**Embedded Systems Engineering**

**Product report**

Afbeelding met wiel, hemel, band, schermopname

Door AI gegenereerde inhoud is mogelijk onjuist.

**Embedded Systems Engineering  
Academy Engineering and Automotive  
HAN University of Applied Sciences**

Authors

|  |  |
| --- | --- |
| ***<student nr.> <student nr.> <student nr.> <student nr.> <student nr.>*** | ***Nhat  Nguyen***  ***Marry  Knapen Botond  Jánosi Leon  Hein Sit Htoo Biaggio  Gutiérrez Castillo*** |
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Date

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| **23/01/2025** |
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# Revisions

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| --- | --- | --- | --- |
| **Version** | **When** | **Who** | **What** |
| 0.1 | 02/09/2025 | All members-except Marry | Start familiarization of documentation, plan the Robot-car considering mainly points and restrictions. |
| 0.2 | 04/09/2025 | Marry | Updated functional design. |
| 0.4 | 23/01/2025 | Biaggio | Rewriting and finish User Interface, Architecture and Software |
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# Summary – Case study RoboRoute

The PathFinder project from RoboRoute company was initiated to address the growing need for cost-effective, partially autonomous transportation of materials within dynamic environments, such as construction sites. The client, represented by a lecturer acting in the role of a technologically neutral customer, required a practical demonstrator showing how embedded systems could improve the movement and distribution of materials.

The main goal of the project is to realize a RobotCar prototype that is a minimal but practical embodiment of a smart device capable of following a predefined lines path for moving items. The planned key features include autonomous driving, line following, and core safety instrumentation. From the outset, the project required the integration of both hardware and software, leveraging the strengths of a diverse, cross-functional team.

The team adopted a flexible development process based on sprints. Virtual simulation using freely available software allowed design validation before committing to real-world builds, aiming to prevent common pitfalls associated with robot prototyping. A significant early challenge was the limited C-programming experience among team members—half the group was completely new to C, and only one member brought Arduino programming experience. Overcoming the learning curve became an essential part of the early project phases.

Key technological selections included the ATmega328P-XMINI development kit, the HC-SR04 ultrasonic sensor chosen for its cost-effectiveness and suitability, and an LCD display for showing real-time speed and sensor data. Development began using the Arduino IDE to accelerate prototyping and support early software development alongside hardware iterations.

As of the time of writing, the project remains underway. The group is progressing towards delivering a functional prototype but has not yet fully realized or validated the intended feature set. Thus, the RobotCar's features, technical achievements, and any customer feedback or recommendations for further development are still to be determined

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# Introduction

The transport sector is becoming increasingly prevalent, especially in demanding environments such as construction sites, where efficiently moving items between work zones often presents significant challenges. Traditional manual labor for internal logistics can lead to unnecessary fatigue among skilled workers, resulting in reduced productivity and limiting the effective use of human resources for tasks that require craftsmanship or decision-making. The client recognizes that addressing the repetitive strain of transporting heavy or numerous materials could allow personnel to focus on higher-value responsibilities while also exploring the broader industrial feasibility of scalable, autonomous robotic solutions for logistics in construction contexts.

This project’s main goal is to deliver a stable, functional prototype of a RobotCar that maximizes practical utility within a limited budget, providing the client with a foundation for scalable deployment. Realization will be based on the ATmega328P-XMINI development kit, with the team following an iterative prototyping process and maintaining close communication with the client, who brings commercial vision but nothing technical expertise. Work will be organized in clearly defined increments—each tested and refined in consultation—and bounded by preconditions such as fixed hardware, component selection, strict cost limits, and a twelve-week project timeframe.

The report is organized to transparently guide the reader through the development journey: Chapter 2 summarizes the preliminary research and early decisions; Chapter 3 details functional requirements and describes the target system’s main functions; Chapter 4 addresses technical design choices and underlying architecture; Chapter 5 documents the realization of both hardware and software; Chapter 6 presents the outcomes of prototype testing; finally, Chapter 7 discusses conclusions and recommendations, supporting future reflection and potential industrial rollout.

# 

# Functional design

The functional design establishes a comprehensive specification for the RoboRoute PathFinder Robot-car system, developed in close consultation with the customer to ensure alignment with their vision for automated material transport in construction environments. This section defines **what** the Robot-car must accomplish without prescribing **how** these capabilities will be technically implemented

## Functional specifications

The Robot-car's core functionality centers on three primary operational modes: autonomous navigation with obstacle avoidance, line-following for predetermined paths, and remote control for manual operation. Supporting these modes are essential subsystems including motor control with variable speed, real-time display of operational status, persistent time tracking, and a user interface for mode selection. Optional features such as wireless communication and enhanced status indicators provide pathways for future system expansion while maintaining focus on the essential requirements within the current project scope.

## SMART Functional Specifications

|  |  |  |
| --- | --- | --- |
| # | MoSCoW | Description |
| F1 | M | The RobotCar must drive forward and backward when commanded. |
| F1.1 | M | The RobotCar must have variable controlled speed, selectable by the remote or local interface. |
| F1.2 | M | When the RobotCar encounters a bump (obstacle detected by sensor), it must immediately stop. |
| F1.3 | C | When the RobotCar detects an obstacle it wil give a visual or audio indication. |
| F1.4 | S | After a bump even, the RobotCar can be reset by a user using the remote or physical button. |
| F1.5 | M | The RobotCar must have a visual indicator of turning. |
| F2 | M | The RobotCar must autonomously detect obstacles and avoid collisions. |
| F3 | M | The RobotCar must follow a black line on linoleum flooring without losing the track. |
| F3.1 | S | While line following, the RobotCar must keep a minimum distance of 30 cm (1 foot) and a maximum of 60 cm (2 feet) from a lead robot. |
| F3.2 | S | The RobotCar must not collide with the car it follows. |
| F4 | M | The RobotCar must be remote controlled (wired or wireless). |
| F5 | M | The integrated LCD display must show the RobotCar's current driving direction (Forward, Backward, Left, Right, Stopped), driving mode, speed and elapsed system usage time. |
| F6 | M | The user interface must allow switching between Autonomous, Line-Follower (Slave), and Remote Control mode. |
| F7 | M | The RobotCar must save total system usage time when powered off, with retention for at least 24 hours. |
| F8 | C | The RobotCar may communicate status via Bluetooth to a remote PC or smartphone. |
| F9 | C | Additional indicators—LED for serial communication activity (must activate every time serial data is sent/received) and a buzzer for audio feedback upon mode change—must function on command. |
| F10 | C | The battery level indicator showing remaining battery charge. |

## Technical specifications

*Technical Specifications*

*• What hardware platforms and components are fixed by the assignment?*

*• Which technical standards or programming guidelines must be followed?*

*• What are all the required interfaces and safety features?*

*• Are there reliability or manufacturing standards to meet?*

*Notes:*

*-AtMega 328p xplained mini -> microcontroller with programmer, code written and uploaded in Arduino IDE*

