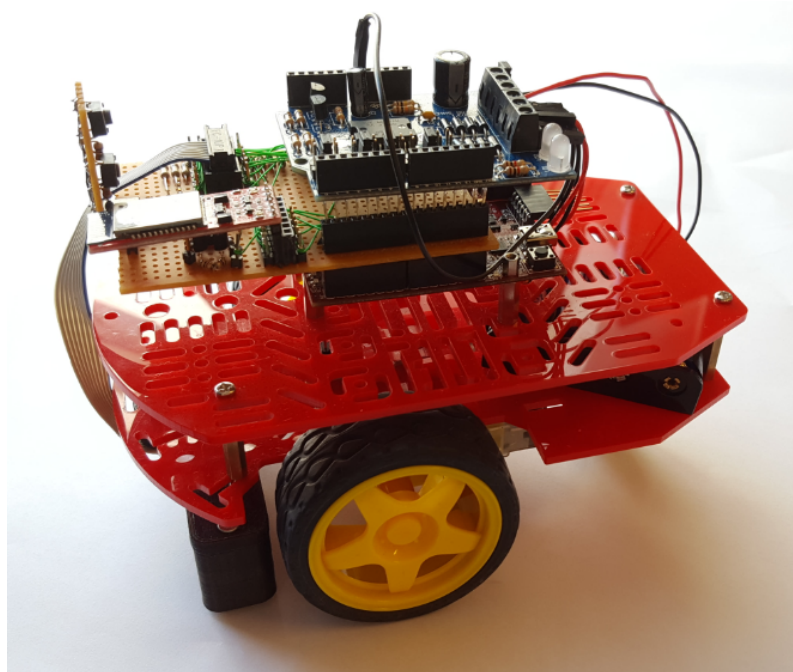


Fall Semester 2016

Autonomous Object Avoidance Robot

Group 2

3. Semester IT-Technology



Group members: Benjamin Nielsen - Henrik Jensen - Martin Nonboe - Nikolaj
Bilgrau

Supervisor: Jesper Kristensen - ¹ Steffen Vutborg

FiXme Fatal:
er han?

¹FiXme Fatal: er han?

Title:

Autonomous Object Avoidance
Robot

Project Period:

3. Semester | Fall semester 2016

Projectgroup:

Group 2

Group participants:

Benjamin Nielsen
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Pages:

Appendices:

Completed:

Preamble

TBD fyld mere på? This project was written by group 2, for the 3rd semester on the IT-electronics education at university college Nordjylland, Sofiendalsvej 60. The project goal is to make an autonomous robot that can navigate a course utilizing object avoidance and localization.

Benjamin Nielsen

Henrik Jensen

Martin Nonboe

Nikolaj Bilgrau

Table of Contents

1	Introduction	1
2	Analysis	2
2.1	Problem statement	2
2.2	Problem analysis	2
2.3	Behaviour	3
3	Requirements specification	4
4	Hardware section	5
4.1	Description of the hardware structure and functionality	5
4.2	Hardware diagram	5
4.3	Sensors and sensor concept	6
4.4	The chipKIT Uno32 board	8
4.5	The motor shield	8
4.6	The Bluetooth transceiver	10
4.7	Part conclusion	10
5	Software section	11
5.1	Software flowchart	11
5.2	Pulse-width modulation	12
5.3	Feedback loop	13
5.4	CPLD	16
5.5	Part conclusion	16
6	Test	17
6.1	Unit Testing	17
6.2	Integration Testing	19
6.3	System Testing	19
6.4	Acceptance Testing	19
7	Conclusion	20
8	Appendices	21
8.1	Group collaboration agreement	21
9	List of references	22
	List of Figures	23
	List of Tables	24
10	Hardware appendix	25
10.1	Hardware Schematics	25
11	Software appendix	29
11.1	C code	29

11.2 C# code - interface	31
Bibliography	32

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 countries with high wages and where manual labour is expensive, the industrial production is often organized as an automated process. To make the whole industry smarter and more customizable, new automated robots and reliabilities are needed. The many new forms of robots rely on sensors to face the many different challenges. Automation of movement and avoidance enables even robotic space exploration, as seen in the many rovers visiting the different nearby planets.

There are different sensors in play when needing to avoid obstacles or collision. To mention a few, ultrasound, infra-red and laser sensors comes to mind, all of which are viable picks when building a robot with object avoidance.

In the project at hand, we will be focusing mainly on the ultrasound sensor for building an object avoiding robot. The objective of this project is to design and implement an automotive robot capable of autonomous object manoeuvring, specially a collision avoiding robot employing light detecting sensing and ultrasound sensing.

The project was handed to the group at the start of third semester and is to be handed in at the 9th of January, 2017.

This section will be focused on analysing any problems the group may face, how to approach them, and how they should be handled.

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.

