

**1. Project Name:** User and Self Controlled Land Rover(USLR)

**2. Project Proposal:** User can control this rover by giving instruction through input. But if the rover detects any obstacle in front of it, it automatically changes its direction to avoid the obstacle. If there is no way out then it halts automatically. User can restart it after it stalls.

**3. Specification of Input/ Output/Control Signal:** The rover can move to 3 direction:

Front, Right and Left. It Also Halts.

Here we are using 3 external input:

$x, D0, D1$ .

$x$  is the input we get from obstacle detector

If  $x=0$ , It detects no obstacle

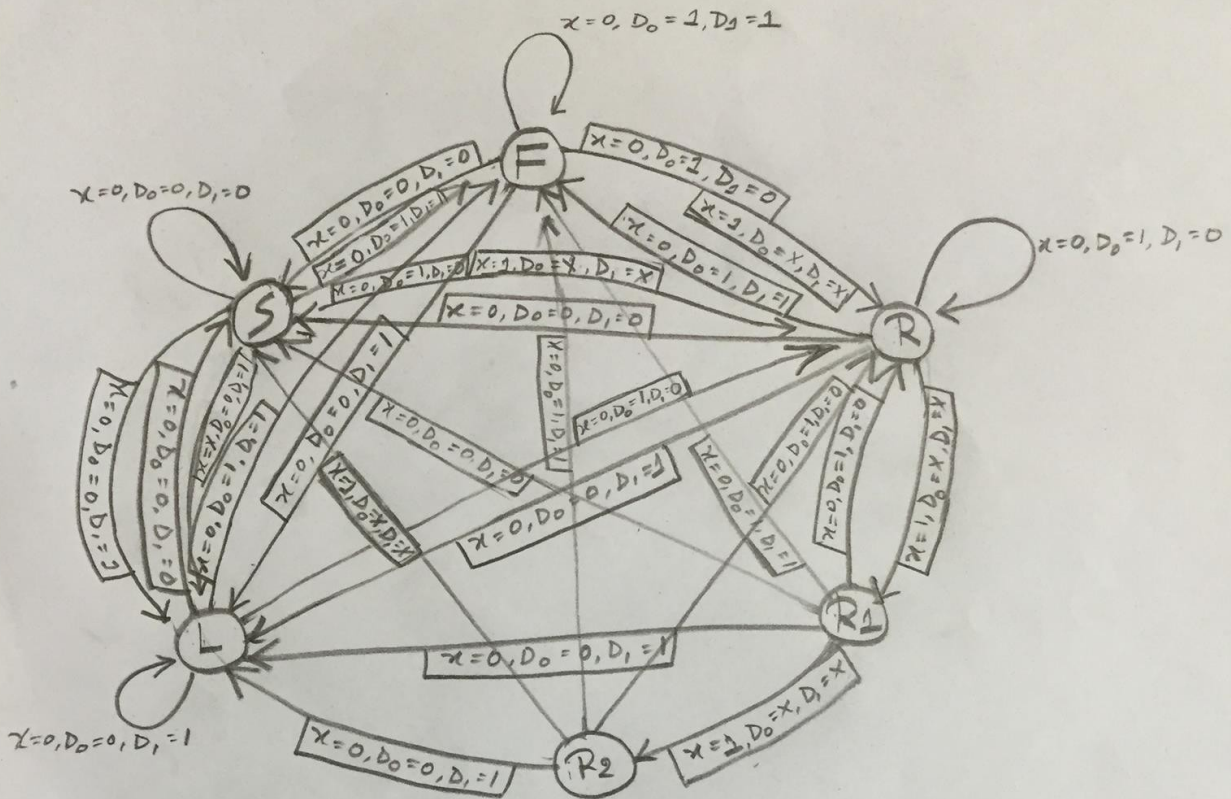
If  $x=1$ , It detects obstacle

$D0, D1$  input is given by user. The Combinations are:

	$D0$	$D1$
Forward:	1	1
Right :	1	0
Left :	0	1
Stall :	0	0

The States used in State Diagram are

Forward:	1	1	1
Right :	1	1	0
Left :	0	1	1
Stall :	0	0	0
$R1$ :	1	0	1
$R2$ :	0	1	0