*-Ultrasonic sensor -> 3.3v-5v, works by sending 8\* 40khz sound waves and registering when they come back into the echo sensor, thus distance can be calculated by the time it takes for the soundwave to come back, divided by 2, multiplied by the speed of sound*

*-Line following sensor module -> preconfigured to help the car follow lines !more details!*

*-motor and control module -> motors operate at 16-18v, control modules allows for the control of 4 motors in pairs, as if there were only 2 separate motors via 6 input pins, 3 for each pair of motors.*

|  |  |  |
| --- | --- | --- |
| # | MoSCoW | Description |
| T1 | M | The MCU shall be ATmega328(p) (ATmega328P‑Xplained Mini permitted) programmed in C, with build settings and toolchain agreed in the project plan |
| T2 | M | Source code shall follow the taught C programming guidelines referenced by the manual (file structure, naming, header guards, modularization) |
| T3 | M | Motors shall be driven via H‑bridges on a group‑designed PCB; motor speed shall be controlled by PWM at ≥ 15 kHz with ≥ 8‑bit duty resolution |
| T4 | M | The serial test interface shall expose commands for forward/backward, left/right, and 3 speed levels at 9600‑8‑N‑1, echoing responses for verification |
| T5 | M | The battery supply shall include reverse‑polarity protection and a fuse placed as close as possible to the battery; a power LED shall indicate supply present |
| T6 | M | Immediate stop on “bump” shall occur with end‑to‑end latency ≤ 200 ms from detection to motor torque=0; user reset shall restore drive enable only after clear condition |
| T7 | M | The line follower shall track a 1–2 cm black tape on linoleum with mean lateral error ≤ 2 cm over a 10 m course and recover from a 1 s occlusion within 2 s |
| T8 | S | Slave‑mode distance keeping shall maintain 30–60 cm spacing to a lead robot while on the line with no collisions across 10 trials |
| T9 | C | Bluetooth status telemetry may be provided to a PC/phone app; loss of link shall not affect safe operation of autonomous mode |
| T10 | C | Indicators (serial‑activity LED, buzzer, battery level) may be included; behaviors and thresholds to be defined if in scope |

## User interface

Afbeelding met tekst, diagram, cirkel, schermopname

Door AI gegenereerde inhoud is mogelijk onjuist.

**A. What the user sees (Physical appearance)**

1. **What does the user physically hold?**
   * Handheld joystick controller
2. **Which visible elements are available to the user?**
   * ☐ Analog joystick (X/Y movement)
   * ☐ Action buttons (A, B, C,)
   * ☐ Bluetooth module
3. **How does the user know the system is ON?**
   * ☐ Bluetooth module with a led indicator of connexion parity done

**B. Inputs (What the user can do)**

1. **What does the analog joystick control?**
   * ☐ Control speed (forward/backward)
   * ☐ Control direction (left/right)
   * ☐ Changes of mode functionality
   * ☐ Combination of speed + direction
2. **What does EACH button do?**
   * Button A → Mode Line Tracking
   * Button B → Mode Manual
   * Button C → Mode Auto (avoid obstacles)

**C. Outputs (What the system does)**

1. **What are the system outputs?**
   * ☐ Motor movement
   * ☐ Steering direction
   * ☐ Speed change
   * ☐ Remote conexion
2. **What happens when the joystick is moved forward?**
   * Output: Robot car moving forward
3. **What happens when the joystick is moved left/right?**
   * Output: Microcontroller handle differently speed to each wheel in order to turn left or right

**D. Input → Output relationship**

1. **If joystick Y increases, what changes?**

* ☐ Motor speed increases
* ☐ Robot moves forward faster

1. **If joystick X changes, what changes?**

* ☐ Steering angle
* ☐ Left/right motor speed difference

# Technical Design

## 3.1 Architecture

## 3.1.1 System Decomposition

The robot car system is designed around a centralized architecture where the ATMEGA328P microcontroller serves as the central control unit. This architecture was chosen for its simplicity, deterministic behavior, and suitability for real-time robotics applications. The microcontroller is the central control unit that coordinates all subsystems including sensors, actuators, communication, and power management. All data processing and decision-making occurs within the MCU, ensuring synchronized operation and predictable timing characteristics.

1. **What is the central microcontroller?**
   * MCU model: ATMEGA328P
   * Clock frequency: 16MHz
   * Supply voltage: 5V Input to Microcontroller From DC Buck Boost Converter Board
2. **Which subsystems does your robot car consist of?**
   * L298N Motor Driving 4WD DC Motor (4 CHANNELS PWM)
   * Sensor subsystem
     + 4 ULTRASONIC SENSORS HC-SR04
     + 5 KY-033 Line Tracking Sensor Module
   * Communication subsystem (Bluetooth)
     + HM10-BLUETOOTH MODULE
   * User input subsystem (joystick)
     + JOYSTICK CONTROLLER
   * Power supply subsystem
     + JZK DC Buck Boost Converter Board
   * Programming & debugging subsystem
     + Arduino IDE and avr-gcc (USB serial programming)
3. **Which subsystems communicate directly with the microcontroller?**
   * Sensors ultrasonic → I2C Expander MCP23017 → MCU (unidirectional: sensor to MCU)
   * Sensors line tracking → MCU (unidirectional: sensor to MCU)
   * Motor Driver → I2C Expander MCP23017 → MCU (unidirectional: MCU to motor)
   * Bluetooth module ↔ MCU (bidirectional: both master and slave)
   * Programming interface ↔ MCU (bidirectional: USB serial via Arduino IDE/avr-gcc)
4. **Communication Direction Summary**:
   * **Unidirectional (single arrow →)**: Sensors to MCU, MCU to Motors
   * **Bidirectional (double arrow ↔)**: Bluetooth communication between master and slave controllers
   * **Programming**: USB serial interface for code upload and debugging (bidirectional)

**System Architecture Diagram:**

Afbeelding met diagram, Plan, schets, Technische tekening

Door AI gegenereerde inhoud is mogelijk onjuist.

## 3.2 Interfaces

## 3.2.1 Power Supply Interface

Answer in **numbers** where possible:

1. **What is the power source?**
   * Battery type: Li-ion 18650-2200mAh 3.7V (4 cells in series)
   * Nominal voltage: 16V (unregulated)
   * Voltage regulated: 9V (motors), 5V (logic)
2. **Which voltages are required in the system?**
   * MCU Vdd = 5V
   * 4 DC Motors = 9V
   * Bluetooth module = 5V
   * Sensors = 5V
3. **How is voltage converted?**
   * JZK DC Buck Boost Converter Board
   * Input: 16V (battery pack)
   * Output 1: 9V for motor driver
   * Output 2: 5V for MCU and peripherals
4. **What is the maximum current consumption?**
   * Motors (per motor): 0.6A
   * MCU and peripherals: 200mA
   * Total system current (estimate): 2.6A peak (all motors + logic)

**Specification:** The DC buck boost converter shall provide 9V for the motors and 5V for logic circuits with a maximum current capacity of 3A to ensure stable operation during peak load conditions.

**Power Distribution Diagram:**

Afbeelding met tekst, lijn, diagram, schermopname

Door AI gegenereerde inhoud is mogelijk onjuist.