2.3 Behaviour

FiXme Fatal:
algorithm¹

¹FiXme Fatal: algorithm

Requirements specification 3

FiXme Fatal:
mere fyld

¹ This section specifies the requirements. The requirements have been found through the analysis.

[2]

- 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

¹FiXme Fatal: mere fyld

Hardware section 4

4.1 Description of the hardware structure and functionality

¹ In this section the different components of the hardware will be listed, described and explained.

FiXme Fatal:
mere fyld og
billede

4.2 Hardware diagram

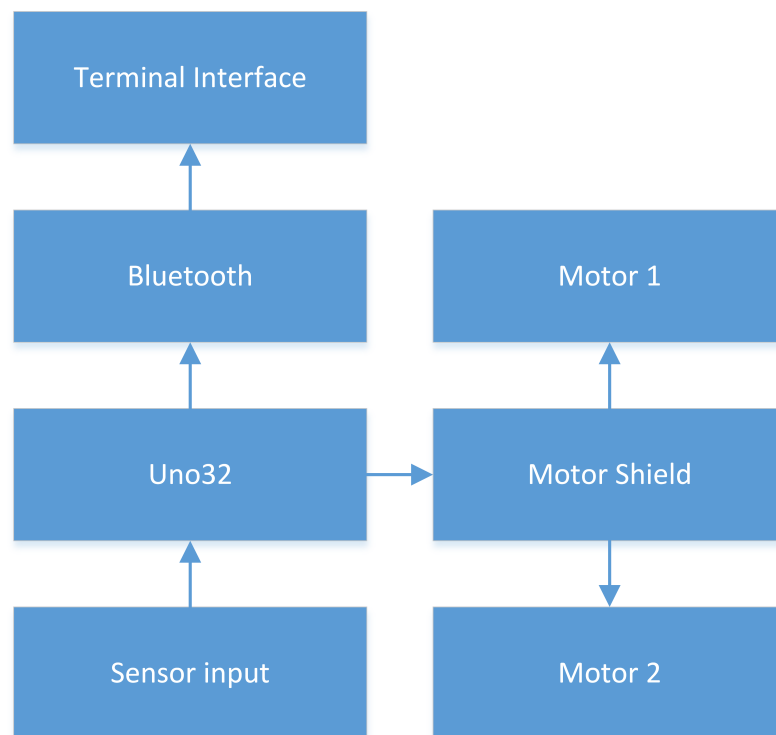


Figure 4.1: Hardware diagram with arrows

The micro controller is connected to the motor-shield. The motor-shield is then connected to the two motors, called motor 1 and motor 2 and is powering both motors. The micro controller is receiving data from the 3 sensor sets; the ultrasound sensors, infrared light-sensors and the tachometer sensor. The micro controller then receives the data from the sensors and sends it further to the Bluetooth transceiver and then the Bluetooth transceiver will send it to the interface.

¹FiXme Fatal: mere fyld og billede

4.3 Sensors and sensor concept

The robot will utilize two sets on sensors - one set of QRE1113 sensors, which will be used for line-following capabilities, they are fastened towards the end of the robot, and will give the robot a way to detect what surface it is about to enter.

The second is a hybrid set of ultrasound and infrared sensors. These will be working together to make the robot able to navigate open spaces more precisely, since infrared and ultrasound sensors work the best under different circumstances. This will end up as a product which is more optimized for usage in situations that would not be ideal for one of the other, since the hybrid design will leverage shortcomings of a given sensor method.

4.3.1 Choice of sensors

FiXme Fatal:
everything²

4.3.2 Ultrasound sensor - HC-SR04

When a robot should be able avoid obstacles it will need a device to inform the robot where it's position is compared to the obstacle. This is where an ultrasound sensor plays an important role. For this task the HC sr04 has been picked.



Figure 4.2: The HC-SR04 ultrasound sensor

FiXme Fatal:
Mere om
denne sensor³

The way the ultrasound sensor works is by emitting acoustic waves and then waits for the waves to reflect back to the sensor. The waves are often at about 40 kHz and humans are unable to detect the sounds because of the frequencies being above the human audible range.

What is causing the device to make ultrasonic sound is a piezoelectric crystal. The crystal is receiving a rapid oscillating electrical signal, this causes the crystal to

²FiXme Fatal: everything

³FiXme Fatal: Mere om denne sensor

expand and contract and thereby creating a sound wave. The sound waves will then after being reflected return to a piezoelectric receiver which can then convert the waves into voltage by using the same method as explained above.

There are several popular ways to process the information gathered from the ultrasound sensor.

- Time of flight
- Doppler shift
- Amplitude attenuation

In the scope of the project, the robot will be using "Time of flight" for sensing the distance between itself and the obstacle.

When working with the term time of flight, it means the ultrasound sensor only generates pulses of sound instead of an continuous streak of sound waves. to avoid confusion. In high speed situations this will mean there is waiting time limits.

