

# DEVELOPMENT OF AN INTELLIGENT, REMOTE / SELF-DRIVING CAR

*An IAESTE Internship Project Report submitted by*

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**DEPARTMENT OF ELECTRICAL AND ELECTRONICS  
ENGINEERING**



**Karunya INSTITUTE OF TECHNOLOGY AND SCIENCES**

(Declared as Deemed to be University under Sec.3 of the UGC Act, 1956)

**A CHRISTIAN MINORITY RESIDENTIAL INSTITUTION**

AICTE Approved & NAAC Accredited

**AUGUST 2018**



## **BONAFIDE CERTIFICATE**

This is to certify that this report entitled, “ **CREATING AND DEVELOPING OF THE INTELLIGENT ROBOT, REMOTE / SELF-DRIVING CAR**”, is a bonafide work of the following candidate from Gdansk University of Technology, Poland, who carried out the IAESTE Internship project work under my supervision during the academic year 2018-19 / **Summer 2018**.

**BARTŁOMIEJ BORZYSZKOWSKI (IS18ET019)**

Dissertation submitted in partial fulfillment of the requirements for the  
completion of the

**IAESTE INTERNSHIP PROJECT**

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## ACKNOWLEDGEMENT

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At the outset I express my gratitude to our eminent Professors – **Prof. D.Sc. Ph.D. M.Sc.E.E. Jerzy Wtorek** – Dean of the Faculty of Electronics, Telecommunications and Informatics and **Prof. D.Sc. Ph.D. M.Sc.E.E. Zdzisław Kowalczyk** – Head of the Department of Decision Systems and Robotics of **Gdansk University of Technology**, Poland for helping me in getting the Internship in India.

I thank **IAESTE Poland**, all the members of association and **Gradient AI Science Club** for their engagement, dedication and support in the project.

I wish to thank with deep sense of acknowledge to the Founders and Management of **Karunya Institute of Technology & Sciences**, Coimbatore for extending all facilities, providing me the educative infrastructure and learning ambience, which motivated me to a great extent.

I wish to express my sincere thanks to **Dr. J. Dinesh Peter**, Associate Professor, Head – IAESTE and **Dr. P. Subha Hency Jose**, Professor & Head of the Department of Instrumentation Engineering for their excellent encouragements in course of this work.

I take immense pleasure in conveying my thanks and deep sense of gratitude to my Supervisor **Dr. K. Rajasekaran**, Professor, for his exhilarating supervision, timely suggestions and encouragement during all phases of this work. Also, I would like to thank all the Teaching faculty members and Supporting staff of our department for advising me whenever in need, co-operating with me and arranging the necessary facilities.

I would like to convey gratitude to my **Parents** whose support was always with me. Last but not the least I would like to thank my **Friends and Others** who directly or indirectly helped me in successful completion of this work.

## **Abstract**

Self-driving cars are vehicles in which human drivers are not required to take control to safely operate the vehicle. Also known as autonomous or „driverless” cars, they combine various sensors and software to control, navigate, and drive the vehicle. Self-driving technology is becoming increasingly common and could radically transform our transportation system (and by extension, our economy and society). The costs and benefits of self-driving cars are still largely hypothetical but in the past several years autonomous driving technologies have made a significant develop, giving a number of perspectives for the further progress.

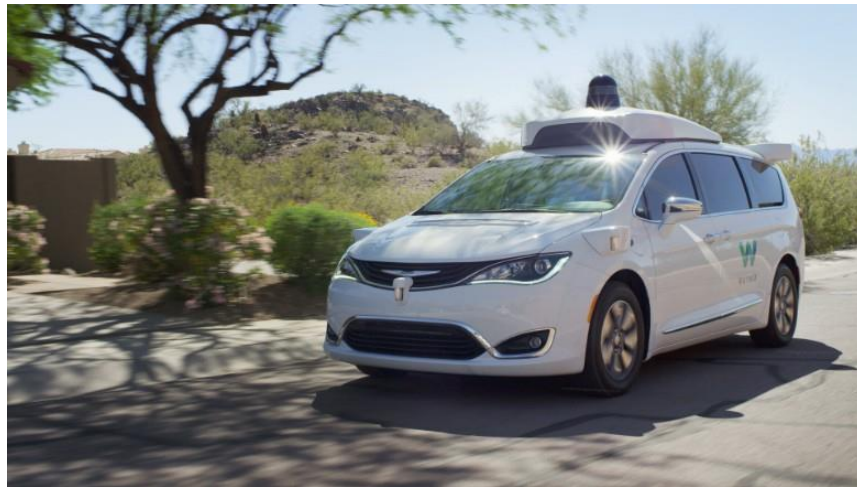


*Figure 1: Stanford Cart (1961) – the first „autonomous” vehicle*

The idea of intelligent vehicle is multi-level, complex and contains a big number of different aspects. More information is needed to fully assess how autonomous cars impact drivers, the economy, equity environmental and public health. Recently, thanks to the artificial intelligence and deep learning methods, software engineers are able to develop solutions which give an answer for the big number of questions and difficulties.

