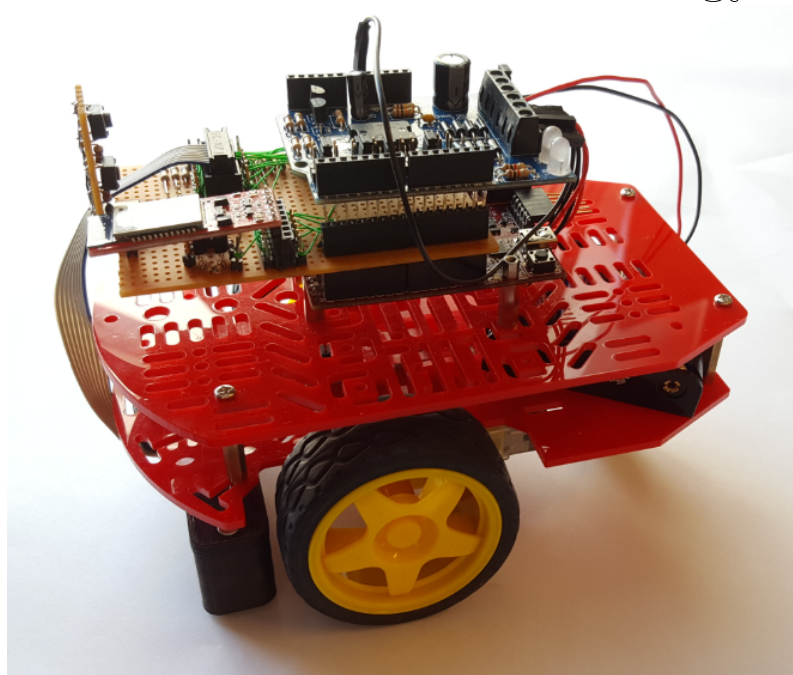


Fall Semester 2016

Autonomous Object Avoidance Robot

Group 2

3. Semester IT-Technology



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Supervisor: Jesper Kristensen - Steffen Vutborg

Title:

Autonomous Object Avoidance
Robot

Project Period:

3. Semester | Spring semester 2016

Projectgroup:

Group 2

Group participants:

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Pages:

Appendices:

Completed:

Preamble

This project was written by group 2, for the third semester on the IT-electronics education at university college Nordjylland, Sofiendalsvej 60. The project goal is to make a line following robot with object avoidance capabilities.

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Table of Contents

| | | |
|-----------|---|-----------|
| 1 | Introduction | 1 |
| 2 | Analysis | 2 |
| 2.1 | Problem statement | 2 |
| 2.2 | Problem analysis | 2 |
| 3 | Requirements specification | 3 |
| 4 | Hardware section | 4 |
| 4.1 | Description of the hardware structure and functionality | 4 |
| 4.2 | Hardware diagram | 4 |
| 4.3 | Analog-to-digital converter | 4 |
| 4.4 | The chipKIT Uno32 board | 4 |
| 4.5 | The motor shield - PKA03 | 4 |
| 4.6 | The Bluetooth transceiver | 4 |
| 5 | Software section | 5 |
| 5.1 | Analog to digital conversion | 5 |
| 5.2 | PID controller | 5 |
| 5.3 | Pulse-width modulation | 5 |
| 5.4 | The interface | 5 |
| 6 | Test | 6 |
| 6.1 | Unit Testing | 8 |
| 6.2 | Integration Testing | 8 |
| 6.3 | System Testing | 8 |
| 6.4 | Acceptance Testing | 8 |
| 7 | Conclusion | 9 |
| 8 | Appendices | 10 |
| 8.1 | Group collaboration agreement | 10 |
| 9 | List of references | 11 |
| | List of Figures | 12 |
| | List of Tables | 13 |
| 10 | Software appendix | 14 |
| 10.1 | C code | 14 |
| 10.2 | C# code - interface | 16 |
| | Bibliography | 17 |

| | |
|----------|---|
| 3D print | 3-Dimensional printing |
| ADC | Analog-digital conversion |
| GUI | Graphical User Interface |
| IDE | Integrated Development Environment |
| MCU | Microcontroller Unit |
| PCB | Printed Circuit Board |
| PID | Proportional-integral-derivative |
| PWM | Pulse-width modulation |
| THT | Through-hole-technology |
| UART | Universal Asynchronous Receiver/Transmitter |

Introduction 1

In this section the problems found when trying to get the robot function, will be listed and analysed

2.1 Problem statement

The problem presented to the group is how to make a robot move from point A to point B, with the help of different sensors, including ultrasound and infrared, and to make use of autonomous algorithms to avoid obstacles.

