

Smart Waste Management System For Metropolitan Cities

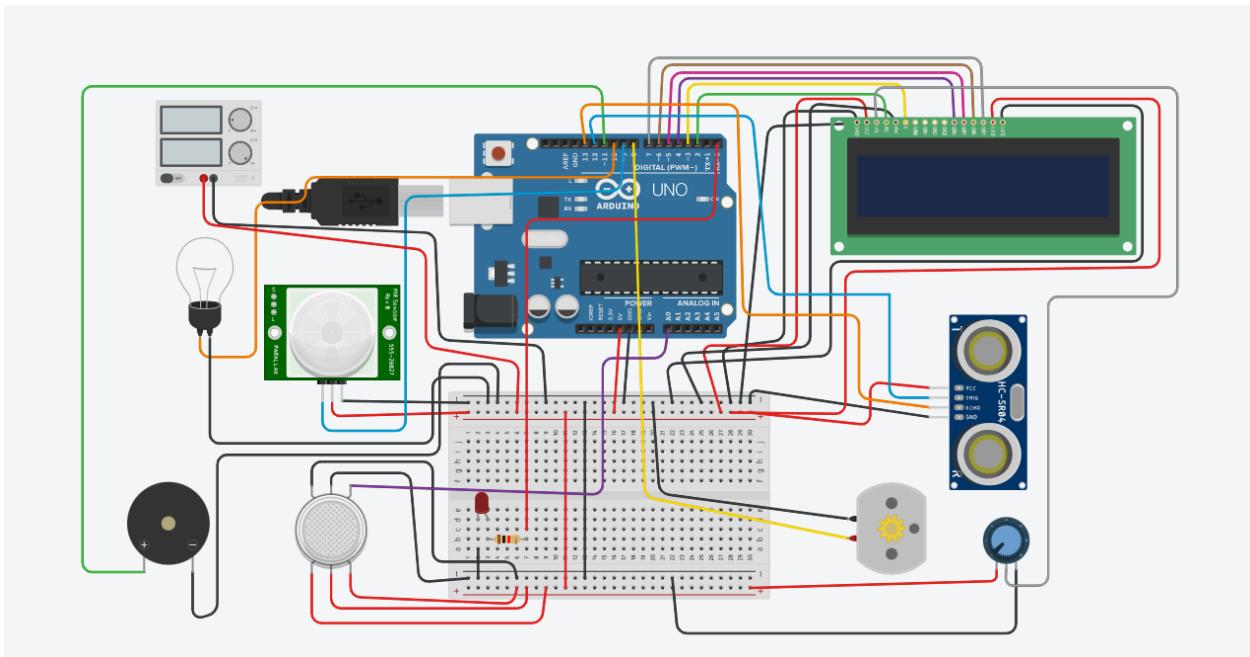
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ASSIGNMENT 1

SMART HOME IN TINKERCAD USING 2+ SENSORS

- Circuit Diagram

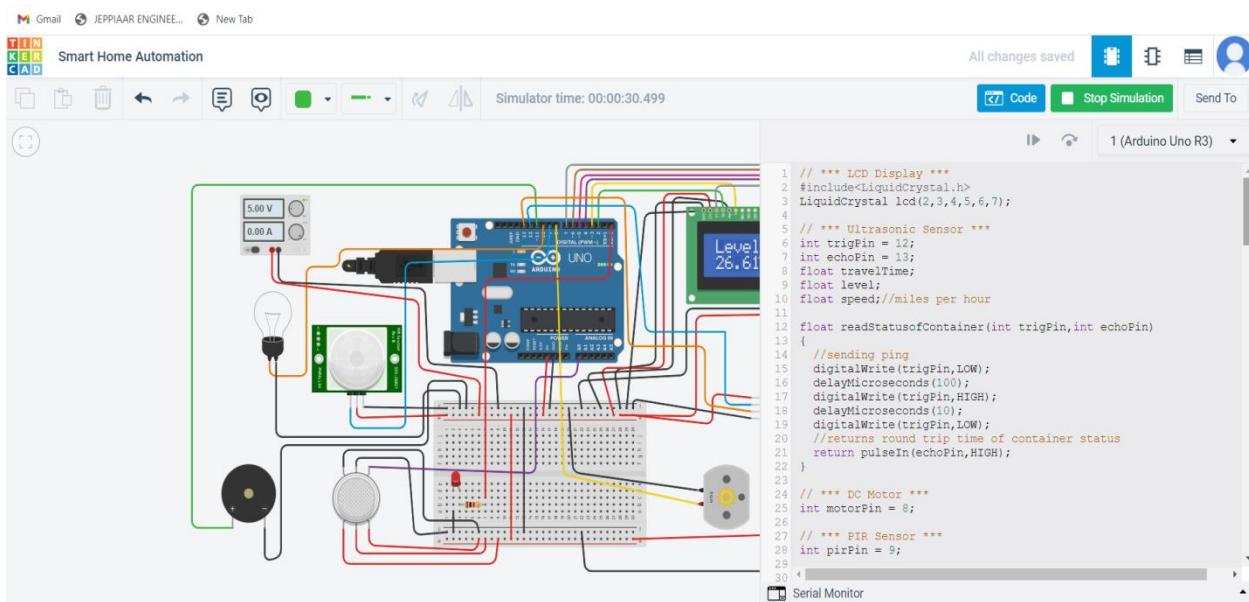


- Components Required:

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
PIEZ01	1	Piezo
R1	1	10 k Ω Resistor
Rpot1	1	250 k Ω Potentiometer
D1	1	Red LED
R2	1	330 k 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
    {
        //dispaly 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:**