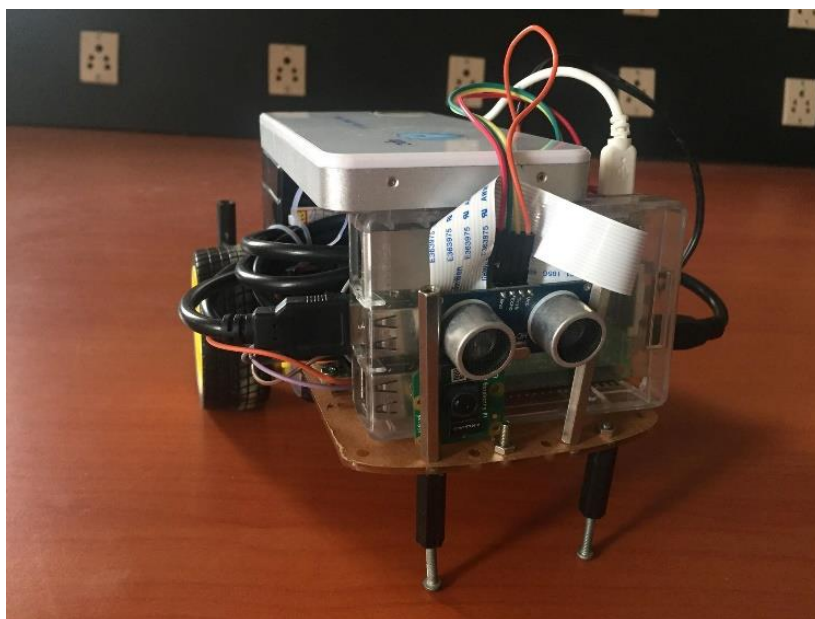
As a result people create cars having different levels of intelligence and working with a diverse systems, sensors and environments. Partially-autonomous vehicles may require a human driver to intervene if the system encounters uncertainty or if the user simply wants to steer; fully-autonomous vehicles may not even offer a steering wheel.

Self-driving cars can be further distinguished as being „connected” or not, indicating whether they can communicate with other vehicles and/or infrastructure, such as next generation traffic lights.



*Figure 2: Waymo/Google – one of the most advanced self-driving cars*

To make the development of self-driving cars easier, low cost, more accessible and prosperous small size models are widely used for the testing purposes. This solution guarantee the possibility to write the software working in the same way as in the real size models, compare the results and eliminate potential mistakes.



*Figure 3: Intelligent Car project by Bartłomiej Borzyszkowski*

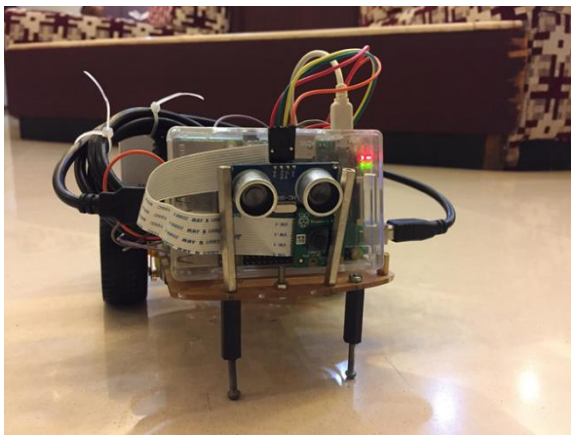


## Aim of the work

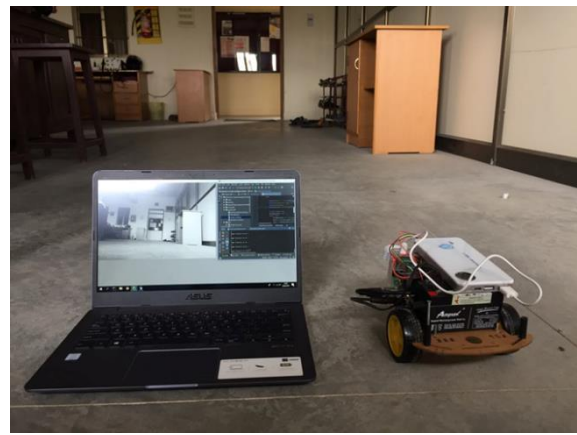
The aim of this project is to develop the model of partially-autonomous vehicle and reach the full-autonomous after future extensions.