Problem statement:

- Bot should be able to move from A to B
- Should be able to stop at a predetermined point
- Manoeuvre around obstacles

2.2 Problem analysis

2.2.1 Mobility from A to B

The robot receives a coordinate to reach, and will use its own starting point to determine a direction to drive towards the given coordinate. The robot will need a way to control its movement and direct current to function optimal.

The robot needs a way to effectively regulate speed and also steer itself autonomously. To dictate how quickly the robot moves, the robot will need some system that allows it to move around on a flat surface, the robot needs to be able to move around from point A to point B. .

2.2.2 Predetermined end point

After starting, the robot needs to know when to stop. The pre-determined end-point consists of a series of circles which the robot needs to detect.

2.2.3 Obstacles avoidance

As part of its functionality, the robot needs to be able to see objects that are in front of it and avoid them.

Requirements specification 3

This section specifies the requirements. The requirements have been found through the analysis.

[1]

- The robot needs line following capabilities
- The robot needs object avoidance
- The robot should make use of an H-bridge
- The robot should make use of Motors
- The robot needs a way to implement motor control
- The robot should make use of a micro-controller unit
- The robot should make use of the Magician chassis

Hardware section 4

4.1 Description of the hardware structure and functionality

In this section the different components of the hardware will be listed, described and explained.

4.2 Hardware diagram

Beskrivelse af hardware diagram

4.2.1 Object avoidance sensor choices

SR04 Ultrasound GP2Y0A02YK0F (long)
GP2Y0A41SK0F (short)

4.2.2 Line following sensor choice

QRE1113 -

4.3 Analog-to-digital converter

ADC diagram

The usage of ADC

4.4 The chipKIT Uno32 board

4.5 The motor shield - PKA03

4.5.1 The H bridge

The robot will make use of an H-bridge. An H-bridge is a circuit made for controlling the motor of the robot, by making sure the motor will never try to do forward and backward motion and cause errors. The point of using an H-bridge is to ensure motor safety and functionality.

4.6 The Bluetooth transceiver

Software section 5

Beskriv Software section

5.0.1 Software diagram

5.1 Analog to digital conversion

5.2 PID controller

5.2.1 Proportional control(P)

5.2.2 Integral control(I)

5.2.3 Derivative control(D)

5.2.4 Loop tuning

5.2.5 Steady-state error

5.2.6 Stability

Table manual explained

5.2.7 PID Implementation

5.3 Pulse-width modulation

5.3.1 Duty cycles

5.4 The interface

Test 6

Beskriv test section

6.1 Unit Testing

6.1.1 Sensor

Setup

Results

6.1.2 DC Motors

Setup

Results

6.1.3 H-Bridge

Equipment

Setup

Results

6.1.4 PWM

Equipment

Setup

Results

6.1.5 ADC

Equipment

Setup

Results

6.2 Integration Testing

6.2.1 PWM motor control

Equipment

Setup

Results

6.2.2 Robot to Interface communication

Equipment

Setup

Results

6.3 System Testing

Equipment

Setup

Results

Conclusion 7

Skriv en fucking Conclusion!!

Appendices 8

8.1 Group collaboration agreement

8.1.1 Contact Information

Table 8.1: Contacts

| | | |
|------------------|---------------|-----------------------------|
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8.1.2 Workflow

8.1.3 Deadline

8.1.4 Milestones and goals

Gerne en kalender der viser dage arbejdet!

List of references 9

List of Figures

Page

List of Tables

| | | |
|-----|--------------------|------|
| 8.1 | Contacts | 10 |
| | | Page |

Software appendix 10

10.1 C code

main.c:

ADC.c:

10.2 C# code - interface

Bibliography

- [1] placeholderAuthor. *placeholderTitle*. 2016. URL: <http://www.ucn.dk>.