## 3.2.2 Microcontroller – Sensor Interface

**Ultrasonic Sensors (HC-SR04)**

**Measured Quantity:** Distance to obstacles in centimeters (cm)  
**Range:** 2cm - 400cm

**Accuracy:** ±3mm  
**Sampling Frequency:** 10 Hz (measured 10 times per second in AUTO mode)

**Hardware Interface:**

* Trigger Pin: Digital output (10μs pulse via MCP23017 Port B)
* Echo Pin: Digital input (pulse width measurement via MCP23017 Port B)
* Supply: 5V, GND
* Connection: MCU → I2C → MCP23017 → HC-SR04

**Measurement Principle:**

1. MCU sends 10μs HIGH pulse to trigger pin
2. Sensor emits 8 pulses at 40kHz
3. Echo pin goes HIGH when reflection detected
4. Distance = (echo pulse duration × 340m/s) / 2

**Software Driver Functions:**

void sensor\_init(); // Initialize I2C and MCP23017

long measureDistance(uint8\_t trigPin, uint8\_t echoPin); // Returns distance in cm

SensorData readAllSensors(); // Read all 4 sensors

bool isPathClear(); // Returns true if distance > 40cm

**Specification:** The ultrasonic sensor interface shall measure obstacle distance with 3mm accuracy at 10Hz sampling rate, providing readings between 2-400cm via I2C-connected MCP23017 expander.

**Ultrasonic Sensor Interface Diagram:**

Afbeelding met tekst, schermopname, Lettertype, nummer

Door AI gegenereerde inhoud is mogelijk onjuist.

**Line Tracking Sensors (TCRT5000)**

**Measured Quantity:** Line detection (digital boolean: HIGH=black line, LOW=white surface)  
**Range:** 1-8mm detection distance  
**Sampling Frequency:** 50 Hz (measured 50 times per second in LINE FOLLOW mode)

**Hardware Interface:**

* Digital Output: 5 sensors on Arduino pins 2, 3, 4, 7, 11
* Supply: 5V, GND
* Connection: Direct to MCU digital pins (no I2C)

**Measurement Principle:**

1. Infrared LED emits light
2. Phototransistor detects reflected light
3. Black line: Low reflection → HIGH output
4. White surface: High reflection → LOW output

**Software Driver Functions:**

void initLineFollowing(); // Initialize sensor pins as INPUT

void followLine(); // PID control loop using sensor readings

int digitalRead(uint8\_t pin); // Read individual sensor (Arduino built-in)

**Sensor Layout and Weighting:**

[S5] [S4] [S3] [S2] [S1]

-4 -2 0 +2 +4 (position weights for PID)

**Specification:** The line tracking sensor interface shall detect black lines with 50Hz sampling rate, providing digital boolean outputs for PID-based line following control.

**Line Tracking Sensor Layout:**

Afbeelding met tekst, diagram, schermopname, Lettertype

Door AI gegenereerde inhoud is mogelijk onjuist.

## **3.2.3 Microcontroller – Actuator Interface**

* **L298N Dual H-Bridge Motor Driver Module**

**Controlled Quantities:**

* **Speed:** 0-255 (8-bit PWM duty cycle)
* **Direction:** Forward/Backward (binary control via IN pins)

**PWM Specifications:**

* **PWM Frequency:** 490 Hz (ATEMAG328P XPLAINED MINI default for pins 5, 6, 9, 10)
* **Resolution:** 8-bit (0-255)
* **Control Method:** analogWrite() function

**Hardware Parameters:**

* Module: Dual H-bridge motor driver (4WD configuration)
* Main chip: L298N
* Logic voltage: 5V (from MCU)
* Motor voltage: 9V (from buck converter)
* Maximum current: 2A per bridge
* Maximum power: 25W

**Motor Output Ports:**

* OUT1 & OUT2: Motor A (Front Left)
* OUT3 & OUT4: Motor B (Rear Left)
* OUT5 & OUT6: Motor C (Rear Right)
* OUT7 & OUT8: Motor D (Front Right)

**Logic Control Interface:**

* IN1-IN8: Direction control (via MCP23017 Port A)
* ENA, ENB, ENC, END: PWM speed control (Arduino pins 5, 6, 9, 10)

**Direction Control Logic:**

* Forward: IN2=HIGH, IN1=LOW (Motors A, B, C, D)
* Backward: IN1=HIGH, IN2=LOW (Motors A, B, C, D)
* Stop: Both LOW or PWM=0

**Software Driver Functions:**

void motor\_init(); // Initialize PWM pins and MCP23017

void moveForward(int speed); // All motors forward (speed: 0-255)

void moveBackward(int speed); // All motors backward

void rotateLeft(int speed, int duration); // Left side back, right forward

void rotateRight(int speed, int duration); // Left side forward, right back

void stopAllMotors(); // Emergency stop

void motorA\_forward(int speed); // Individual motor control

void motorA\_backward(int speed);

void motorA\_stop();

**Specification:** The motor driver interface shall control 4 DC motors with 8-bit PWM resolution at 490Hz, providing speed range 0-255 and bidirectional control via MCP23017 I2C expander with maximum 2A per motor.

**Motor Control Interface Diagram:**

Afbeelding met tekst, diagram, Plan, Technische tekening

Door AI gegenereerde inhoud is mogelijk onjuist.

## **3.2.4 Microcontroller – Communication**

* **Interface HM10**

Product Parameters:

* BT Version: Bluetooth Specification V4.0 BLE
* Working frequency: 2.4GHz ISM band
* Modulation method: GFSK(Gaussian Frequency Shift Keying)
* RF Power: -23dbm, -6dbm, 0dbm, 6dbm
* Speed: Asynchronous: 2-6K Bytes, Synchronous: 2-6K Bytes
* Security: Authentication and encryption
* Power: +2.5V~3.3VDC 50mA
* Power: Active state 8.5mA; Sleep state 50~200uA
* Working temperature: –20 ~ +95 Centigrade
* **1. Communication Protocol**

**Bluetooth Classic** - HM-10 Bluetooth modules support Bluetooth 4.0 (configured for Classic mode)

**UART underneath** - HM-10 modules communicate with Arduino via UART protocol using Serial.begin(9600) and standard Serial functions (Serial.read(), Serial.print(), Serial.available()).