The goal of the research is to design the construction of the intelligent car by using the Raspberry Pi, Arudino, ultrasonic sensor, camera and motor driver. Moreover, to write and develop the intelligent software using Python and C/C++ languages and design the „client – server” architecture between the used devices.

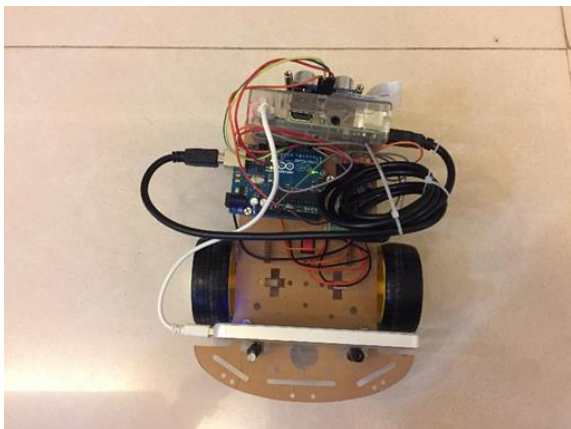
## Robot overview



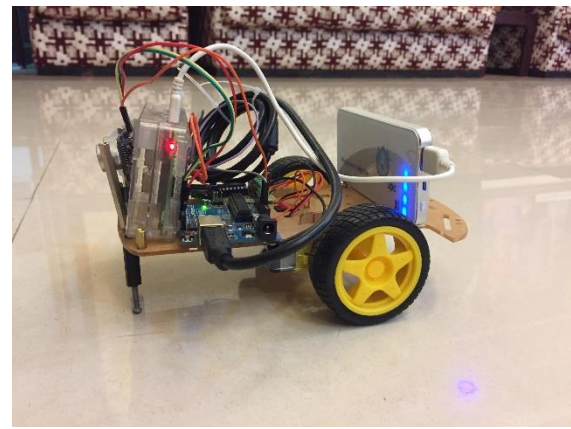
*Figure 1: Front*



*Figure 2: Back and display*



*Figure 3: Top*



*Figure 4: Side*

## Project repository

The complete project repository, including the software, programs and libraries, multimedia and sources (videos and pictures from the laboratory), explanation of the project, schemes, problem solutions, robot construction and description of every particular device in the project is free and open to access, available on the GitHub profile under the link below:

[github.com/Borzyszkowski/Robotics-in-India-Intelligent-Robot](https://github.com/Borzyszkowski/Robotics-in-India-Intelligent-Robot)

The screenshot shows the GitHub repository page for 'Borzyszkowski / Robotics-in-India-Intelligent-Robot'. The repository is forked from 'hamuchiwa/AutoRCCar'. It has 0 Watchers, 0 Stars, and 813 Forks. The repository is on the 'master' branch, which is 50 commits ahead and 28 commits behind 'hamuchiwa:master'. The repository contains 84 commits, 1 branch, 0 releases, and 3 contributors. The license is BSD-2-Clause. The repository description states: 'Scientific internship at the Karunya Institute of Technology and Sciences in Coimbatore, India. Development of an intelligent, remote/self-driving car based on Raspberry Pi, ultrasonic sensors, camera and Arduino (Python + OpenCV with neural networks and digital image processing). Vehicle capable of recognizing traffic lights, road signs and obs...'. The repository contains the following files and folders:

File/Folder	Commit Message	Commit Time
.idea	scheme	an hour ago
Multimedia and Sources	scheme	an hour ago
Traffic_signal	Traffic_Signal	2 years ago
arduino tests programs by Bartek Borzyszkowski	Ultrasonic change	10 days ago
arduino	Create README.md	3 years ago
computer	keyboard server/client	12 days ago
raspberrypi	keyboard client	11 days ago
test	readme	a day ago
venv	init	19 days ago
.gitattributes	init	19 days ago
Agenda for the workshop by Borzyszkowski Bartlomiej.jpg	multimedia	a day ago
LICENSE.md	Create LICENSE.md	3 years ago
README.md	scheme	an hour ago
Scheme.png	scheme	an hour ago
environment.yml	init	19 days ago
robot1.jpg	robotpic	a day ago
robot2.jpg	robotpic	a day ago

The project was inspired by the construction of autonomous car developed by Zheng Wang, available in the document below:

[zhengludwig.wordpress.com/projects/self-driving-rc-car/](http://zhengludwig.wordpress.com/projects/self-driving-rc-car/)

## **Functionality**

The robot is an intelligent, partially-autonomous car, what means that user's interve is required in the process but at the same time information collected from the environment make the robot capable to decide on its own and take some actions by itself.

The vehicle is able to move in four different directions – forward, backward, right, left and stop after pressing a corresponding button. The main functionality is steering by the user from the laptop keyboard (wireless connection/remote control).