The calculation for using the ultrasound sensor is:

t = time

r = distance travelled

c = speed of light

$r = c * t$

With this the robot can calculate the time of flight.

Considerations:

When using the ultrasound as a sensing tool, there are some factors that must be taken into consideration.

Temperature and humidity can affect the speed of sound, just as air currents have been known to be able to create invisible boundaries that can reflect ultrasonic waves.

Ultrasound sensors have something called a dead zone, this occurs when an object is in front of the sensors and the receiver can't keep up.

Some materials are very absorbent, which will result in less reflected ultrasound to be detected by the receiver.

Mounting

TBD billede med lille tekst

4.4 The chipKIT Uno32 board

⁴ The robot will utilize the chipKIT Uno 32 board to execute code. The board was chosen both due to past experiences, but also because the robot would need line-following properties, and we had already written a functional line-following robot previously, which also included some important features, including PID control and pulse-width modulation patterns.

This enabled a lot of recycled code, which was a strong point in the Uno 32's favor due to time constraints.

FiXme Fatal:
section need
readover

The board is also compatible with Arduino shields, and as such designing the H-bridge for it becomes more straightforward. It's fast enough to execute the code, and works well within the input power the robot will utilize.

4.5 The motor shield

The motor shield is the single add on board used in the project, and contains all the features needed for making the robot work. The features are:

- Dual H-bridges.
- Low side current sensor for each H-bridge.
- CPLD for reconfigurable H-bridge logic control.
- All connectors needed for sensors and other units needed:
 - Screw terminal for motor connection.
 - Screw terminal for input power.
 - Molex connector for ultrasound distance Sensor.
 - Molex connector for distance sensor.
 - Molex connector for motor encoder.
 - Molex connector for infrared light sensor.
 - Header for Bluetooth module.

FiXme Fatal:
INDSÆT ⁵
BILLEDE
AF SHIELD

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 or short circuits. The point of using an H-bridge is to ensure motor safety and functionality.

⁴FiXme Fatal: section need readover

⁵FiXme Fatal: INDSÆT BILLEDE AF SHIELD

4.5.2 Pololu 100:1 Micro Metal Gearmotor 6V High Power

This is a small motor, drawing 120mA when there is no load, and 1600mA when stalling. They run up to 320 RPM; because of this, the robot will be able to move very rapidly. The ones used for the robot have an extended motor shaft, which makes it possible to utilize the Pololu motor encoders.

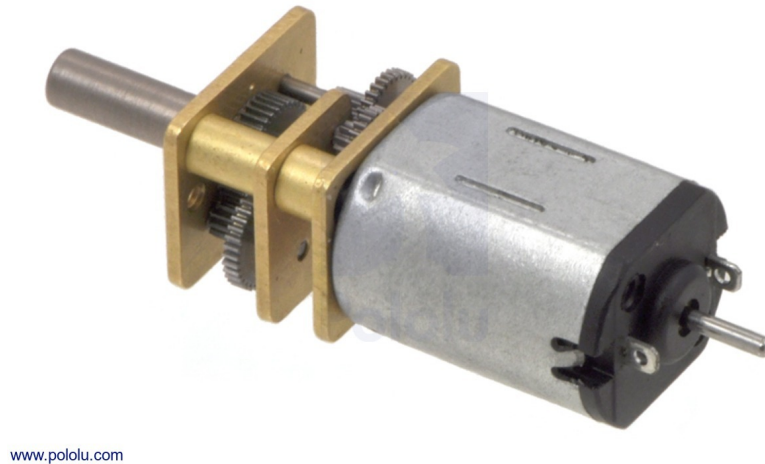


Figure 4.3: Pololu micro metal gear motors

Pololu Magnetic Encoder Pair Kit

These encoders allow the transmission of data based on motor movement. It works by having the encoder board count the revolutions of the magnetic disc mounted on the board. It does this twelve times per revolution.

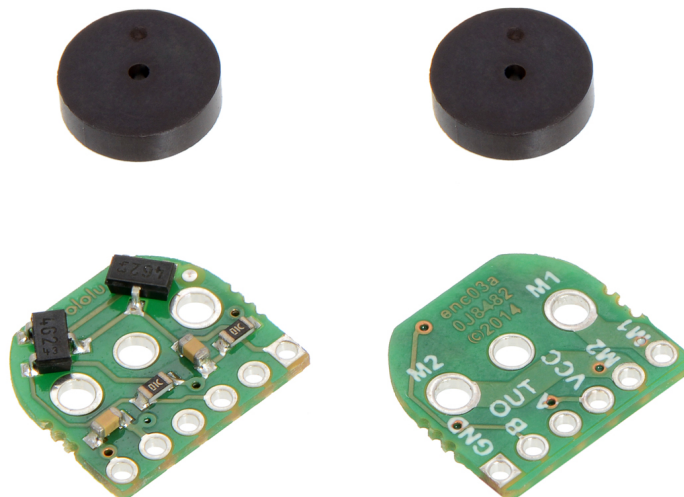


Figure 4.4: Pololu Magnetic Encoder Pair Kit

4.6 The Bluetooth transceiver

The robot will utilize the BlueSmiRF Silver bluetooth transceiver. The transceiver is made by Sparkfun, it is utilized to make use of an GUI, by sending data from the MCU to the computer (GUI) by the use of bluetooth.