State

Forward : 111

Right : 110

Left : 011

Stall : 000

R<sub>1</sub> : 101

R<sub>2</sub> : 010

User input

	D <sub>0</sub>	D <sub>1</sub>
Forward :	1	1
Right :	1	0
Left :	0	1
Break :	0	0

#### 4.Truth Table:

Previous				Ext. Input			Next				Flip-flops		
Symb ol	A	B	C	D0	D1	x	A	B	C	Symb ol	D(A)	D(B)	D(C)
S	0	0	0	0	0	0	0	0	0	S	0	0	0
S	0	0	0	0	0	1	1	1	0	R	1	1	0
S	0	0	0	0	1	0	0	1	1	L	0	1	1
S	0	0	0	0	1	1	1	1	0	R	1	1	0
S	0	0	0	1	0	0	1	1	0	R	1	1	0
S	0	0	0	1	0	1	1	1	0	R	1	1	0
S	0	0	0	1	1	0	1	1	1	F	1	1	1
S	0	0	0	1	1	1	1	1	0	R	1	1	0
XXXX	0	0	1	0	0	0	X	X	X	XXXX	X	X	X
XXXX	0	0	1	0	0	1	X	X	X	XXXX	X	X	X
XXXX	0	0	1	0	1	0	X	X	X	XXXX	X	X	X
XXXX	0	0	1	0	1	1	X	X	X	XXXX	X	X	X
XXXX	0	0	1	1	0	0	X	X	X	XXXX	X	X	X
XXXX	0	0	1	1	0	1	X	X	X	XXXX	X	X	X
XXXX	0	0	1	1	1	0	X	X	X	XXXX	X	X	X
XXXX	0	0	1	1	1	1	X	X	X	XXXX	X	X	X
R2	0	1	0	0	0	0	0	0	0	S	0	0	0
R2	0	1	0	0	0	1	0	0	0	S	0	0	0
R2	0	1	0	0	1	0	0	1	1	L	0	1	1
R2	0	1	0	0	1	1	0	0	0	S	0	0	0
R2	0	1	0	1	0	0	1	1	0	R	1	1	0
R2	0	1	0	1	0	1	0	0	0	S	0	0	0
R2	0	1	0	1	1	0	1	1	1	F	1	1	1
R2	0	1	0	1	1	1	0	0	0	S	0	0	0
L	0	1	1	0	0	0	0	0	0	S	0	0	0
L	0	1	1	0	0	1	1	1	0	R	1	1	0
L	0	1	1	0	1	0	0	1	1	L	0	1	1
L	0	1	1	0	1	1	1	1	0	R	1	1	0
L	0	1	1	1	0	0	1	1	0	R	1	1	0
L	0	1	1	1	0	1	1	1	0	R	1	1	0
L	0	1	1	1	1	0	1	1	1	F	1	1	1
L	0	1	1	1	1	1	1	1	0	R	1	1	0
XXXX	1	0	0	0	0	0	X	X	X	XXXX	X	X	X
XXXX	1	0	0	0	0	1	X	X	X	XXXX	X	X	X
XXXX	1	0	0	0	1	0	X	X	X	XXXX	X	X	X
XXXX	1	0	0	0	1	1	X	X	X	XXXX	X	X	X
XXXX	1	0	0	1	0	0	X	X	X	XXXX	X	X	X
XXXX	1	0	0	1	0	1	X	X	X	XXXX	X	X	X
XXXX	1	0	0	1	1	0	X	X	X	XXXX	X	X	X

XXXX	1	0	0	1	1	1	X	X	X	XXXX	X	X	X
R1	1	0	1	0	0	0	0	0	0	S	0	0	0
R1	1	0	1	0	0	1	0	1	0	R2	0	1	0
R1	1	0	1	0	1	0	0	1	1	L	0	1	1
R1	1	0	1	0	1	1	0	1	0	R2	0	1	0
R1	1	0	1	1	0	0	1	1	0	R	1	1	0
R1	1	0	1	1	0	1	0	1	0	R2	0	1	0
R1	1	0	1	1	1	0	1	1	1	F	1	1	1
R1	1	0	1	1	1	1	0	1	0	R2	0	1	0
R	1	1	0	0	0	0	0	0	0	S	0	0	0
R	1	1	0	0	0	1	1	0	1	R1	1	0	1
R	1	1	0	0	1	0	0	1	1	L	0	1	1
R	1	1	0	0	1	1	1	0	1	R1	1	0	1
R	1	1	0	1	0	0	1	1	0	R	1	1	0
R	1	1	0	1	0	1	1	0	1	R1	1	0	1
R	1	1	0	1	1	0	1	1	1	F	1	1	1
R	1	1	0	1	1	1	1	0	1	R1	1	0	1
F	1	1	1	0	0	0	0	0	0	S	0	0	0
F	1	1	1	0	0	1	1	1	0	R	1	1	0
F	1	1	1	0	1	0	0	1	1	L	0	1	1
F	1	1	1	0	1	1	1	1	0	R	1	1	0
F	1	1	1	1	0	0	1	1	0	R	1	1	0
F	1	1	1	1	0	1	1	1	0	R	1	1	0
F	1	1	1	1	1	0	1	1	1	F	1	1	1
F	1	1	1	1	1	1	1	1	0	R	1	1	0

### 5.Simplification:

K-Map:

D(A):

ABC/D0 D1 x	000	001	011	010	100	101	111	110
000	0	1	1	0	1	1	1	1
001	1	X	X	X	X	X	X	X
011	0	0	0	1	1	1	1	1
010	x	0	0	0	0	1	1	0
100	1	x	x	x	x	x	x	x
101	x	0	0	0	0	1	1	0
111	1	0	0	1	1	1	1	1
110	0	0	0	1	1	1	1	1

$$D(A) = D0x + BCD0 + ABD0 + A'B'x + A'B'D0 + A'B'C + AB'C' + BCD1x' + ABD1x' + ABCx'$$

D(B) :

ABC/D0 D1 x	000	001	011	010	100	101	111	110
000	0	1	1	1	1	1	1	1
001	X	X	X	X	X	X	X	X
011	0	1	1	1	1	1	1	1
010	0	0	0	1	1	0	0	1
100	x	x	x	x	x	x	x	x
101	0	1	1	1	1	1	1	1
111	0	1	1	1	1	1	1	1
110	0	0	0	1	1	0	0	1

$$D(B) = Bx + D1x + D0x + Cx$$

D(C) :

ABC/D0 D1 x	000	001	011	010	100	101	111	110
000	0	0	0	1	0	0	0	1
001	X	X	X	X	X	X	X	X
011	0	0	0	1	0	0	0	1
010	0	0	0	1	0	0	0	1
100	x	x	x	x	x	x	x	x
101	0	0	0	1	0	0	0	1
111	0	0	0	1	0	0	0	0
110	0	1	1	1	0	1	1	1

$$D(C) = D1x' + AC'x$$