate the position of the transmitter. This is done with a method call Trilateration. Trilateration is a way of calculating a position, in a three-dimensional space, from three distances of known locations, with the help of spheres, circles and triangles. The distances are caculated with the time when each satellites by a comparison to the transmitter send the signal. Therefore it is necessary for the system to have atleast three satellites, as mentioned earlier. With additional satellites a check up can be performed to ensure the position of the transmitter is correct. Trilateration does not work if the three known points are on a single line therefore the satellites should be placed in a triangle.

If the satellites have been moved, it is necessary to recalibrate the system. This is done with a

Appendix A. The Games on Track GT-position system

calibration triangle. The calibration triangle is made of three points on a flat surface and have a distance of 40 to 200 centimeters between them. One of the points on the calibration triangle is made the origin (0,0,0) of the new coordinate system. Another point on the triangle will then be call (X,0,0), in which the line between the first point and the second point will become the X-axis. The last point will be call (X,Y,0) and will determine in which way the positive Y-axis will go. The surface which the calibration triangle is placed on, will be the XY-plan, where Z will go vertically, defining the (x,y,z) coordinates. The distance between the three points is measured and put into the program. Thereafter, the transmitter is placed in the three point, with (0,0,0) first and (X,Y,0) last. When the transmitter is placed in a point, the satellites measure the distance between them and the transmitter. From those information, the program can calculate the position of each satellites, with the help of trilateration.

B | Motor Tests

B.1 Armature Resistance

Name: Group 510

Date: 30/09 - 2015

Purpose

The purpose of the test is to measure the Armature resistance R_a .

Setup

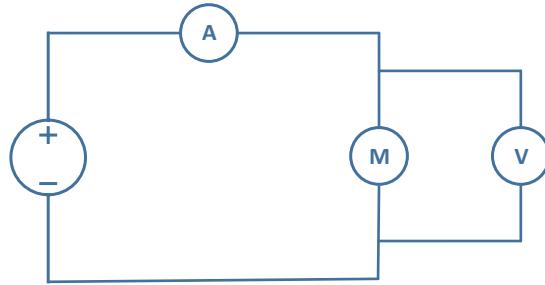


Figure 2.4: Use-Case Diagram

List of Equipment

Example of list of equipment:

Instrument	AAU-no.	Type
Multimeter 1	60764	Fluke 189 True RMS
Multimeter 2	60769	Fluke 189 True RMS
Power Supply (0 - 32 V) (0 - 10 A)	77076	Ea - ps 7032 - 100
Clamp for fixing the motor	03039	

Procedure

1. Turn on the two multimeters and choose Voltage and Ampere setting respectively.
2. Fix the motor shaft so it does not turn.
3. Choose the first current value (0.5 A) on the current limiting of the power supply.
4. Turn on the power supply and adjust the current limiting in accordance with the ampere meter.

5. Repeat the two previous steps for each measurement of 0.5 A increments up to 5 A.
6. Switch the poles of the power supply and repeat the measurements in the negative direction.

Results

Input (A)	Output (V)
-5.0	-0.07
-4.5	-0.14
-4.0	-0.20
-3.5	-0.27
-3.0	-0.36
-2.5	-0.43
-2.0	-0.54
-1.5	-0.59
-1.0	-0.65
-0.5	-0.71

Input (A)	Output (V)
0.5	0.16
1.0	0.34
1.5	0.53
2.0	0.62
2.5	0.64
3.0	0.75
3.5	0.78
4.0	0.80
4.5	0.83
5.0	0.88