The bluetooth transceiver makes it possible to monitor both the inputs and the logic behind the steering. The baudrate is between 2400-115200 bps and the transceiver can be powered from 3.3v up to 6v.

4.7 Part conclusion

After initial H-bridge problems, the rest of the process of building the robot went according to plan, and there were no future issues. The robot utilize a range of components which have been used for previous projects, which made the project much more simple to work with. This eliminated some of the learning curve that the previous robot presented, and made it possible to plan out and assemble the robot very rapidly, even though a lot of time was spent waiting for components for the motor shield, and the faulty components. This way, a lot more time could be used on programming and other software solutions.

Software section 5

The following section will introduce the most important parts of the software for the project. The design of the software will be shown as a flow chart and described. The section will focus on the feedback loop used, but will also go through some of the smaller parts, such as PWM and the code used for the CPLD.

Pulse Width Modulation is a very effective and straightforward way to control the speed of the robot rapidly. It works by limiting how long the of a given period the power is 'on' compared to 'off'. PWM is used by utilizing Output Compare on the chip, which lets the chip generate pulses based on a timer. This is initialized in the following way:

5.1 Software flowchart

1

FiXme Fatal:
insert
software
flowchart

¹FiXme Fatal: insert software flowchart

5.2 Pulse-width modulation

Pulse Width Modulation is a very effective and straightforward way to control the speed of the robot rapidly. It works by limiting how long the of a given period the power is 'on' compared to 'off'.²

FiXme Fatal:
virker lidt
underligt?

```

1 void initPWM() {
2     int sysClk = 80000000; //FPB
3     int pwmFreq = 1000; //Desired frequency
4     int prescaleV = 1;
5     int dutyCycle = 0;
6
7     PMCONbits.ON = 0; //TBD bruger vi det?
8     PMAEN = 0;
9
10    OC4CON = 0x0000; //Turn off the Output Compare while setting
        up
11    OC4R = 0x00638000; //Config compare Register, rising edge
12    OC4RS = 0x00638000; //Secondary compare Register, falling
        edge
13    OC4CON = 0x0006; //Turn on Output Compare in PWM mode
14    OC4RS = (PR4 + 1)*((float) dutyCycle / 100); //Sets the duty
        cycle, RS = time until falling edge starts
15    OC4CONSET = 0x8020; //Enable peripheral, bit 5: 0=16 bit
        compare mode, 1=32 bit
16
17    OC5CON = 0x0000; //Same as above
18    OC5R = 0x00638000;
19    OC5RS = 0x00638000;
20    OC5CON = 0x0006;
21    OC5RS = (PR2 + 1)*((float) dutyCycle / 100);
22    OC5CONSET = 0x8020;
23
24    T2CONSET = 0x0008; //Starts a 32-bit timer
25    T2CONSET = 0x8000; //Enables the timer
26
27    PR4 = (sysClk / (pwmFreq * 2) * prescaleV) - 1; //Calculate
        how often the timer should trigger
28    PR2 = (sysClk / (pwmFreq * 2) * prescaleV) - 1;
29 }

```

5.2.1 Why utilize pulse-width modulation

Pulse-width modulation, or PWM, is a way to regulate power distribution within a system. It is a software solution that manages when a device receives power, and for how long at a time it does this. This is called a duty cycle. The robot utilizes PWM for its motors, to regulate how quickly it moves. PWM can be compared to turning a switch on and off extremely quickly - much more quickly than what

²FiXme Fatal: virker lidt underligt?

will affect the performance of the motors. Effectively, this means that the robot's programming will now be able to regulate speed autonomously ³.

FiXme Fatal:
au-
tonomously?

5.2.2 Duty cycles

The duty cycle is used to describe how long the power is 'on' compared to 'off'. A higher duty cycle will yield more energy than a low one. The software uses a frequency of 1000Hz, which makes it straightforward to calculate to real time, if this is needed - it also provides enough precision to make the motors responsive quickly. The duty cycle can be changed by changing how long until the Output Compare sends a falling edge:

```

1 void adjustDuty(int channel, int duty) { //The function takes an
    argument based on which motors PWM should change, and the
    desired duty cycle
2     switch (channel) {
3         case 1:
4             OC5RS = (PR2 + 1)*((float) duty / 100); //Sets the
                secondary register, to tell it how long until it
                should send a falling edge
5             break;
6         case 2:
7             OC4RS = (PR4 + 1)*((float) duty / 100);
8             break;
9     }
10 }
```

5.3 Feedback loop

A feedback loop is a way of controlling how something, in this case a robot, behaves by receiving an output and adjusting the performance to match a desired output. The robot made in this project utilizes a feedback loop by firstly turning towards a set goal, and then avoiding obstacles along the way through sensors measuring the distance from the robot to the obstacle. If an obstacle gets too close, the robot will turn away from the obstacle and head back towards the goal.

