

Smart Waste Management System For Metropolitan Cities

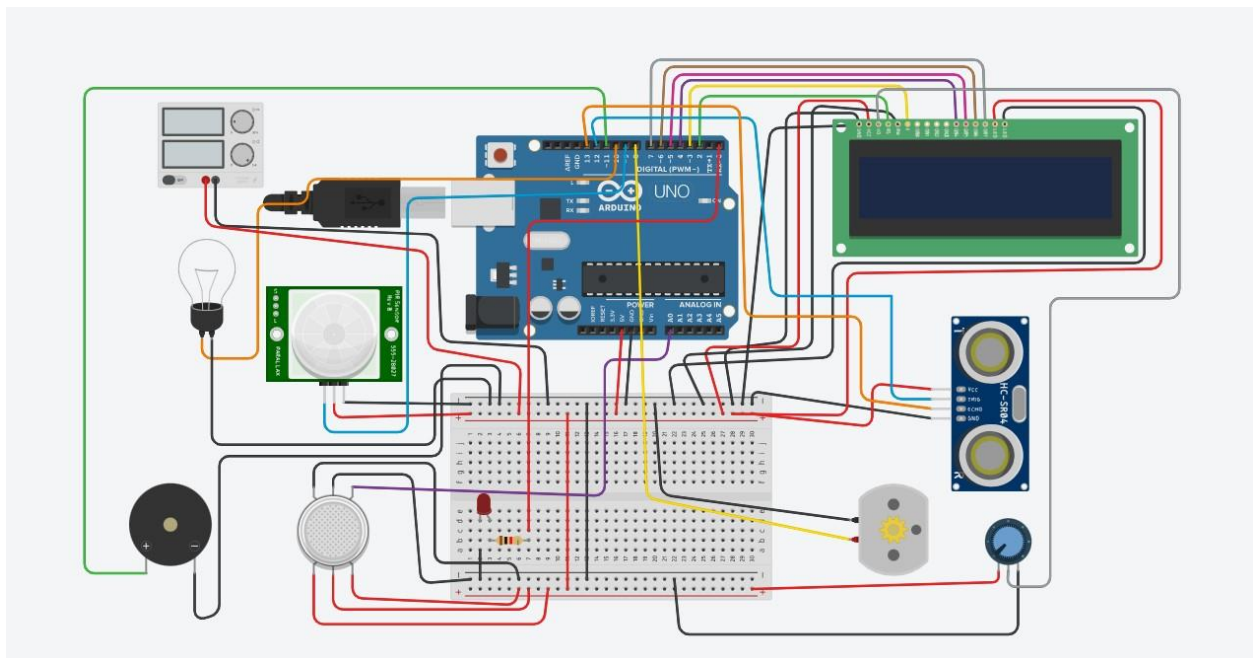
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ASSIGNMENT 1

SMART HOME IN TINKERCAD USING 2+ SENSORS •

Circuit Diagram

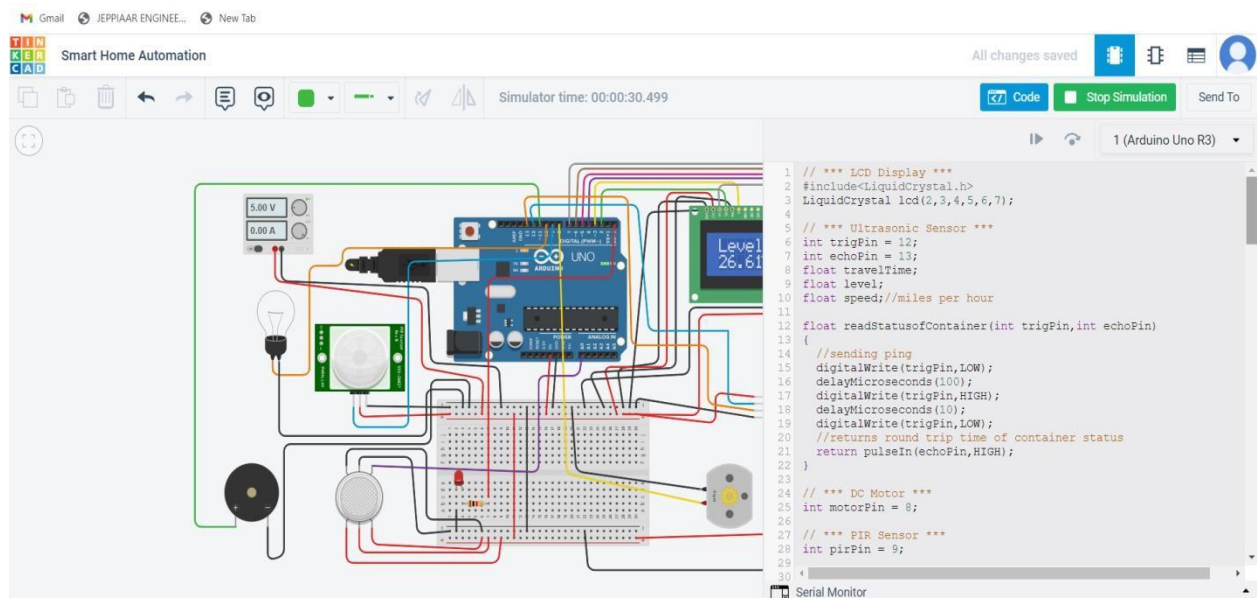


• Components Required:

Name	Quantity	Component
U1	1	Arduino Uno R3
DIST1	1	Ultrasonic Distance Sensor
M1	1	DC Motor
U2	1	LCD 16 x 2
P1	1	21 , 5 Power Supply

PIR1	1	20.722593638638443 , 237.58262756842853 , -
		197.9092690878765 , - 253.1130883508938 PIR Sensor
L2	1	Light bulb
GAS1	1	Gas Sensor
PIEZO1	1	Piezo
R1	1	10 k Ω Resistor
Rpot1	1	250 k Ω Potentiometer
D1	1	Red LED
R2	1	330 Ω Resistor

- Running Simulation in Tinkercad



- Code:

```
// *** LCD Display ***
```

```

#include<LiquidCrystal.h>
LiquidCrystal lcd(2,3,4,5,6,7);

// *** Ultrasonic Sensor ***
int trigPin = 12; int echoPin
= 13; float travelTime; float
level; float speed;//miles
per hour

float readStatusofContainer(int trigPin,int echoPin)
{
    //sending ping  digitalWrite(trigPin,LOW);
    delayMicroseconds(100);
    digitalWrite(trigPin,HIGH);
    delayMicroseconds(10);
    digitalWrite(trigPin,LOW); //returns round
    trip time of container status
    return pulseIn(echoPin,HIGH);
}

// *** DC Motor ***
int motorPin = 8;

// *** PIR Sensor ***
int pirPin = 9;

// *** Light ***
int lightPin = 10;

// *** Gas Sensor *** int
gasPin = A0;
int threshold = 400;

// *** Piezo *** int
buzzPin = 11;

// *** LED ***
int ledPin = 0;

void setup()
{
    Serial.begin(9600);

    // *** LCD Display ***
    lcd.begin(16,2);

```

```

// *** Ultrasonic Sensor ***
pinMode(trigPin,OUTPUT);
pinMode(echoPin,INPUT);

// *** DC Motor ***
pinMode(motorPin,OUTPUT);

// *** PIR Sensor ***
pinMode(pirPin,INPUT);

// *** Light ***
pinMode(lightPin,OUTPUT);

// *** Gas Sensor ***
pinMode(gasPin,INPUT);

// *** Piezo ***
pinMode(buzzPin, OUTPUT);

// *** LED ***
pinMode(ledPin,OUTPUT);
}

void loop()
{
  // *** Trash can monitoring ***
  // Trash can height 5 inches
  travelTime = readStatusofContainer(trigPin,echoPin);//microseconds
  travelTime = travelTime/1000000;//seconds  travelTime =
  travelTime/3600;//hours  speed = 60.0;//miles per hour(86.4 for 5
  inches)  level = speed * travelTime;//miles
  level = level/2;//because travelTime is round trip time
  level = level * 63360;//inch
  if(level <= 4.5)
  {
    //dispaly status
    lcd.clear();
    lcd.setCursor(0,0);
    lcd.print("Trash Level:");
    lcd.setCursor(0,1);
    lcd.print(level);
    lcd.print(" inches");
    delay(100);
  }
}

```

```

else
{
    //display status
    lcd.clear();
    lcd.setCursor(0,0);
    lcd.print("Trash is full");
    lcd.setCursor(0,1);
    lcd.print(level);
        lcd.print(" inches away");
        delay(100);
}

// *** Water level monitoring ***
// Water tank height 20 inches
    travelTime = readStatusofContainer(trigPin,echoPin);//microseconds
travelTime = travelTime/1000000;//seconds  travelTime =
travelTime/3600;//hours  speed = 240.1;//miles per hour(345.3 for
20 inches)  level = speed * travelTime;//miles
    level = level/2;//because travelTime is round trip time
level = level * 63360;//inch  if(level <= 19.0)
{
    //display status and Turn on motor
    digitalWrite(motorPin,HIGH);
    lcd.clear();
    lcd.setCursor(0,0);
    lcd.print("Level:  Motor");
    lcd.setCursor(0,1);
    lcd.print(level);
        lcd.print(" in  On");
    delay(100);
}
else
{
    //display status and Turn off motor
    digitalWrite(motorPin,0);
    lcd.clear();
    lcd.setCursor(0,0);
    lcd.print("Level:  Motor");
    lcd.setCursor(0,1);
    lcd.print(level);
        lcd.print(" in  Off");
    delay(100);
}

```

```

// *** Motion Detection
if(digitalRead(pirPin)==HIGH)
    digitalWrite(lightPin, HIGH);
else
    digitalWrite(lightPin, LOW);
delay(100);

// *** Detects flammable gases ***
if(analogRead(gasPin) >= threshold) {
    digitalWrite(ledPin,HIGH);
    digitalWrite(buzzPin,HIGH);
}
else
{
    digitalWrite(ledPin,LOW);
    digitalWrite(buzzPin,LOW);
}
delay(100);
}

```

- **Output:**