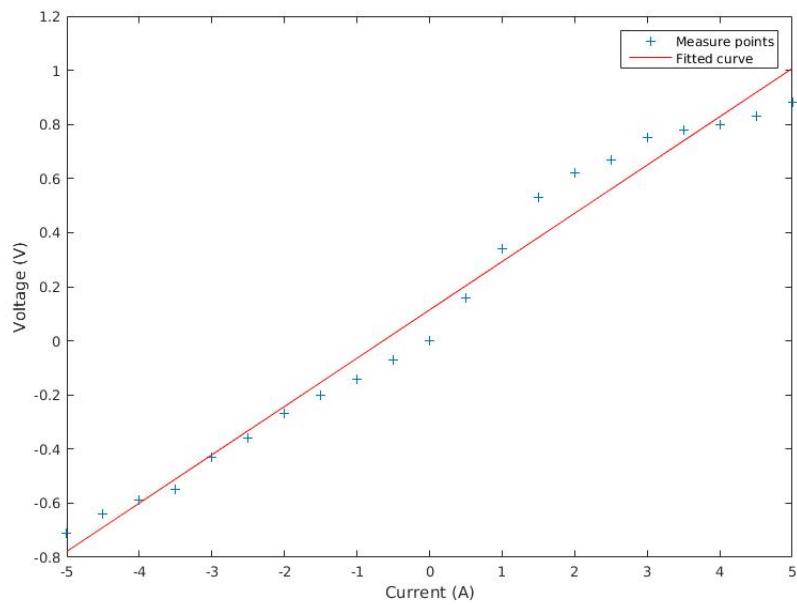


Figure 2.5: Plot of test results

Appendix B. Motor Tests

The slope of the fitted curve yields: $R_a = 0.17\Omega$

B.2 Armature Inductance

Name: Group 510

Date: 30/09 - 2015

Purpose

The purpose of the test is to measure the Armature inductance L_a .

Setup

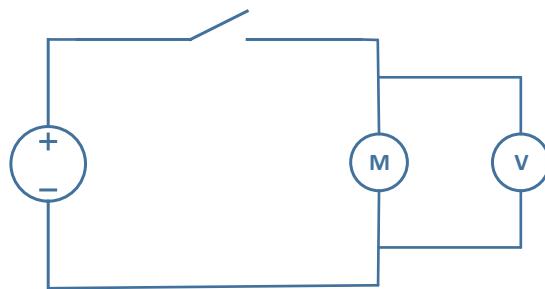


Figure 2.6: Use-Case Diagram

List of Equipment

Instrument	AAU-no.	Type
Power Supply (0 – 32 V) (0 – 10 A)	77076	Ea - ps 7032 - 100
AC/DC Current Clamp (Output: 100 mV/A)	78550	FLUKE i30s
Oscilloscope	64672	Agilent DSO6034A
Clamp for fixing the motor	03039	

Procedure

1. Fix the motor shaft so it does not turn.
2. Start with the power supply disconnected and turn on the oscilloscope.
3. On the oscilloscope press the "mode"-key choose the "normal"-option and push the "single"-key.
4. To prevent false triggering on the oscilloscope set the trigger value to
5. To give the motor a pulse of 5 V, put the power supply to 5 V and connect it.
6. Insert a USB-pin in the oscilloscope and press the save key to extract the data.