5.3.1 Reading sensors

To know how far away an object is, some form of sensor feedback is needed. In this case, 3 ultrasound sensors have been implemented. The microprocessor sends a turn-on signal to the sensors, starts a timer and then waits until the sensors return with their own signal. The time between the start and finish signal can then be used to calculate the distance between the robot and the object.

```

1 long readUltrasonic(int channel){
2     long timerFinish = 0;
```

³FiXme Fatal: autonomously?

```

3   long timerOld = 0;
4   int timeout = 3000; //Sets a limit for how long the MCU waits
    for data
5   switch(channel){ //Switches between the 3 sensors
6       case 1:
7           Trigger1 = 1; //Pin RG6
8           DelayUs(10); //Sends a short pulse
9           Trigger1 = 0;
10          while(Echo1 == 0){} //Waits until pin RF6 is set to
            high
11          timerOld = micros(); //Sets the start timer to time
            since the program started, in microseconds
12          while(Echo1 == 1){ //While the sensors signal is high
13              timerFinish = micros(); //Sets the end timer to
                check for timeout
14              if(timerFinish - timerOld > timeout ||
                  timerFinish - timerOld < 0) //If the time to
                    return is too high or below 0, return a
                        default value
15                  return 500;
16          }
17          break;
18  ...
19  }
20  timerFinish = micros();
21  long result = ((timerFinish-timerOld)*0.34)/2; //Calculate
            distance from speed of sound, divided by 2 since the sound
            wave also needs to return to the sensor.
22  return result;
23 }

```

The short pulse sent in the beginning of the function has been set by the manufac-

FiXme Fatal: turer: ⁴

reference til

<http://www.micropik.com/P1>

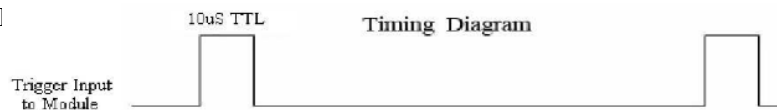


Figure 5.1: HC-SR04 timing diagram

To reduce false sensor data, which there seems to be a lot of with these sensors, a rolling average has been implemented. This calculates the average of the previous 5 readings instead of a single reading, allowing the robot to ignore spikes in data.

⁴FiXme Fatal: reference til <http://www.micropik.com/PDF/HCSR04.pdf>

5.3.2 Feedback

The controller function takes the data from the 3 sensors and uses these to control how the robot should behave. The function is by no means fully optimized, but allows the robot to avoid obstacles in it's way.

```

1 void controller(int midSensor, int rightSensor, int leftSensor){
2     int midDistance = 100; //Sets the limit for the sensors, in
        millimetres
3     int sideDistance = 50;
4     if(midSensor < midDistance) //First check the middle sensor
5     {
6         brake(); //Stops the motors
7         calculatePosition(); //Defunct, but should calculate
            where the robot is now in a coordinate system
8         backwards(); //Starts backing away from the object
9         int tachTarget = tach1-300; //Sets a tach target
10        while(tach1 > tachTarget){} //Drives backwards until
            hitting the target
11        brake(); //Brake again
12        presetTurnLeft(); //Turn 30 degrees left
13        brake();
14        forwards(); //Start driving forwards again
15    }
16    else if(leftSensor < sideDistance)
17    {
18        int tachTarget = tach1-20; //Sets the target tach
19        turnRight(); //Turn right
20        while(tachTarget > tach1){} //Until target tach is hit
21        brake(); //Brakes
22    }
23    else if(rightSensor < sideDistance) //Same as left, but
        reverse
24    {
25        int tachTarget = tach1+20;
26        turnLeft();
27        while(tachTarget < tach1){}
28        brake();
29    }
30    else
31        forwards(); //If no sensor is within the limit, just
            drive forwards
32 }

```

5.4 CPLD

FiXme Fatal:
everything⁵

5.5 Part conclusion

FiXme Fatal:
Software⁶
problemer og⁷
løsninger⁸

FiXme Fatal:
Hvorfor ikke
RTOS?

FiXme Fatal:
hvilke krav
har vi
droppet?

⁵FiXme Fatal: everything

⁶FiXme Fatal: Software problemer og løsninger

⁷FiXme Fatal: Hvorfor ikke RTOS?

⁸FiXme Fatal: hvilke krav har vi droppet?