Furthermore, the equipment with the ultrasonic sensor enables the robot to measure the distance from obstracles in the front and stop in case of possible collision. Thanks to the Pi camera the user has a real time display from the front of the robot on the laptop/PC screen. This solution allows the robot to be independent and wireless but at once the user has an access to steer the robot. In following steps of the project total autonomous and possibility to choose between self-drive or remote control steering is also possible.

## **Equipment / Components**

- Raspberry Pi 3 Model B
- Camera desired for the Raspberry Pi
- Arduino UNO
- Laptop/PC
- Ultrasonic sensor HC-SR04
- Motor driver L293
- 2 separate motors and 2 wheels
- Power supply (power bank and an additional rechargeable battery)
- Robot board – car frame
- Cords/wires
- Switch button
- Soldering equipement
- Wi-Fi network
- External display
- Programming environment and software



## Architecture / Scheme

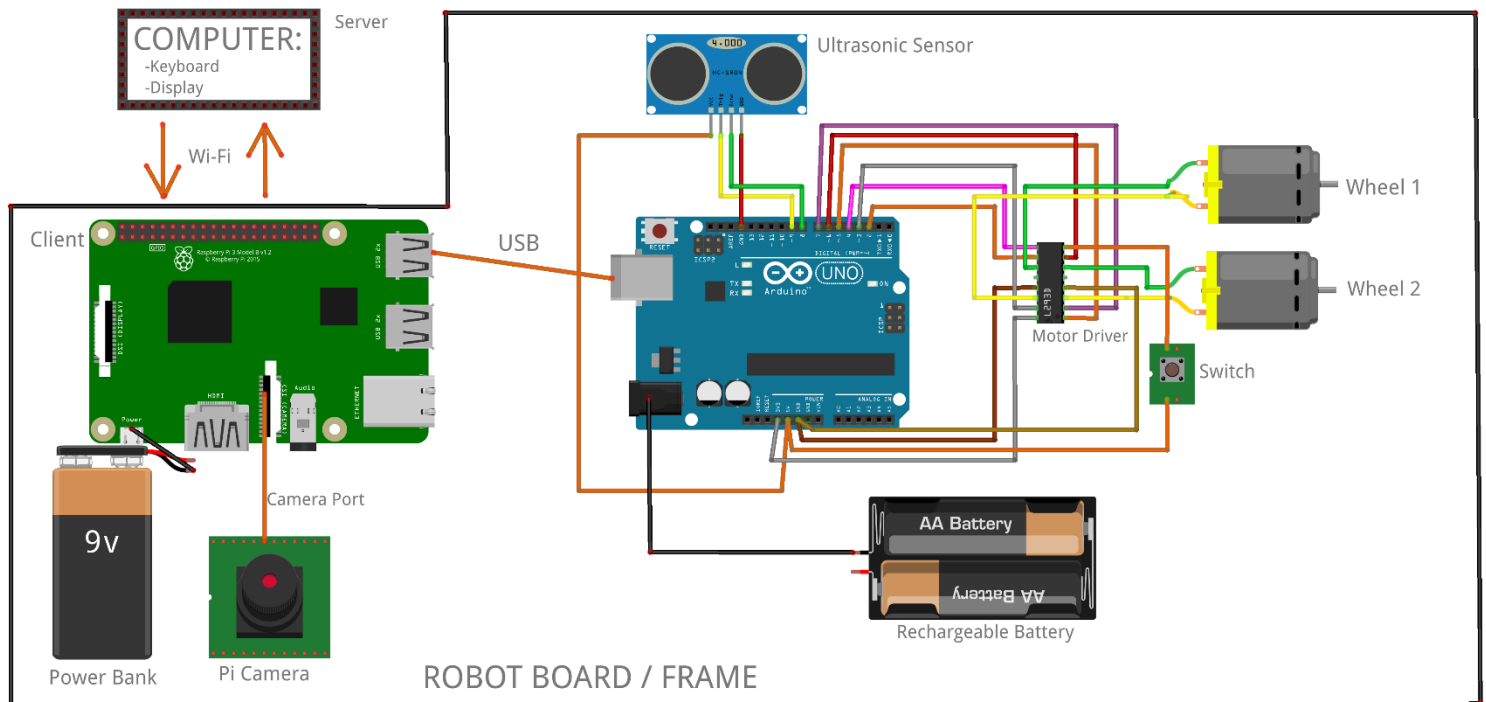


Figure 1: Full architecture scheme

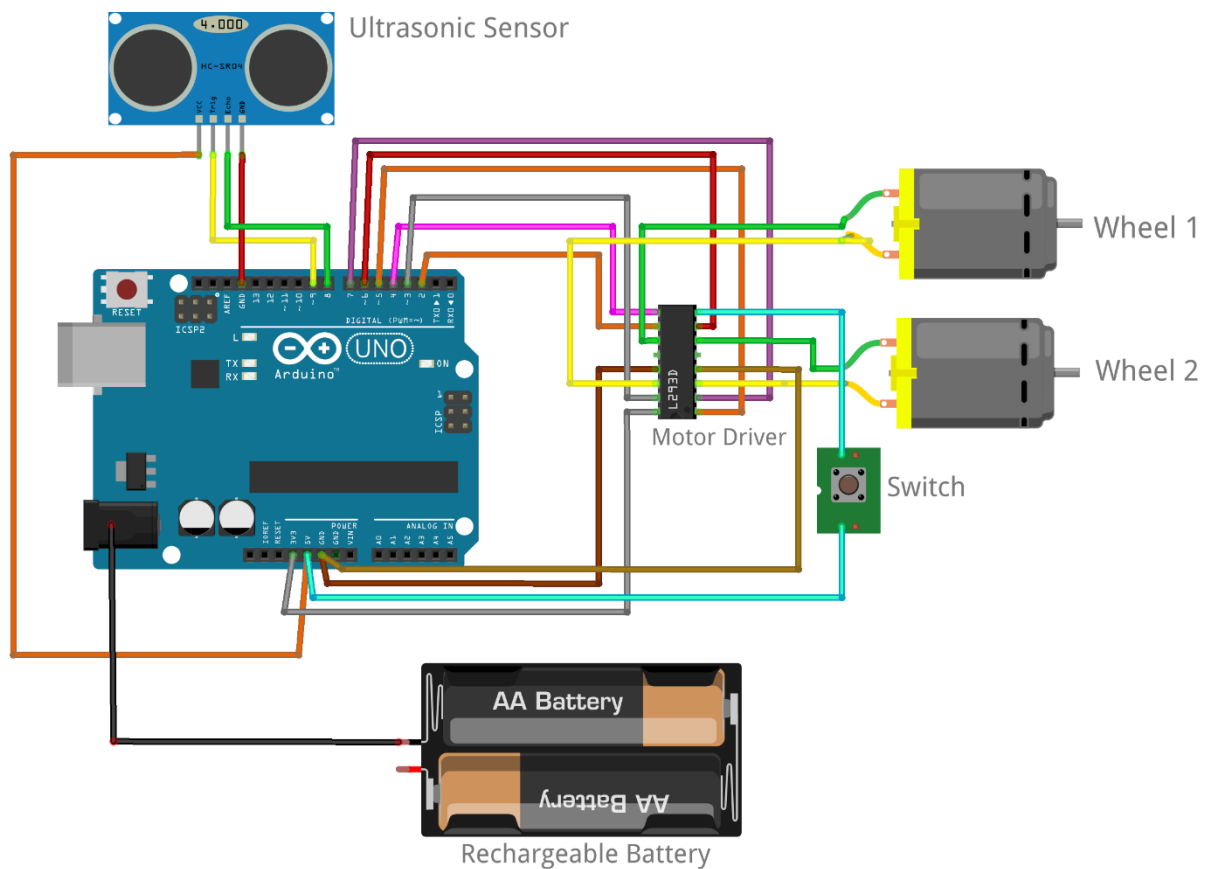


Figure 2: Arduino scheme

# Hardware description

## 1. Computer

- Working as a server for the Raspberry Pi (client) via Wi-Fi
- Collecting information about steering from the keyboard and forwarding it to the Raspberry Pi
- Receiving video from the Raspberry Pi and showing the display