Appendix B. Motor Tests

Results

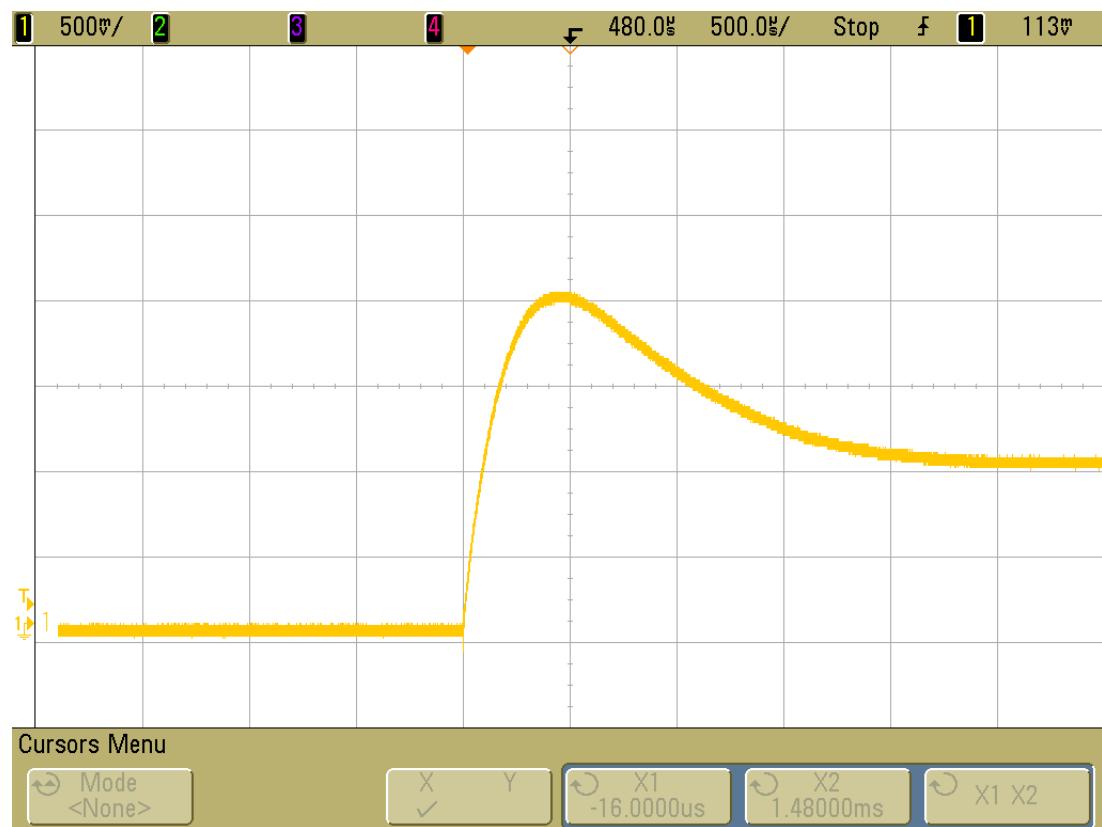


Figure 2.7: Plot of test results

B.3 Tachometer Constant

Name: Group 510

Date: 30/09 - 2015

Purpose

The superpose of the test is to measure verify that tachometer constant (in V) is 0.030 multiplied by the motor constant.

Setup

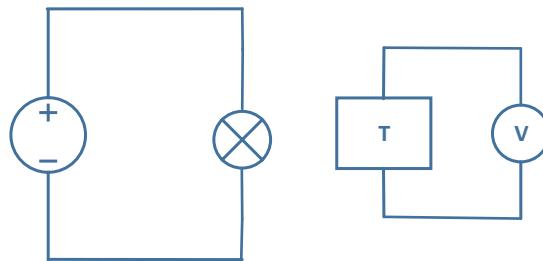


Figure 2.8: Use-Case Diagram

List of Equipment

Instrument	AAU-no.	Type
Power Supply (0 – 32 V) (0 – 10 A)	77076	Ea - ps 7032 - 100
Multimeter	60764	Fluke 189 True RMS
Torque sensor	08772	Icom
Optical tachometer	08246	Shimpo DT-205

Procedure

1. Adjust voltage of power supply till you reach 6 V on the multimeter over the tachometer.
2. Measure the RPM with the Optical tachometer.

Results

Measured: 1933 RPM We use the measured RPM to verify a tachometer constant of 0.03:

$$\frac{1933}{60} \cdot 2 \cdot \pi \cdot 0.03 = 6.07 \approx 6 \quad [\text{V}] \quad (2.1)$$

B.4 Generator Constant

Name: Group 510

Date: 30/09 - 2015

Purpose

The purpose of the test is to find the generator constant K_e by measuring the motor voltages, currents and velocities, in several steady states.