In this section the different parts and signals will be tested, this is to make sure everything is up to par with our requirements specifications. The tests consists of measuring different factors, such as current, voltage and response time of each fundamental part. The testing will be done with the available measuring devices such as an oscilloscope, power supply or multimeter.

¹

FiXme Fatal:
ALT TEST
SKAL
TJEKKES
IGENNEM

6.1 Unit Testing

6.1.1 Ultrasound HC-SR04

Equipment

- Arduino UNO
- Agilent MSO-X 3024A Oscilloscope

Setup

A small program for the Arduino has been written which allows the MCU to trigger the sensor and waits a pre-specified amount of time before triggering again, to allow for the return of the ultrasound wave.

Results

30mm: 152 us
50mm: 285 us
100mm: 600 us
200mm: 1.23 ms
500mm: 2.32 ms

6.1.2 DC Motors

Equipment

- Hameg HM8040-2 Triple Power Supply
- Fluke 45 Multimeter

¹FiXme Fatal: ALT TEST SKAL TJEKKES IGENNEM

Setup**Results****6.1.3 H-Bridge****Equipment**

- Elcanic Power Supply
- Fluke 45 Multimeter

Setup

Power to the H-bridge is supplied by the power supply. Current and voltage will be measured by the multimeter. All of the Mosfet transistors were removed before doing the test. It was done to avoid powering the engines.

Results

There was a suspicion concerning the H-bridge, it had been measured that there was an error or a damaged component. The affected suspected part was the H-bridge for the left motor.

All of the transistors were tested on the part of the H-bridge in question. Since there was a 0 in value on the base, it is suspected that a resistor which sat on the board just before the transistor. This and the other resistor values were measured and found to be identical, based on the measures it could be concluded that it was most likely a failed transistor.

FiXme Fatal: It was concluded that the damaged transistor was the: Q14 [1] ².

link til
schematics

The results were as following:

Normal NPN transistors: base 0.854V, collector 0.073V

Faulty NPN transistor. base 0V, collector 0V.

²FiXme Fatal: link til schematics

6.1.4 PWM

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

6.4 Acceptance Testing

Equipment

Setup

Results

Conclusion 7

FiXme Fatal: ¹
Skriv en
fucking
Conclusion!!.
FANDME!

¹FiXme Fatal: Skriv en fucking Conclusion!! FANDME!

8.1 Group collaboration agreement

8.1.1 Contact Information

Table 8.1: Contacts

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Nikolaj Bilgrau	Tlf: 29802715	@: nikolajbilgrau@gmail.com

8.1.2 Workflow

8.1.3 Milestones and goals

Hardware

The hardware part of the project was supposed to be ready before the 22th

Software

Gerne en kalender der viser dage arbejdet!

¹FiXme Fatal: hele den her section

List of references 9

List of Figures

4.1	Hardware diagram with arrows	5
4.2	The HC-SR04 ultrasound sensor	6
4.3	Pololu micro metal gear motors	9
4.4	Pololu Magnetic Encoder Pair Kit	9
5.1	HC-SR04 timing diagram	14
		Page
10.1	H-bridge 1 Schematics	25
10.2	H-bridge 2 Schematics	26
10.3	Schematics of the CPLD	26
10.4	Power supply	27
10.5	Full board Schematics	28