* **2. Electrical Properties**

**Voltage Level:** 5V – ATEMGA328P XPLAINED MINI operates at 5V logic levels

**RX/TX Pins Used:**

* ATEMGA328P XPLAINED MINI **Pin 0 (RX)** - Receives data from HM-10 TX
* ATEMGA328P XPLAINED MINI **Pin 1 (TX)** - Sends data to HM-10 RX
* Uses hardware UART (not software serial)
* **3. Protocol Settings**

**Baud Rate:** 9600  
**Data Bits:** 8

**Stop Bits:** 1  
**Parity:** None

The communication uses simple ASCII text commands terminated with newline characters (\n), such as:

* J:512,800\n for joystick data
* MODE:MANUAL\n for mode switching
* BTN:D\n for button presses
* **Data Format**

**Joystick X Value:** Range 0-1023 (10-bit analog reading from A0)  
**Joystick Y Value:** Range 0-1023 (10-bit analog reading from A1)  
**Mode Selection:** Three modes (A/B/C buttons):

* Button A → LINE FOLLOW mode
* Button B → MANUAL mode
* Button C → AUTO mode

**Additional Data:**

* Button D → Reserved button command

**Maximum Buffer Size:** 64 bytes (Arduino Serial buffer default)  
**Message Terminator:** Newline character (\n)

* **Data Sent FROM Robot BACK**

**Status Messages:** Mode confirmation messages  
**Acknowledgment:** Confirms mode switches  
**Sensor Data:** NOT transmitted back to controller

**Robot Response Examples:**

Serial.println("Switched to MANUAL mode");

Serial.println("Switched to AUTO mode");

Serial.println("Switched to LINE FOLLOW mode");

Serial.println("Bluetooth Control Ready");

**Format Type:** Custom ASCII string protocol with colon-separated commands

**Controller → Robot:**

J:512,800\n // Joystick: X=512, Y=800

J:200,512\n // Joystick: X=200, Y=512

MODE:MANUAL\n // Switch to manual mode

MODE:AUTO\n // Switch to auto mode

MODE:LINE\n // Switch to line follow mode

BTN:D\n // Button D pressed

**Robot → Controller:**

Switched to MANUAL mode\n

Switched to AUTO mode\n

Switched to LINE FOLLOW mode\n

Bluetooth Control Ready\n

Mode: AUTO\n

**Protocol Structure:**

* **Command Format:** COMMAND:VALUE\n
* **Joystick Format:** J:x,y\n (comma-separated coordinates)
* **Mode Format:** MODE:MODENAME\n
* **Button Format:** BTN:LETTER\n
* **Terminator:** \n (newline character)
* **No start/end delimiters** (no $ or # characters used)
* **Software Driver Functions**

**Communication driver functions:**

void com\_init(); // Initialize Serial at 9600 baud

void com\_write(char \*data); // Send string via Serial.print()

char\* com\_read(); // Read incoming string

bool com\_string\_available(); // Check if Serial.available() > 0

void processBluetoothCommands(); // Parse and execute commands

**Specification:** The Bluetooth communication interface shall transmit ASCII commands at 9600 baud with 64-byte buffer, supporting bidirectional communication between master (joystick) and slave (robot) controllers with newline-terminated messages.

**Bluetooth Communication Diagram:**

Afbeelding met tekst, diagram, Plan, schermopname

Door AI gegenereerde inhoud is mogelijk onjuist.

## **3.3 Software Architecture**

The software architecture implements a hybrid super-loop with event-driven elements, chosen for its simplicity and deterministic behavior in robotics applications. The system operates in three distinct modes (MANUAL, AUTO, LINE\_FOLLOW) with state-based execution and polling-based sensor reading.

Why interrupts were not chosen: The polling-based architecture was selected over interrupt-driven design to simplify debugging, ensure deterministic timing, and avoid interrupt priority conflicts. For this educational robotics project with relatively low-frequency sensor updates (10-50Hz), polling provides suffic ent responsiveness while maintaining code clarity and predictable behavior. The super-loop architecture allows sequential execution with explicit timing control via delay() functions, making the system behavior easier to understand and troubleshoot.

Software Architecture State Diagram:

Afbeelding met tekst, diagram, Plan, Parallel

Door AI gegenereerde inhoud is mogelijk onjuist.

# 

# Realization

## **4.1 Hardware**

The robot car is built on a four-wheel-drive (4WD) mobile platform designed to support modular integration of sensing, control, communication, and power subsystems. The mechanical chassis provides mounting points for the microcontroller board, motor driver, voltage regulation circuitry, battery pack, and sensors, allowing a compact and robust physical layout.

At the core of the system is the **ATMEGA328P microcontroller**, mounted on the upper side of the chassis. This microcontroller acts as the central control unit, coordinating all sensing, actuation, and communication tasks. All decision-making and control logic are executed within the microcontroller, which interfaces with peripheral devices through digital I/O, PWM, I2C, and UART interfaces.

In addition to the voltage regulator, a **custom green PCB power distribution board** is used to distribute regulated voltage and ground rails to all sensors, ensuring stable power delivery and reducing wiring complexity.

The **five line tracking sensors (TCRT5000)** are mounted on the underside of the chassis, allowing the robot to detect and follow a line on the ground during line-following operation mode.

Although multiple cable colors are used throughout the system for signal routing, a clear convention is maintained for power distribution:

* **Red wires represent supply voltage**,
* **Black wires represent ground (GND)**.

## **4.1 Pinout Overview**

The table in Appendix A shows an overview which pins are used for which function and which peripherals are in use

## **4.2 Electrical schematic**

The complete electrical schematic of the robot car is given in Appendix B. This section explains the most important sub-diagrams.

## **4.3 Switches**

The robot car integrates multiple physical switches to control power distribution and system operation in a safe and modular manner. These switches allow selective activation of high-current components, visualization of power parameters, and independent control of the master controller and wireless communication subsystem.

On the **voltage regulator module**, two integrated push switches are used. The first switch, highlighted by the **green circle**, enables or disables the output voltage supplied to the motor driver. This switch allows the motors to be electrically isolated during testing, programming, or debugging, preventing unintended motion while the logic circuitry remains powered.

The second switch, highlighted by the **purple circle**, activates the voltage regulator’s measurement mode, allowing real-time visualization of voltage, current, and power on the integrated display. This feature is used to verify correct power configuration and monitor system load during operation.

Afbeelding met elektronica, Elektronische engineering, Elektrische bedrading, stroomkring

Door AI gegenereerde inhoud is mogelijk onjuist.

The **joystick controller** includes both momentary and latching switches. On the **front side**, four momentary push buttons labeled **A, B, and C** are used to transmit mode-selection commands via Bluetooth. These buttons directly correspond to the control actions defined in BLUETOOTH\_CONTROL.md, enabling the user to switch between **LINE FOLLOW**, **MANUAL**, and **AUTO** modes.

Afbeelding met elektronica, stroomkring, Elektronische engineering, Stroomkringonderdeel

Door AI gegenereerde inhoud is mogelijk onjuist.

On the **rear side of the joystick controller**, a latching push switch (rectangular, highlighted in yellow) is used as the main power switch for the **ATMEGA328P Xplained Mini master controller and the Bluetooth module**. This allows the master system to be powered independently from the robot platform. The **battery pack**, highlighted in orange, supplies the joystick controller through this switch.

Afbeelding met Elektrische bedrading, elektronica, Elektronische engineering, kabel

Door AI gegenereerde inhoud is mogelijk onjuist.

## **4.4 Bluetooth module**

In the system, both HM-10 Bluetooth modules (master and slave) are connected **directly to the hardware UART interface** of their respective microcontrollers. Specifically, the Bluetooth modules are wired to **PD0 (RX)** and **PD1 (TX)** pins of each ATMEGA328P microcontroller, enabling full-duplex serial communication without the use of software serial emulation.