Setup

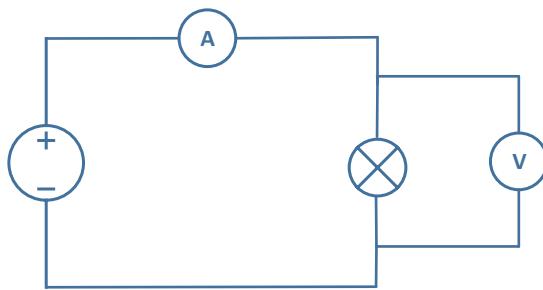


Figure 2.9: Use-Case Diagram

List of Equipment

Instrument	AAU-no.	Type
Multimeter 1	60764	Fluke 189 True RMS
Multimeter 2	60769	Fluke 189 True RMS
Power Supply (0 – 32 V) (0 – 10 A)	77076	Ea - ps 7032 - 100
Optical tachometer	08246	Shimpo DT-205

Procedure

1. Turn on the two multimeters and put them in ampere and voltage mode respectively.
2. Apply 1 V by use of the voltage mode multimeter
3. Read out the current value from the ampere mode multimeter
4. Read out RPM of the motor using the optical tachometer.
5. Repeat the past 3 steps up to 7 V in 1 V increments.

Results

Input (V)	Output (A)	Output (RPM)
1	1.7	3684
2	2.2	8063
3	2.6	12021
4	3.3	16746
5	4.1	21966
6	4.8	26420
7	5.6	31447

Appendix B. Motor Tests

B.5 Motor Constant

Name: Group 510

Date: 30/09 - 2015

Purpose

The purpose of this test is to measure the motor constant K_t .

Setup

Test setup

List of Equipment

Instrument	AAU-no.	Type
Multimeter 1	60764	Fluke 189 True RMS
Multimeter 2	60769	Fluke 189 True RMS
Power Supply (0 – 32 V) (0 – 10 A)	77076	Ea - ps 7032 - 100
Torque sensor	08772	Icom

Procedure

1. Fix the motor shaft so it does not turn.
2. Turn on the two multimeter in current and voltage mode respectively.
3. Start by setting the power supply at 1 A current limiting.
4. Turn on the supply and note the voltage across the torque sensor.
5. Repeat the previous two steps up to 10 A with 1 A increments.

Results

Input (A)	Output (V)
1	0.08
2	0.08
6	0.15
7	0.15
8	0.15
10	0.18

Moment of Inertia

Name: Group 510

Date: 30/09 - 2015

Purpose

The purpose of this test is to find the moment of inertia I , by measuring the motor velocity as a function of time.

Setup

Test setup

List of Equipment

Instrument	AAU-no.	Type
Oscilloscope	64672	Agilent DSO6034A
Power Supply (0 – 32 V) (0 – 10 A)	77076	Ea - ps 7032 - 100
Optical tachometer	77087	Compact

Procedure

1. Turn on the oscilloscope.
2. On the oscilloscope press the "mode"-key choose the "normal"-option, set the trigger to "falling edge".
3. To prevent false triggering on the oscilloscope set the trigger value to
4. Turn on the power supply at 7 volt.
5. Press "single"-key on oscilloscope and cut the power of the motor.
6. Insert a USB-pin in the oscilloscope and press the save key to extract the data.

Appendix B. Motor Tests

Results



Figure 2.10: Plot of test results

B.6 Time Constant and Gain

Name: Group 510

Date: 30/09 - 2015

Purpose

The purpose of this test is to find the time constant τ and gain, by measuring the step response of the motor.

Setup

Test setup

List of Equipment

Instrument	AAU-no.	Type
Oscilloscope	64672	Agilent DSO6034A
Power Supply (0 – 32 V) (0 – 10 A)	77076	Ea - ps 7032 - 100
Optical tachometer	77087	Compact

Procedure

1. Turn on the oscilloscope.
2. On the oscilloscope press the "mode"-key choose the "normal"-option, set the trigger to "rising-edge".
3. To prevent false triggering on the oscilloscope set the trigger value to
4. Press "single"-key on oscilloscope.
5. Turn on the power supply at 5 volt.
6. Insert a USB-pin in the oscilloscope and press the save key to extract the data.

