A Low-Cost Approach to Autonomous Litter Collection

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# Part A: Introduction and Background

## Chapter 1: Introduction to Domain

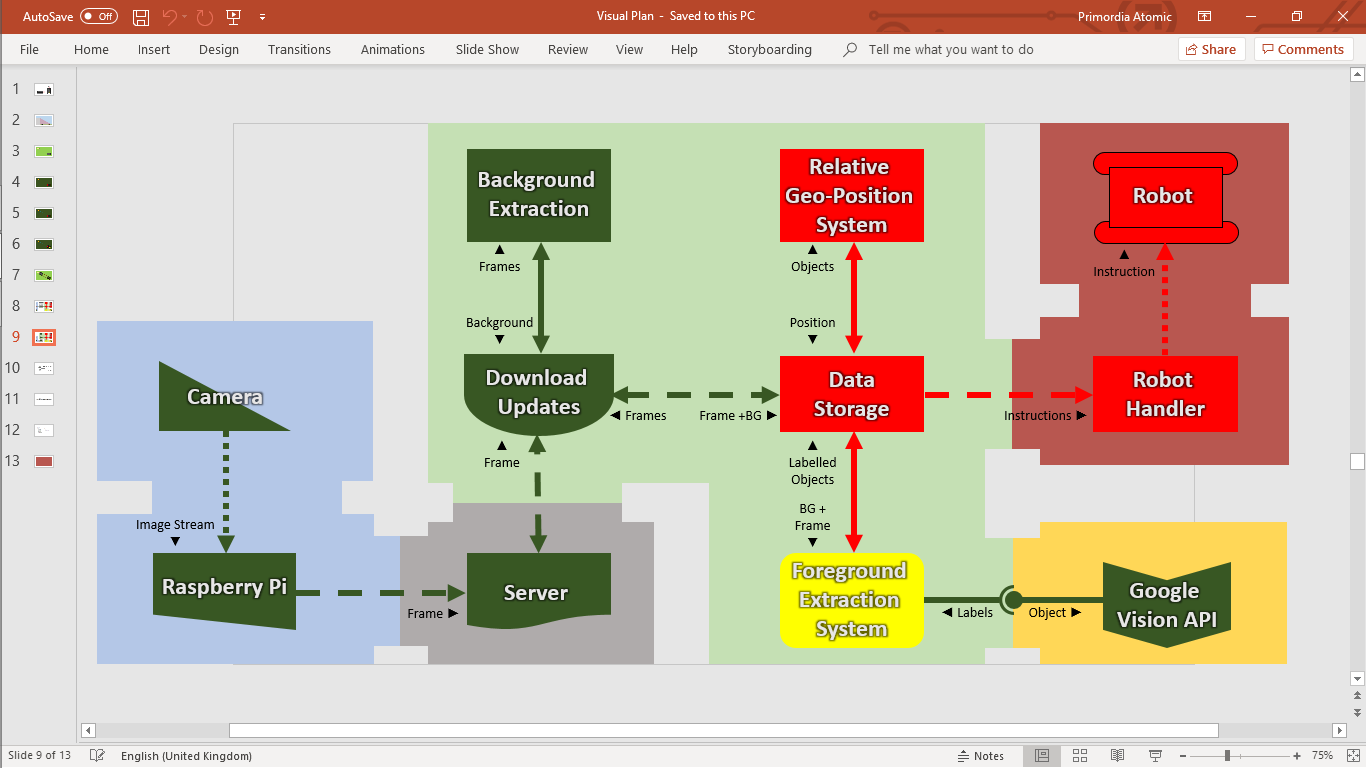
The aim of the project is to design and develop an autonomous system to deploy a robot to pick up litter. The project is focused around the requirements of the system being low-cost, low-maintenance, and high-efficacy. To ensure these requirements are met, special emphasis is placed on them during the decision-making processes throughout the development.

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| Abstract—Path motion object detection based on video is a fundamental part of intelligent transportation systems, In the aspect of background extraction, this paper compared all existing theories and algorithms, aimed at specific objects (city expressways or high-speed Road), and combined with the virtual loop set method. This paper proposed an extraction and updating algorithm based on the sub-segmentations of invariant background, which greatly increased the time efficiency of the background extraction. It achieved great results of accuracy and real-time of this algorithm under background extraction. |
| With the application of autonomy invading all areas, I say why not anti-littering  What are the biggest hurdles preventing autonomy in different areas?   * Cost? Effectiveness? Maintenance/Complexity? Social/Legal/Ethical?   This project plans to investigate, design and develop an autonomous system to deploy a robot to identify litter within an independent live video feed. |

## Chapter 2: Background Domain Research

# Part B: Methodology:

The project is broken down into different methods, in each chapter, a section of the methodology will be researched, tested, implemented, and evaluated. The development will continue from these decisions and follow a plan of progression so as development continues, the systems progression will be clear.