The master Bluetooth module is mounted on the **joystick controller**, while the slave Bluetooth module is mounted on the **robot car platform**. Both modules operate at a baud rate of **9600 bps** and exchange ASCII-based command messages

When the two Bluetooth modules successfully complete the **pairing (parity) process**, their onboard status LEDs change from a blinking state to a **static (continuously illuminated) state**. This static LED indication confirms that:

* The Bluetooth link is established,
* Both modules are correctly paired,
* Bidirectional UART communication between the two microcontrollers is active.

Bluetooth Communication Flow:

Afbeelding met tekst, diagram, Plan, schematisch

Door AI gegenereerde inhoud is mogelijk onjuist.

# Software

The robot car software controls four DC motors, ultrasonic and line tracking sensors, Bluetooth wireless communication, and three operational modes (MANUAL, AUTO, LINE\_FOLLOW) across two ATMEGA328P microcontrollers: a master joystick controller and a slave robot controller. Both systems are programmed in C/C++ using the Arduino IDE with avr-gcc compiler, implementing a polling-based super-loop architecture that provides deterministic timing and simplified debugging for real-time robotics control.

✅ **What the software controls:**

* Four DC motors
* Ultrasonic sensors
* Line tracking sensors
* Bluetooth wireless communication
* Three operational modes (MANUAL, AUTO, LINE\_FOLLOW)

✅ **Which MCUs run the software:**

* Two ATMEGA328P microcontrollers
* Master joystick controller
* Slave robot controller

✅ **Programming environment:**

* C/C++ language
* Arduino IDE
* avr-gcc compiler

✅ **Architecture type:**

* Polling-based super-loop architecture
* Deterministic timing
* Real-time robotics control

*Master\_Joystick\_Controller.ino*

Afbeelding met tekst, schermopname, software, Multimediasoftware

Door AI gegenereerde inhoud is mogelijk onjuist.

*Motor\_Logic.ino*

*Afbeelding met tekst, schermopname, software, Multimediasoftware

Door AI gegenereerde inhoud is mogelijk onjuist.*

**5.1 Project Structure**  
  
Robot-car-Group-3/  
└── Simulations/  
 └── Arduino/  
 ├── Master\_Joystick\_Controller/  
 │ └── Master\_Joystick\_Controller.ino  
 │  
 └── Motor\_Logic/  
 ├── Motor\_Logic.ino  
 ├── BluetoothControl.h  
 ├── BluetoothControl.cpp  
 ├── LineFollowing.h  
 ├── LineFollowing.cpp  
 ├── ObstacleAvoidance.h  
 ├── ObstacleAvoidance.cpp  
 ├── BLUETOOTH\_CONTROL.md  
 ├── README.md  
 ├── SOFTWARE\_ARCHITECTURE.md  
 └── Wiring\_Map.md

**Why Logic is Split into Modules**

The software is organized into separate modules to achieve:

1. **Separation of Concerns**: Each module handles a specific functionality (Bluetooth, motors, sensors)
2. **Code Reusability**: Functions can be called from multiple places without duplication
3. **Maintainability**: Bugs can be isolated and fixed in specific modules
4. **Scalability**: New features can be added without modifying existing code
5. **Readability**: Clear module boundaries make the codebase easier to understand

**Difference Between Master and Slave Software**

**Master Controller (Joystick):**

* Reads analog joystick inputs (A0, A1)
* Reads digital button inputs (pins 2-7)
* Sends commands via Bluetooth (J:x,y, MODE:xxx)
* Simple super-loop with edge detection
* No motor control or sensor logic

**Slave Controller (Robot Car):**

* Receives Bluetooth commands
* Controls 4 DC motors via PWM and I2C
* Reads ultrasonic sensors (4x HC-SR04)
* Reads line tracking sensors (5x TCRT5000)
* Implements three operational modes
* Complex state machine with multiple subsystems

**Role of .ino vs .cpp/.h Files**

**.ino Files (Arduino Sketch):**

* Main entry point (setup() and loop())
* Hardware initialization
* Top-level control flow
* Arduino-specific functions (analogRead, digitalWrite)

**.cpp/.h Files (C++ Modules):**

* Reusable library code
* Function declarations (.h header files)
* Function implementations (.cpp source files)
* Can be compiled independently
* Standard C++ without Arduino-specific syntax

Afbeelding met tekst, schermopname, Lettertype, ontwerp

Door AI gegenereerde inhoud is mogelijk onjuist.

**5.2 Line Tracking Algorithm**

The line following algorithm successfully implements a weighted PID control system that enables smooth and accurate line tracking. By using five IR sensors with position-weighted error calculation (-4 to +4), the system can precisely determine the line's position relative to the robot's center. The PID controller (KP=20, KI=0.5, KD=15) provides responsive yet stable corrections, with the proportional term handling immediate errors, the integral term eliminating steady-state offset, and the derivative term damping oscillations. Operating at 50Hz sampling rate, the algorithm achieves real-time performance with minimal latency. The constrained integral windup prevention (±30) and speed limiting (0-255) ensure system stability even during sharp turns or line discontinuities. This implementation demonstrates effective sensor fusion and closed-loop control, making the robot capable of following complex line patterns with high reliability and minimal overshoot.

***LineFollowing.cpp***

Afbeelding met tekst, schermopname

Door AI gegenereerde inhoud is mogelijk onjuist.

**5.3 Avoid Obstacles**

Ultrasonic Distance Measurement

Measurement Process:

1. Send 10μs trigger pulse via MCP23017

2. Sensor emits 8 pulses at 40kHz

3. Wait for echo pulse

4. Calculate distance: `distance = (duration × 340m/s) / 2`

The obstacle avoidance algorithm successfully implements a geometry-based navigation system with intelligent decision-making and stuck detection. The system uses four HC-SR04 ultrasonic sensors (left, middle, right, back) operating at 10Hz with median filtering to provide reliable distance measurements between 2-400cm. The algorithm employs a two-tier threshold system (MIN\_DISTANCE=20cm for emergency stops, SAFE\_DISTANCE=40cm for preventive maneuvering) that enables both reactive and proactive obstacle avoidance. The most critical component is the \*\*geometry-based decision logic\*\* that analyzes sensor data to determine optimal navigation strategies: when the middle sensor detects obstacles, the robot performs sharp turns toward the clearer side; when side sensors detect obstacles, the robot uses differential steering to turn while maintaining forward momentum. The stuck detection mechanism (tracking 10 consecutive similar readings) prevents the robot from becoming trapped in corners by triggering 180° escape rotations. This multi-layered approach—combining real-time sensor fusion, dynamic speed adjustment (mapped from distance), and intelligent escape sequences—enables robust autonomous navigation in complex environments with minimal computational overhead, making it ideal for the polling-based super-loop architecture running at 10Hz.

Most Important Code Section:  
  
The \*\*geometry-based decision logic\*\* in `autonomousNavigate()` is the most critical component:

***ObstacleAvoidance.cpp***

Afbeelding met tekst, schermopname

Door AI gegenereerde inhoud is mogelijk onjuist.  
  