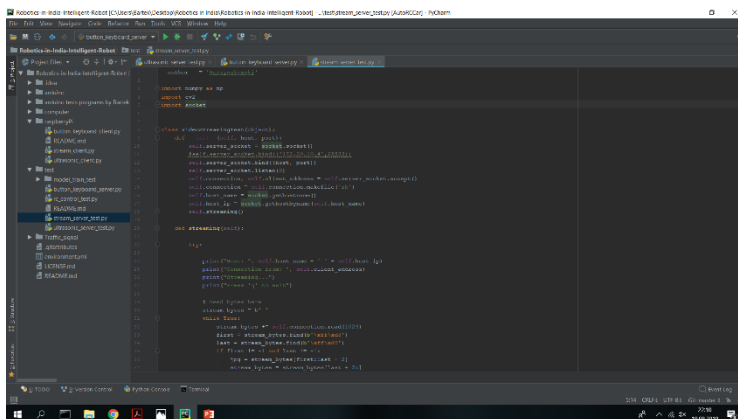


Figure 1: PyCharm Python Environment

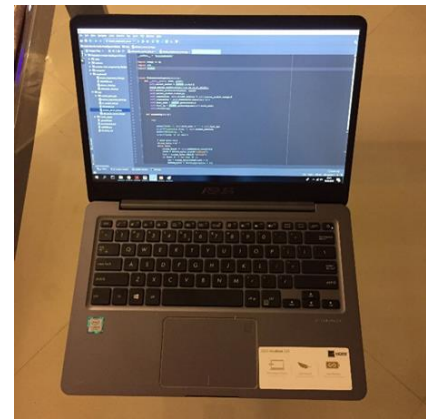


Figure 2: laptop used for the project

## 2. Raspberry Pi

- Working as a client for the computer (server) via Wi-Fi
- Connected to the Arduino via USB
- Connected with the Pi camera
- Collecting information about steering from the computer (keyboard) and forwarding it to the Arduino
- Collecting data from the camera and sending it to the computer

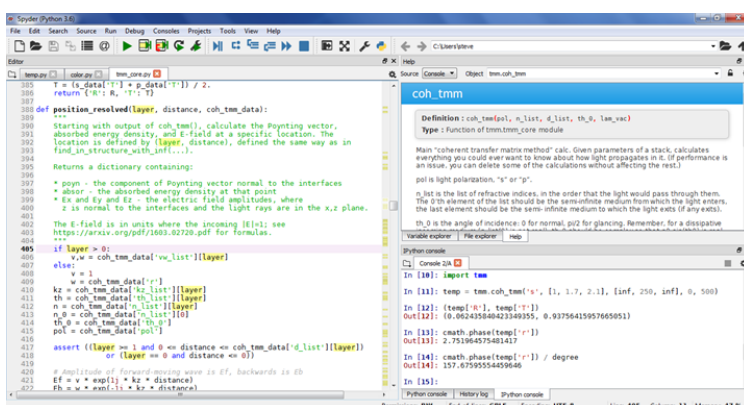


Figure 3: Spyder Python Environment



Figure 4: Raspberry Pi 3 model B with Pi Camera

### 3. Arduino

- Connected to the Raspberry Pi via USB
- Connected to the Motor Driver
- Connected to the ultrasonic sensor
- Receiving data for steering from the Raspberry Pi and forwarding information to the Motor Driver
- Receiving distance from the ultrasonic sensor and stopping the car in case of obstacle detection (front)

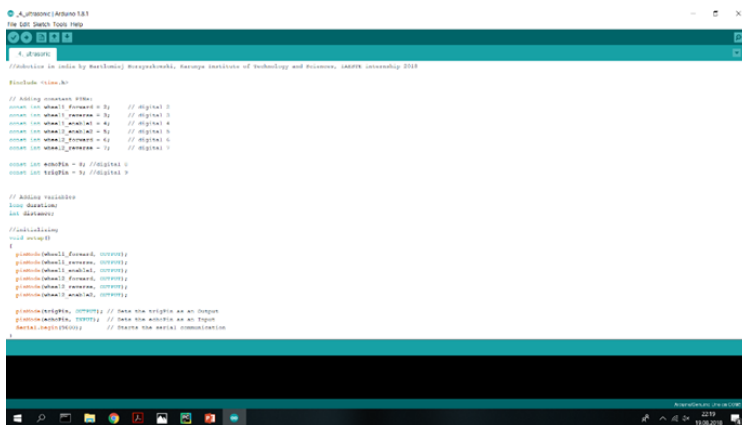
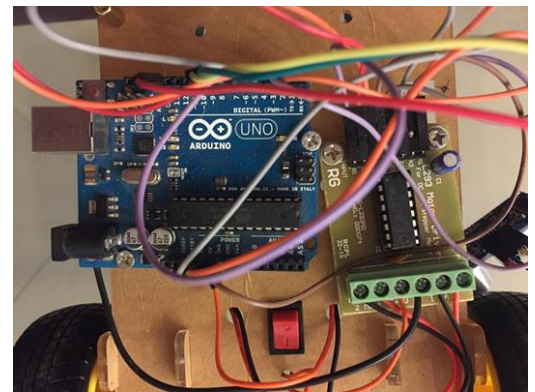