Appendix B. Motor Tests

Results

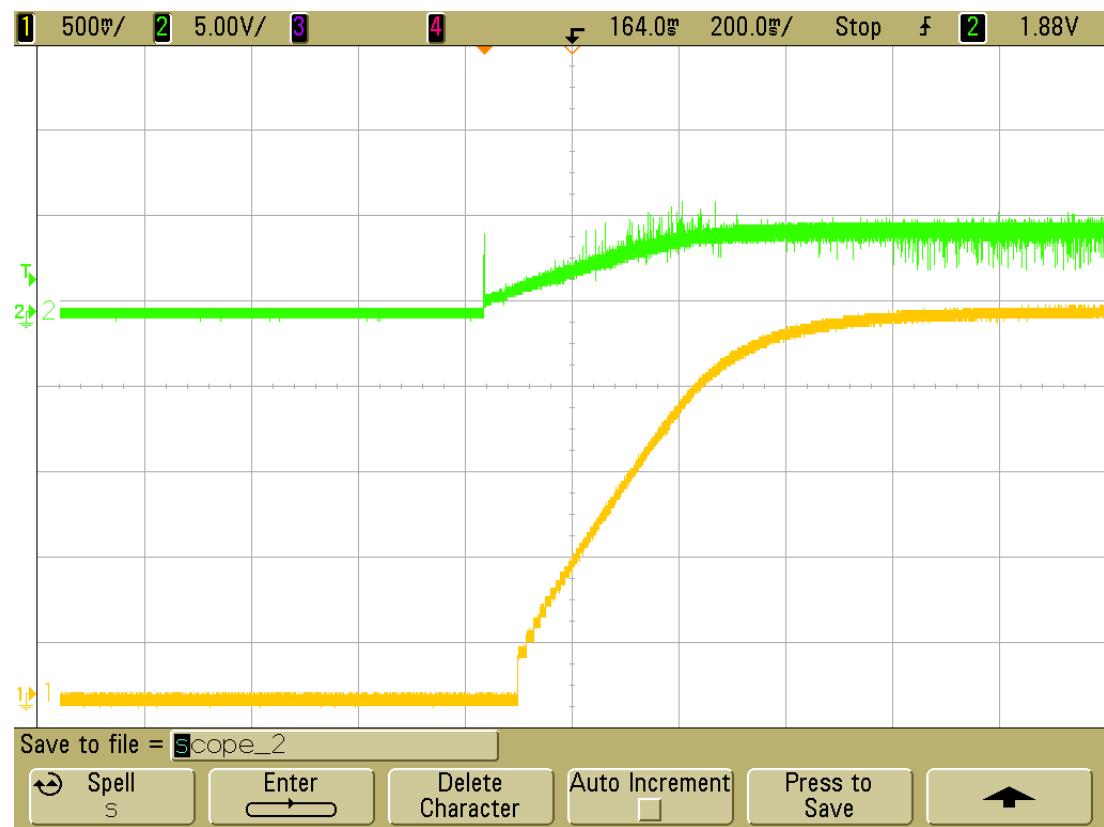


Figure 2.11: Plot of test results

Todo list

■ -Resolved– is two enough? Answer: It is according to the GoT site (see reference in LaTeX comments)	5
■ Wrong reasons for GPS vs GoT, elaborated below	5
■ –To be reviewed again– GPS uses very little power -> depending on the accuracy needed...	5
■ –To be reviewed again– Only applies to cheap solutions, differential GPS can go to mm level, but is extremely expensive. This is what we are trying to replace with GoT, as it is a lot cheaper than diff-GPS	6
■ –To be reviewed again– nope, it's just a radio receiver, uses almost no power	6
■ –Resolved– insert price approximation here - not so true actually	6
■ datasheet of the vehicle	9
■ what is the frequency?	13
■ What kind of "radio waves" does the sallite transmit data to the master?	13