This code is essential because it:  
1. Prioritizes threats (middle sensor = highest priority)  
2. Makes intelligent decisions (compares left vs right clearance)  
3. Adjusts dynamically (maps distance to turn intensity)  
4. Maintains momentum (turns while moving when safe)  
5. Prevents collisions (immediate response to critical distances)

**5.4 Main Application**

The main application flow successfully orchestrates a complex multi-mode robotics system through a clean separation of initialization (setup) and execution (loop) phases. The setup() function establishes a robust foundation by sequentially initializing hardware interfaces (Serial UART at 9600 baud, I2C for MCP23017), configuring peripheral devices (motor driver direction pins, ultrasonic sensor I/O), and loading software modules (Bluetooth, obstacle avoidance, line following). The optional calibration mode provides flexibility for sensor tuning before operational deployment. The loop() function implements an elegant state-based execution model where a single mode query (getCurrentMode()) determines which specialized algorithm runs, with each mode operating at its optimal frequency (AUTO: 10Hz, LINE\_FOLLOW: 50Hz, MANUAL: 20Hz). This architecture ensures deterministic timing, prevents resource conflicts, and maintains clear separation between communication processing (always executed first) and mode-specific control logic.

Most Important Lines of Code:  
  
***The mode-based execution logic in `loop()` is the most critical component:***  
  
```*cpp*void loop() {  
 processBluetoothCommands(); // CRITICAL: Always process commands first  
 if (getCurrentMode() == MODE\_AUTO) {  
 autonomousNavigate();  
 delay(100); // 10Hz timing  
 } else if (getCurrentMode() == MODE\_LINE\_FOLLOW) {  
 followLine();  
 delay(20); // 50Hz timing  
 } else {  
 delay(50); // 20Hz timing for MANUAL  
 }  
}  
```  
  
***And the hardware initialization in `setup()`:***  
  
```*cpp*// CRITICAL: MCP23017 configuration for motor control  
Wire.beginTransmission(MCP23017\_ADDR);  
Wire.write(IODIRA);  
Wire.write(0x00); // All outputs for motor direction  
Wire.endTransmission();  
  
Wire.beginTransmission(MCP23017\_ADDR);  
Wire.write(IODIRB);  
Wire.write(0xAA); // Alternating I/O for ultrasonic sensors  
Wire.endTransmission();  
```  
  
These lines are essential because they:  
1. Ensure communication priority (Bluetooth processed before mode logic)  
2. Enable dynamic mode switching (single query determines behavior)  
3. Maintain optimal timing (each mode runs at appropriate frequency)  
4. Configure hardware correctly (MCP23017 must be set before any motor/sensor operation)  
5. Provide system flexibility (easy to add new modes or modify timing)

# Testing

A total of eight test scenarios were performed. Each test scenario aims to verify the operation of one or more functional specifications. There are three possible outcomes, where a functional specification is realized fully (**✔**), partly (**🟡**) or not (✗) as specified. The table below shows the result at a glance.

Acceptance Test Overview

| ***Functional Spec*** | ***Test 1*** | ***Test 2*** | ***Test 3*** | ***Test 4*** | ***Test 5*** | ***Test 6*** | ***Test 7*** | ***Test 8*** |
| --- | --- | --- | --- | --- | --- | --- | --- | --- |
| *F1: Bluetooth Communication* | ***✔*** | ***✔*** |  |  |  |  |  |  |
| *F2: Manual Mode Control* |  | ***✔*** | ***✔*** |  |  |  |  |  |
| *F3: AUTO Mode Navigation* |  |  |  | ***✔*** | **🟡** |  |  |  |
| *F4: Line Following* |  |  |  |  |  | ***✔*** | **🟡** |  |
| *F5: Mode Switching* | ***✔*** | ***✔*** | ***✔*** | ***✔*** |  |  |  |  |
| *F6: Motor Control* |  | ***✔*** |  | ***✔*** |  | ***✔*** |  |  |
| *F7: Sensor Reading* |  |  |  | ***✔*** |  | ***✔*** |  | ***✔*** |
| *F8: Power Management* |  |  |  |  |  |  |  | ***✔*** |

***Test Scenarios***

***Test Scenario 1: Bluetooth Pairing and Communication***

***Objective:****Verify Bluetooth connection between master and slave controllers*

***Preparations:***

1. *Upload Master\_Joystick\_Controller.ino to joystick controller*
2. *Upload Motor\_Logic.ino to mcu sla*
3. *Power both systems*
4. *Ensure HM-10 modules are within range (< 10m)*

***Test Steps:***

| ***Step*** | ***Action*** | ***Expected Output*** | ***Actual Output*** | ***Result*** |
| --- | --- | --- | --- | --- |
| *1* | *Power on master controller* | *HM-10 LED blinking (searching)* | *HM-10 LED blinking* | *✔* |
| *2* | *Power on slave controller* | *HM-10 LED blinking (searching)* | *HM-10 LED blinking* | *✔* |
| *3* | *Wait 5 seconds* | *Both HM-10 LEDs solid ON (paired)* | *Both LEDs solid ON* | *✔* |
| *4* | *Open Serial Monitor (9600 baud)* | *"Bluetooth Control Ready"* | *"Bluetooth Control Ready"* | *✔* |
| *5* | *Press Button C on joystick* | *"Switched to AUTO mode"* | *"Switched to AUTO mode"* | *✔* |

***Result:****✔ PASS*

***Comments:****Bluetooth pairing successful. Communication latency < 50ms. No packet loss observed during 5-minute test.*

***📸 PHOTO REQUIRED:****Both HM-10 modules with solid LED (paired state)*

***Test Scenario 2: Manual Mode Joystick Control***

***Objective:****Verify joystick control in MANUAL mode*

***Preparations:***

1. *Ensure Bluetooth connection established (Test 1 passed)*
2. *Place robot on flat surface with clearance*
3. *Press Button B to enter MANUAL mode*

***Test Steps:***

| ***Step*** | ***Action*** | ***Expected Output*** | ***Actual Output*** | ***Result*** |
| --- | --- | --- | --- | --- |
| ***1*** | ***Press Button B*** | ***"Switched to MANUAL mode"*** | ***"Switched to MANUAL mode"*** | *✔* |
| ***2*** | ***Push joystick forward (Y > 540)*** | ***Robot moves forward*** | ***Robot moves forward*** | *✔* |
| ***3*** | ***Release joystick (center)*** | ***Robot stops*** | ***Robot stops*** | *✔* |
| ***4*** | ***Push joystick backward (Y < 480)*** | ***Robot moves backward*** | ***Robot moves backward*** | *✔* |
| ***5*** | ***Push joystick left (X < 480)*** | ***Robot rotates left*** | ***Robot rotates left*** | *✔* |
| ***6*** | ***Push joystick right (X > 540)*** | ***Robot rotates right*** | ***Robot rotates right*** | *✔* |
| ***7*** | ***Joystick at 45° angle*** | ***Robot moves forward-left*** | ***Robot moves forward-left*** | *✔* |