Figure 5: Arduino Programming Environment



*Figure 6: Arduino UNO*

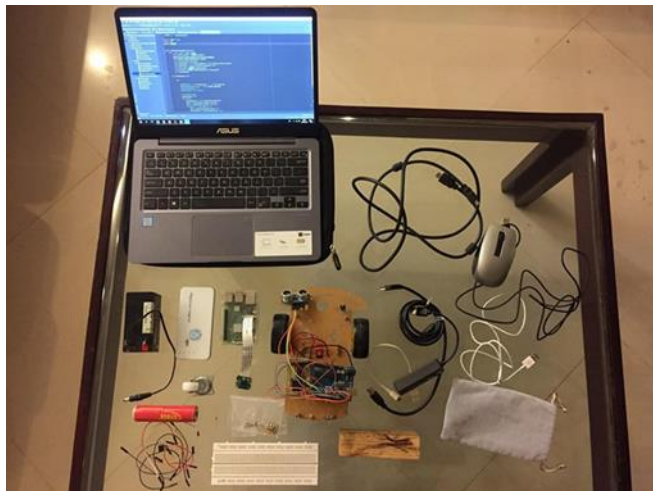


Figure 7: Project Components

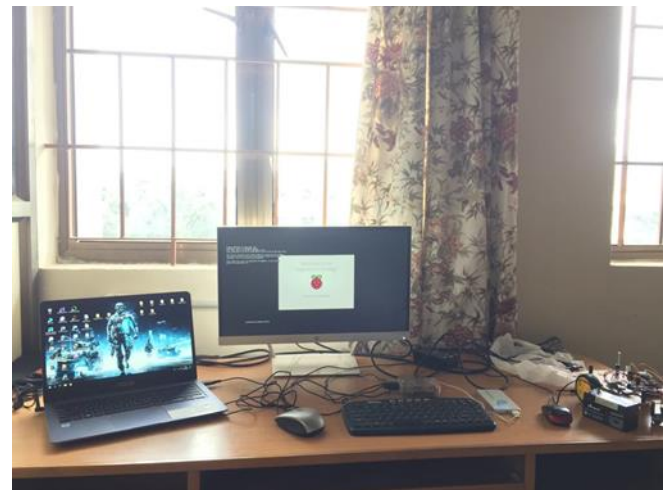


Figure 8: External display

## Software description

In the current project version to achieve the required result five programs should run in the same time:

- Computer:
  1. „button\_keyboard\_server.py”
  2. „stream\_server\_test.py”
- Raspberry Pi:
  3. „button\_keyboard\_client.py”
  4. „stream\_client.py”
- Arduino:
  5. „\_7.\_steering.ino”

For exchange of the data between the Raspberry Pi and the computer connection „server – client” is required. The received information about steering (from the keyboard) is transferred from the Raspberry Pi to the Arduino and further to the Motor Driver.