List of Tables

8.1	Contacts	21
		Page

Hardware appendix 10

10.1 Hardware Schematics

10.1.1 H-bridge 1

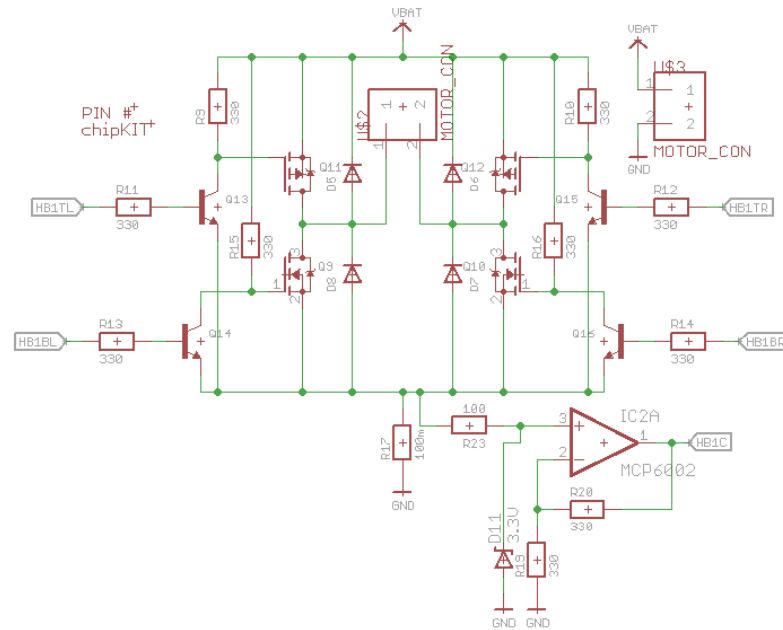


Figure 10.1: H-bridge 1 Schematics

10.1.2 H-bridge 2

10.1.3 CPLD

10.1.4 Power

10.1.5 Board schematics

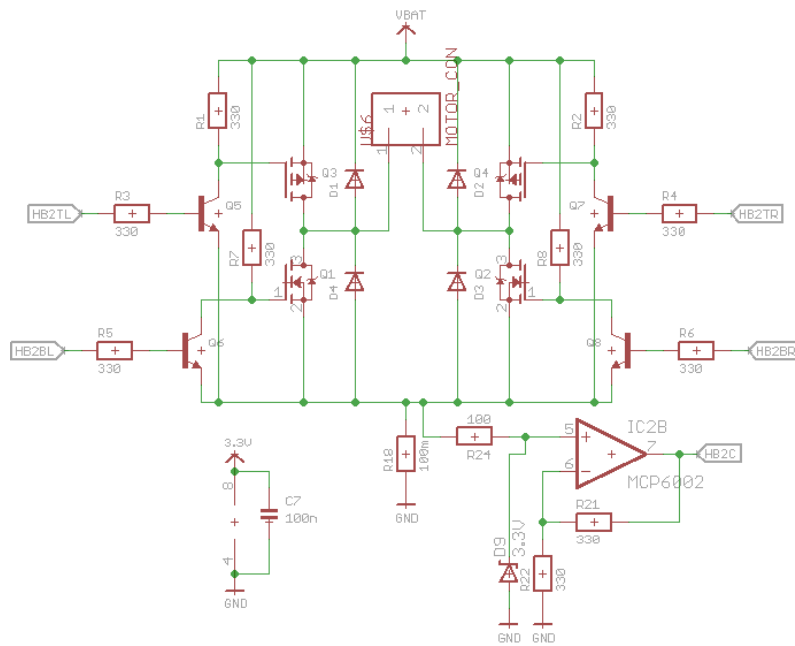


Figure 10.2: H-bridge 2 Schematics

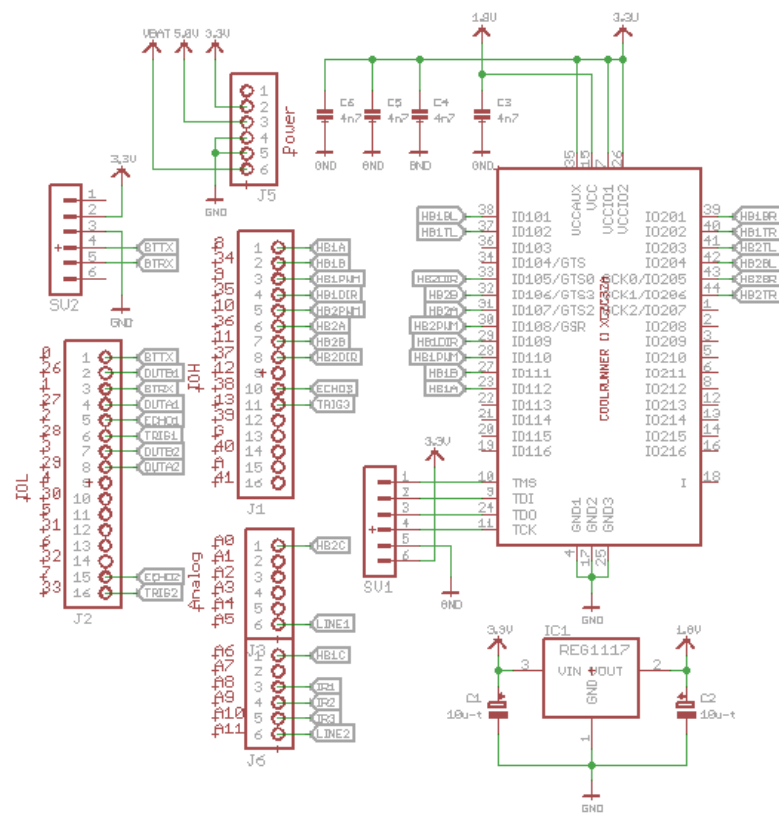


Figure 10.3: Schematics of the CPLD

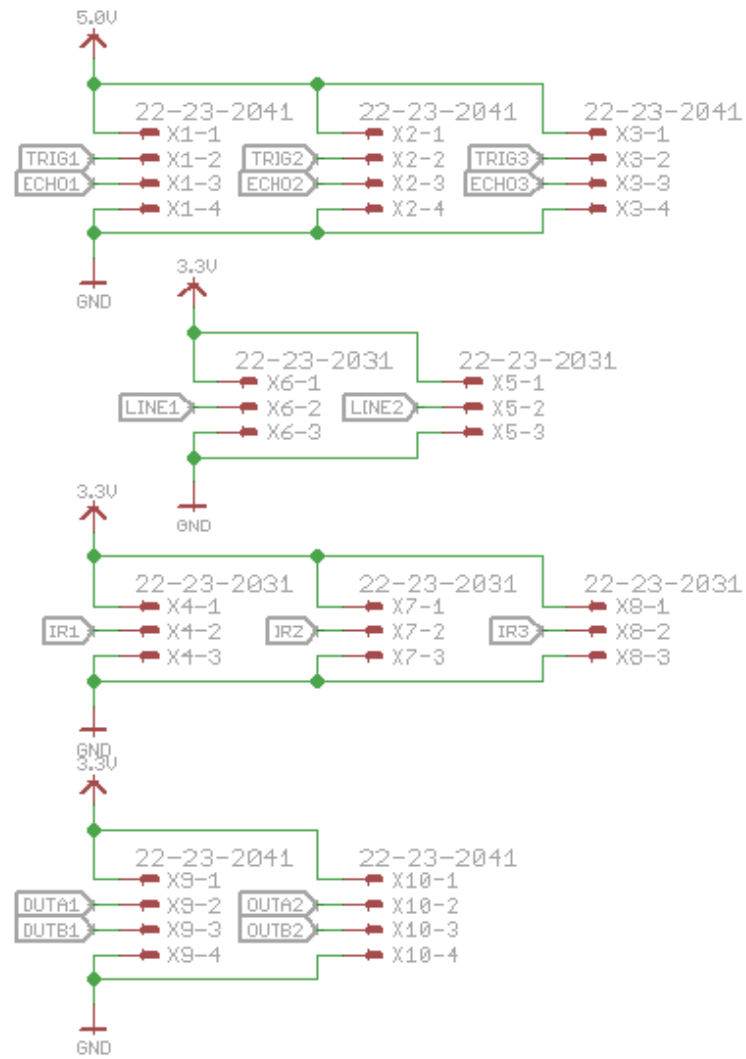


Figure 10.4: Power supply

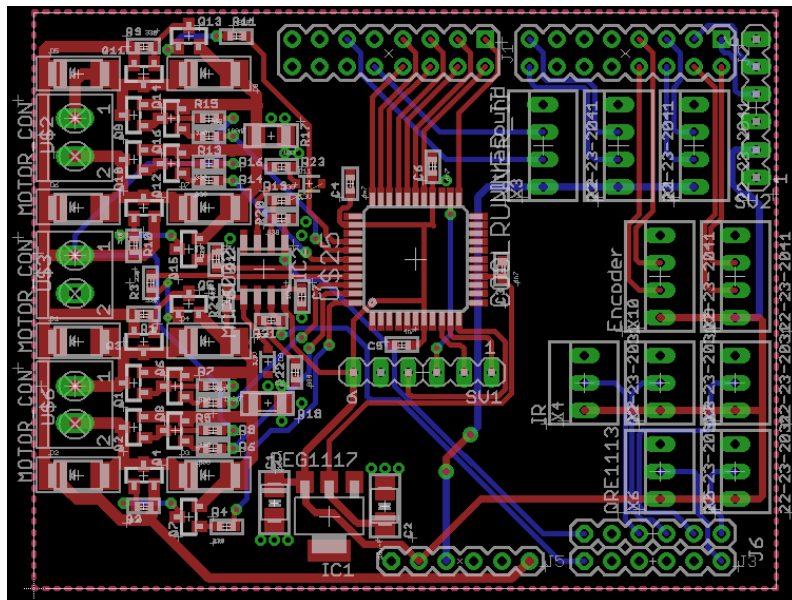


Figure 10.5: Full board Schematics

Software appendix 11

11.1 C code

main.c:

ADC.c:

11.2 C# code - interface

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- [1] UCN Group 2. “Third semester report”. Chapter 10, board schematics. 2016.
- [2] placeholderAuthor. *placeholderTitle*. 2016. URL: <http://www.ucn.dk>.

Rettelser

Fatal: er han?	1
Fatal: algorithm	3
Fatal: mere fyld	4
Fatal: mere fyld og billede	5
Fatal: everything	6
Fatal: Mere om denne sensor	6
Fatal: section need readover	8
Fatal: INDSÆT BILLEDE AF SHIELD	8
Fatal: insert software flowchart	11
Fatal: virker lidt underligt?	12
Fatal: autonomously?	13
Fatal: reference til http://www.micropik.com/PDF/HCSR04.pdf	14
Fatal: everything	16
Fatal: Software problemer og løsninger	16
Fatal: Hvorfor ikke RTOS?	16
Fatal: hvilke krav har vi droppet?	16
Fatal: ALT TEST SKAL TJEKKES IGENNEM	17
Fatal: link til schematics	18
Fatal: Skriv en fucking Conclusion!! FANDME!	20
Fatal: hele den her section	21