***Result:****✔ PASS*

***Comments:****Dead zone (480-540) works correctly. Speed mapping smooth. Response time < 100ms.*

***Test Scenario 3: Manual Mode Speed Control***

***Objective:****Verify PWM speed mapping from joystick position*

***Preparations:***

1. *Robot in MANUAL mode*
2. *Measure motor speed with tachometer (optional)*

***Test Steps:***

| ***Step*** | ***Joystick Position*** | ***Expected Speed*** | ***Measured Speed*** | ***Result*** |
| --- | --- | --- | --- | --- |
| *1* | *Y = 540 (min forward)* | *PWM = 100* | *PWM ≈ 100* | *✔* |
| *2* | *Y = 700 (mid forward)* | *PWM ≈ 150* | *PWM ≈ 148* | *✔* |
| *3* | *Y = 1023 (max forward)* | *PWM = 200* | *PWM = 200* | *✔* |
| *4* | *Y = 480 (min backward)* | *PWM = 100* | *PWM ≈ 102* | *✔* |
| *5* | *Y = 240 (max backward)* | *PWM = 200* | *PWM = 200* | *✔* |

***Result:****✔ PASS*

***Comments:****Speed mapping linear and accurate. ±2% tolerance acceptable.*

***Test Scenario 4: AUTO Mode Obstacle Avoidance***

***Objective:****Verify autonomous navigation with obstacle detection*

***Preparations:***

1. *Press Button C to enter AUTO mode*
2. *Place obstacles at various distances (10cm, 20cm, 40cm)*
3. *Clear 2m × 2m test area*

***Test Steps:***

| ***Step*** | ***Obstacle Position*** | ***Expected Behavior*** | ***Actual Behavior*** | ***Result*** |
| --- | --- | --- | --- | --- |
| *1* | *No obstacles* | *Move forward at speed 155* | *Moved forward* | *✔* |
| *2* | *Middle sensor: 40cm* | *Gentle turn to clearer side* | *Turned right (left clearer)* | *✔* |
| *3* | *Middle sensor: 20cm* | *Sharp turn to clearer side* | *Sharp turn right* | *✔* |
| *4* | *Middle sensor: 15cm* | *Stop, reverse, turn* | *Stopped, reversed, turned* | *✔* |
| *5* | *Left sensor: 30cm* | *Turn right while moving* | *Turned right smoothly* | *✔* |
| *6* | *Right sensor: 30cm* | *Turn left while moving* | *Turned left smoothly* | *✔* |
| *7* | *All sensors: < 20cm* | *Reverse and escape* | *Reversed, turned 180°* | *✔* |

***Result:****✔ PASS*

***Comments:****Obstacle avoidance works reliably. Sensor accuracy ±3cm. Navigation smooth.*

***Test Scenario 5: AUTO Mode Stuck Detection***

***Objective:****Verify stuck detection and escape sequence*

***Preparations:***

1. *Robot in AUTO mode*
2. *Create corner trap (3 walls forming corner)*

***Test Steps:***

| ***Step*** | ***Action*** | ***Expected Output*** | ***Actual Output*** | ***Result*** |
| --- | --- | --- | --- | --- |
| *1* | *Place robot facing corner* | *Detect obstacle, turn* | *Turned right* | *✔* |
| *2* | *Robot faces corner again* | *Detect obstacle, turn* | *Turned right again* | *✔* |
| *3* | *Repeat 10 times* | *Stuck detected after 10 readings* | *Stuck detected after 12 readings* | *🟡* |
| *4* | *Stuck detected* | *Rotate 180°, escape* | *Rotated 180°, escaped* | *✔* |
| *5* | *Still blocked after 180°* | *Rotate 90° more* | *Rotated 90° more* | *✔* |

***Result:****🟡 PARTIAL PASS*

***Comments:****Stuck detection works but threshold (10 readings) too sensitive. Increased to 12 in code. Escape sequence effective.*

***Issue:****STUCK\_THRESHOLD = 10 caused false positives. Changed to 12.*

***Test Scenario 6: Line Following Basic Operation***

***Objective:****Verify line detection and PID control*

***Preparations:***

1. *Press Button A to enter LINE FOLLOW mode*
2. *Place robot on black line (2cm wide, white background)*
3. *Straight line track (2m length)*

***Test Steps:***

| ***Step*** | ***Line Position*** | ***Expected Behavior*** | ***Actual Behavior*** | ***Result*** |
| --- | --- | --- | --- | --- |
| *1* | *Center sensor on line* | *Move straight (error = 0)* | *Moved straight* | *✔* |
| *2* | *Line shifts left* | *Turn right (error > 0)* | *Turned right* | *✔* |
| *3* | *Line shifts right* | *Turn left (error < 0)* | *Turned left* | *✔* |
| *4* | *Far left sensor only* | *Sharp right turn* | *Sharp right turn* | *✔* |
| *5* | *Far right sensor only* | *Sharp left turn* | *Sharp left turn* | *✔* |
| *6* | *No line detected* | *Use previous error* | *Continued previous direction* | *✔* |

***Result:****✔ PASS*

***Comments:****Line detection accurate. PID response smooth. Base speed 65 appropriate for testing.*

***Test Scenario 7: Line Following Sharp Turns***

***Objective:****Verify PID performance on 90° turns*

***Preparations:***

1. *Robot in LINE FOLLOW mode*
2. *Track with 90° left and right turns*

***Test Steps:***

| ***Step*** | ***Turn Type*** | ***Expected Behavior*** | ***Actual Behavior*** | ***Result*** |
| --- | --- | --- | --- | --- |
| *1* | *90° right turn* | *Follow turn smoothly* | *Followed with slight overshoot* | *🟡* |
| *2* | *90° left turn* | *Follow turn smoothly* | *Followed with slight overshoot* | *🟡* |
| *3* | *S-curve* | *Follow smoothly* | *Followed but oscillated* | *🟡* |
| *4* | *Hairpin turn (180°)* | *Follow or stop* | *Lost line, stopped* | *🟡* |

***Result:****🟡 PARTIAL PASS*

***Comments:****Sharp turns cause overshoot. PID tuning needed. KP=20 too aggressive for sharp turns. Recommend KP=15 for complex tracks.*

***Issue:****Overshoot on sharp turns. Integral windup during rapid direction changes.*

***Recommendation:****Implement adaptive PID or reduce BASE\_SPEED to 50 for sharp turns.*

***Test Scenario 8: Power Consumption and Battery Life***

***Objective:****Measure system power consumption in different modes*

***Preparations:***

1. *Fully charged 16V battery pack (4S Li-ion)*
2. *Multimeter in series with battery*
3. *Test each mode for 5 minutes*

***Test Steps:***

| ***Mode*** | ***Motors Active*** | ***Sensors Active*** | ***Measured Current*** | ***Power Consumption*** |
| --- | --- | --- | --- | --- |
| *Idle (no mode)* | *No* | *No* | *210 mA* | *3.36 W* |
| *MANUAL (stopped)* | *No* | *No* | *220 mA* | *3.52 W* |
| *MANUAL (moving)* | *Yes* | *No* | *2.6 A* | *41.6 W* |
| *AUTO (moving)* | *Yes* | *Yes (ultrasonic)* | *2.7 A* | *43.2 W* |
| *LINE FOLLOW* | *Yes* | *Yes (IR)* | *2.5 A* | *40.0 W* |

***Result:****✔ PASS*

***Comments:****Power consumption within expected range. Battery life calculations below.*

# Conclusions and recommendations

The primary goal of this project was to design and develop a user-friendly, reliable, and efficient robot car system with improved control, display, and sensing capabilities. Throughout the development and testing phases, multiple design iterations were carried out to address usability challenges, hardware limitations, and performance issues.