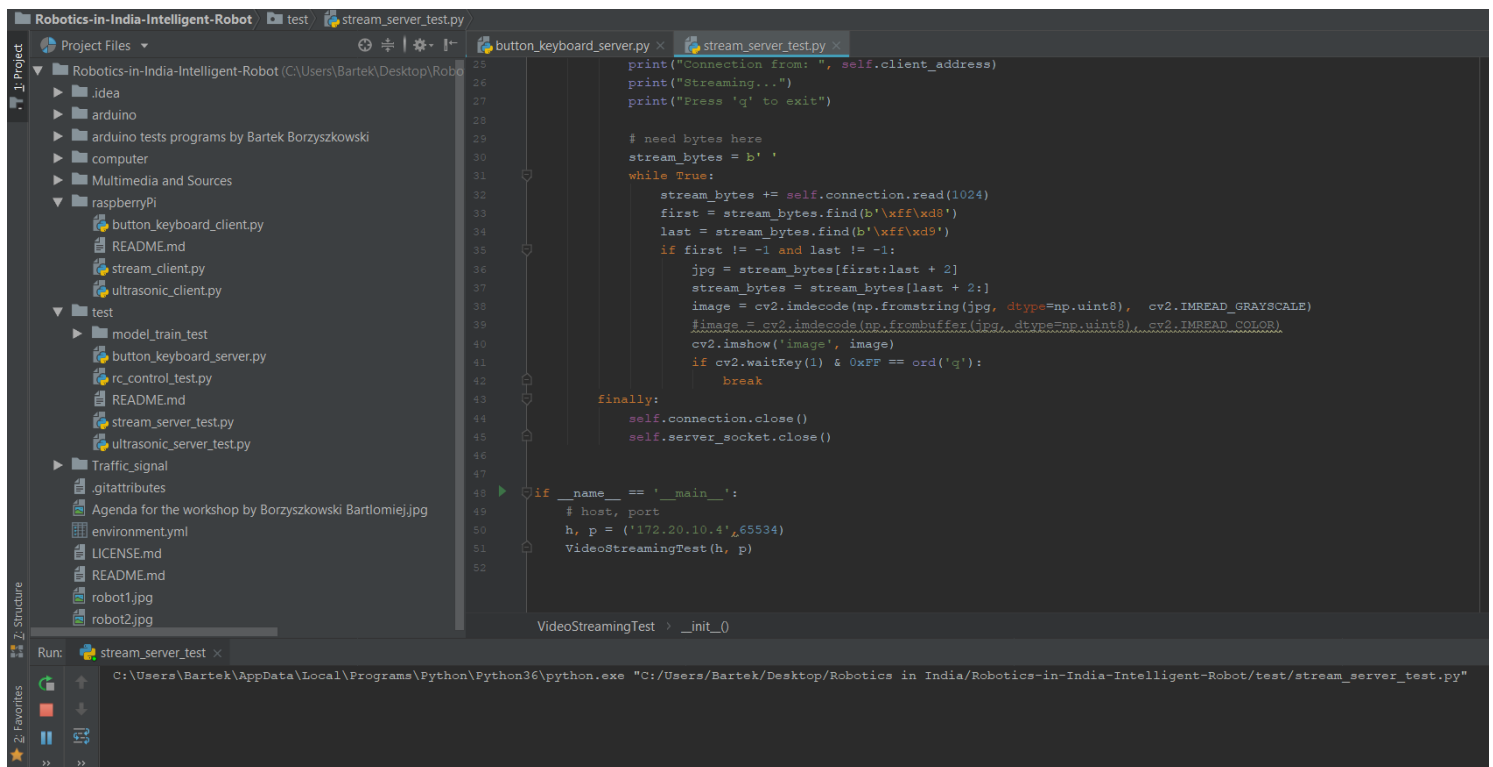


Figure 1: Project Software

Corresponding relation between devices allows to send the image from the camera to the Raspberry Pi and forward it further to the computer. Thanks to this solution, the user knows what is currently happening in front of the robot.

Besides the programs used in the project, GitHub repository is much more extended and gives more possibilities for different robot configurations (e.g. using the folder „arduino test programs by Bartek Borzyszkowski”). Moreover, folders including model training and programs developing and training the neural network allows the further evolution of the car.

### **Further develop**

- Total autonomous
- Artificial intelligence, neural networks and image processing
- Road lines, signs and traffic lights recognition
- More advance steering (30, 45, 60 degree turn)
- Both kinds of control (self-drive and remote control) with balanced priorities or possibility to choose by the user

### **Conclusion / Sum up**

To conclude, the aims of this internship were achieved successfully and are posted above as a result and source for future extensions and uses. Despite some difficulties, such as the camera streaming delay (solved by scaling down the resolution) the car works impressively.

Finally, intelligent vehicles are an important element in technological development and can contribute to the revolution on roads around the world. The design of the robot model created during the internship at the Karunya Institute of Technology and Sciences allows to observe the processes necessary to construct such a car, learn and draw the presented conclusions that will help in solving future potential problems.

*Bartłomiej Borzyszkowski*

## **Bibliography / References**

### Similar projects:

1. by Zheng Wang
  - [zhengludwig.wordpress.com/projects/self-driving-rc-car/](http://zhengludwig.wordpress.com/projects/self-driving-rc-car/)
  - [github.com/hamuchiwa/AutoRCCar](https://github.com/hamuchiwa/AutoRCCar)
2. by Ryan Zotti
  - [github.com/RyanZotti/Self-Driving-Car](https://github.com/RyanZotti/Self-Driving-Car)
3. by Yazeed Alrubyli
  - [becominghuman.ai/building-self-driving-rc-car-series-5-serverless-control-using-computer-vision-fdf0d0136888](http://becominghuman.ai/building-self-driving-rc-car-series-5-serverless-control-using-computer-vision-fdf0d0136888)
  - [github.com/yazeedalrubyli/SDRC](https://github.com/yazeedalrubyli/SDRC)
4. by Multunus
  - [github.com/multunus/autonomous-rc-car](https://github.com/multunus/autonomous-rc-car)

### Guides and specifications:

#### L293 Motor Driver:

- [ti.com/lit/ds/symlink/l293.pdf](http://ti.com/lit/ds/symlink/l293.pdf)

#### HC-SR04 Sensor:

- [components101.com/ultrasonic-sensor-working-pinout-datasheet](http://components101.com/ultrasonic-sensor-working-pinout-datasheet)
- [tutorials-raspberrypi.com/raspberry-pi-ultrasonic-sensor-hc-sr04/](http://tutorials-raspberrypi.com/raspberry-pi-ultrasonic-sensor-hc-sr04/)
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#### Pi Camera:

- [projects.raspberrypi.org/en/projects/getting-started-with-picamera](http://projects.raspberrypi.org/en/projects/getting-started-with-picamera)
- [opencv-python-tutroals.readthedocs.io/en/latest/py\\_tutorials/py\\_calib3d/py\\_calibration/py\\_calibration.html](http://opencv-python-tutroals.readthedocs.io/en/latest/py_tutorials/py_calib3d/py_calibration/py_calibration.html)

### Other sources:

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- [ucsusa.org/clean-vehicles/how-self-driving-cars-work#.W4YvVegzZPZ](http://ucsusa.org/clean-vehicles/how-self-driving-cars-work#.W4YvVegzZPZ)