FOR EACH CHAPTER , LIST THE DECISIONS MADE FOR NOW

## Chapter 3: Wireless Surveillance System and File Transfer

### Requirement Definition:

### Research:

Was going to use Wired USB Camera but Changed to use (wireless)/Wi-Fi Camera as wired didn’t allow for having multiple cameras over a large area. This was simpler and easier to implement for cost reduction.

Changed to use Wired USB Camera connected to RPI as it was easier than connecting cam to internet or setting up own campus-wide subnet or adding own routers for each Wi-Fi cam.

Was going to use FTP to connect directly with desktop… didn’t have admin perms to do so, so for the sake of the report a server is used as a middle ground where the cam publishes to, and the processing unit subscribes to.

Update speed justification…?

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| RESEARCH POINTS: |

### Design:

### Testing:

### Implementation:

### Evaluation:

## Chapter 4: Background and Foreground Extraction

### Research:

Significant research concluded for this…

Various image stacking algorithms have been tested beginning with mean stacking, it was removed as a day-night cycle and weather shifts would drastically change the overall appearance of the images.

Entropy blurring was attempted but the implementation for such a system meant the quality of images were reduced making small objects harder to identify.

Stacking with edge detection was tested, however for it to work the quality of the camera needed to be improved, and the material patterns on the floor, greatly impacted the quality of the output.

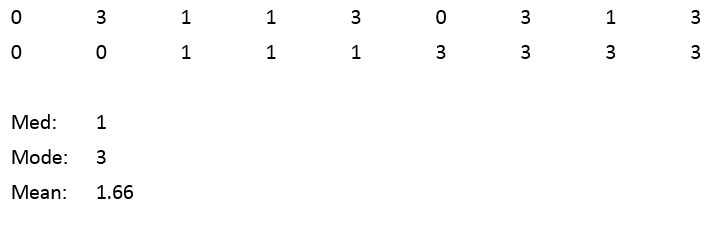
Mode stacking on a relatively small timed cycle was found to be the most effective and allow the smallest impact of changes. The only issue currently remaining is random parts have high values when they should not… so more development needs to be put into making this work smarter. The maths behind why this is so effective at detecting change stems from the lack of maths. Mean is impacted by random sparks, and when there is a lot of change, it cannot identify the background. While mode is not impacted by random changes. It takes what is most static in the frame-set, which should always represent the background.

Foreground Extraction is background subtraction. It is simply the new frame minus the background, where the value is 0 or near-0 then there is no change and should be disregarded.

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| RESEARCH POINTS: |

### Testing:

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### Implementation:

### Evaluation:

## Chapter 5: Object Identification and Litter Filter

### Research:

Object identification was originally planned to extract many features form the objects and apply SVM on them to classify against a dataset or labelled data. This was changed to use the Google Vision API, as the dataset of labelled data and its accuracy is much higher then what could be achieved in the time frame.

I may come back to it later on in the project and develop a custom model from the Google ML API.

For the litter filter; essentially, I need to list out all valid matches…. How do I choose what is defined as trash though? TESTING WITH RESPONSES FROM GOOGLE VISION API REQUIRED 2

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| RESEARCH POINTS: |

### Testing:

### Implementation:

### Evaluation:

## Chapter 6: SLAM System

### Research:

I kindda have an idea. We use the footage from the camera to find the relative position of the trash returned from the object identification and calculate how much the robot must rotate until its head and tail line up pointing at the trash. Then we move it forward until it hits the trash.

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| RESEARCH POINTS:  [ <https://en.wikipedia.org/wiki/List_of_SLAM_Methods> ] |

### Testing:

### Implementation:

### Evaluation:

## Chapter 7: Robot Development/Build

### Research:

Decided to begin with the low-cost approach of using a basic toy off-the-shelf £12 RC car, and rewiring it. Breadboarding a motor driver chip to control it was not successful and broke the Pi, diodes, LEDs, and breadboard. So, decided to look for pre-built alternatives, many worked off of Arduino Uno, and this gave me an idea of prices. I bought a kit for £30, however it did not include the electronics or any assembly instructions, so it was returned. A motor control board was bought prebuilt for £10.

… PENDING RESULTS…

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| RESEARCH POINTS:  <https://www.amazon.com/gp/product/1457186039/ref=as_li_qf_sp_asin_il_tl?ie=UTF8&camp=1789&creative=9325&creativeASIN=1457186039&linkCode=as2&tag=therobpod-20&linkId=QHNJA3OMPG5P7T4Z> |

### Testing:

### Implementation:

### Evaluation:

## Chapter 8: Robot Communication and Movement Systems

### Research:

### Testing:

### Implementation:

### Evaluation:

# Part C: Conclusion

## Chapter 9: Evaluation through Metrics

## Chapter 10: Achieving the Aim

## Chapter 11: Changes to Development

# Part D: Reflective Analysis

## Chapter 12: WW and EBI

## Chapter 13: Further Research / Research Limitations

# Part E: References