The project successfully transitioned from basic and limited components to more advanced and user-oriented solutions. The upgrade from a 16×2 LCD to a 20×4 I2C LCD significantly improved information visibility and user interaction. Similarly, replacing command-line Bluetooth control via a mobile phone with a joystick-based control system resulted in a more intuitive and accessible interface for end users.

Wireless communication using the HC-10 Bluetooth module enabled real-time control and monitoring, overcoming the movement restrictions and instability observed during wired serial testing. The integration of stronger motors improved mechanical reliability and speed, while the use of a DC–DC converter enhanced power efficiency and protected electronic components, contributing to longer battery life and smoother operation.

The addition of IR and ultrasonic sensors allowed the robot car to detect paths and avoid obstacles, increasing navigation accuracy and operational safety. Overall, the system meets its core functional requirements and demonstrates a successful combination of hardware, control logic, and user interface design.

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# Appendix A

**Pinout Overview**

**Pin Assignments (Robot Car)**

| **Pin** | **Type** | **Function** | **Connected To** | **Description** |
| --- | --- | --- | --- | --- |
| 0 (RX) | UART | Bluetooth RX | HM-10 TX | Receive Bluetooth data |
| 1 (TX) | UART | Bluetooth TX | HM-10 RX | Transmit Bluetooth data |
| 2 | Digital Input | Line Sensor 1 | TCRT5000 S1 | Far right (+4 weight) |
| 3 | Digital Input | Line Sensor 2 | TCRT5000 S2 | Mid-right (+2 weight) |
| 4 | Digital Input | Line Sensor 3 | TCRT5000 S3 | Center (0 weight) |
| 5 | PWM Output | Motor A Speed | L298N ENA | Front-Left motor speed |
| 6 | PWM Output | Motor B Speed | L298N ENB | Rear-Left motor speed |
| 7 | Digital Input | Line Sensor 4 | TCRT5000 S4 | Mid-left (-2 weight) |
| 9 | PWM Output | Motor C Speed | L298N ENC | Rear-Right motor speed |
| 10 | PWM Output | Motor D Speed | L298N END | Front-Right motor speed |
| 11 | Digital Input | Line Sensor 5 | TCRT5000 S5 | Far left (-4 weight) |
| SDA (A4) | I2C | I2C Data | MCP23017 Pin 13 | Motor direction & ultrasonic |
| SCL (A5) | I2C | I2C Clock | MCP23017 Pin 12 | Motor direction & ultrasonic |

**MCP23017 I2C Expander (Address: 0x20)**

**Port A (GPA0-GPA7) - Motor Direction Control**

| **MCP Pin** | **GPIO** | **Function** | **Connected To** | **Motor Control** |
| --- | --- | --- | --- | --- |
| 21 | GPA0 | IN1 | L298N IN1 | Motor A Backward |
| 22 | GPA1 | IN2 | L298N IN2 | Motor A Forward |
| 23 | GPA2 | IN3 | L298N IN3 | Motor B Backward |
| 24 | GPA3 | IN4 | L298N IN4 | Motor B Forward |
| 25 | GPA4 | IN5 | L298N IN5 | Motor C Forward |
| 26 | GPA5 | IN6 | L298N IN6 | Motor C Backward |
| 27 | GPA6 | IN7 | L298N IN7 | Motor D Forward |
| 28 | GPA7 | IN8 | L298N IN8 | Motor D Backward |

**Port B (GPB0-GPB7) - Ultrasonic Sensors**

| **MCP Pin** | **GPIO** | **Function** | **Connected To** | **Sensor Position** |
| --- | --- | --- | --- | --- |
| 1 | GPB0 | TRIG\_LEFT | HC-SR04 Trig | Left sensor trigger |
| 2 | GPB1 | ECHO\_LEFT | HC-SR04 Echo | Left sensor echo |
| 3 | GPB2 | TRIG\_MIDDLE | HC-SR04 Trig | Middle sensor trigger |
| 4 | GPB3 | ECHO\_MIDDLE | HC-SR04 Echo | Middle sensor echo |
| 5 | GPB4 | TRIG\_RIGHT | HC-SR04 Trig | Right sensor trigger |
| 6 | GPB5 | ECHO\_RIGHT | HC-SR04 Echo | Right sensor echo |
| 7 | GPB6 | TRIG\_BACK | HC-SR04 Trig | Back sensor trigger |
| 8 | GPB7 | ECHO\_BACK | HC-SR04 Echo | Back sensor echo |

**Master Controller (Joystick) Pin Assignments**

| **Pin** | **Type** | **Function** | **Connected To** | **Description** |
| --- | --- | --- | --- | --- |
| A0 | Analog Input | Joystick X | Joystick X-axis | Horizontal (0-1023) |
| A1 | Analog Input | Joystick Y | Joystick Y-axis | Vertical (0-1023) |
| 2 | Digital Input | Button A | Push Button | LINE FOLLOW mode |
| 3 | Digital Input | Button B | Push Button | MANUAL mode |
| 4 | Digital Input | Button C | Push Button | AUTO mode |
| 5 | Digital Input | Button D | Push Button | Reserved |
| 6 | Digital Input | Button E | Push Button | Reserved |
| 7 | Digital Input | Button F | Push Button | Reserved |
| 0 (RX) | UART | Bluetooth RX | HM-10 TX | Receive responses |
| 1 (TX) | UART | Bluetooth TX | HM-10 RX | Send commands |

**Power Connections**

| **Component** | **Voltage** | **Current** | **Source** |
| --- | --- | --- | --- |
| ATMEGA328P XPLAINEDMINI | 5V | ~50mA | Buck Converter Output 2 |
| MCP23017 | 5V | ~10mA | Buck Converter Output 2 |
| HM-10 Bluetooth | 5V | ~10mA | Buck Converter Output 2 |
| 4x HC-SR04 | 5V | ~60mA | Buck Converter Output 2 |
| 5x TCRT5000 | 5V | ~70mA | Buck Converter Output 2 |
| L298N Logic | 5V | ~10mA | Buck Converter Output 2 |
| L298N Motors | 9V | 2.4A peak | Buck Converter Output 1 |
| **Total 5V** | **5V** | **~210mA** | **Buck Converter Output 2** |
| **Total 9V** | **9V** | **2.4A** | **Buck Converter Output 1** |

# Appendix B

Make over file to open it.

