CSCM68/CSC68 Lab submission

Group 16

Jordan Jones
1910397
1910397@swansea.ac.uk

Ashish R. Sonwane
2145411
2145411@swansea.ac.uk

Christodoulos Gabriel
1905302
1905302@swansea.ac.uk

Dec 15, 2022

Task 1: Analysing Sensors

1. **Document values with the different**

Light sensor on blue carpet

Distance (mm)	Value 1	Value 2	Value 3	Value 4	Value 5	Value 6	Value 7	Mean	Std. Deviation
5	100	100	100	100	100	100	100	100	0
25	32	27	26	27	25	29	26	27.42857	2.194613
50	5	8	7	7	7	7	6	6.714286	0.880631
100	1	2	1	2	2	1	1	1.428571	0.494872

Light sensor on white line

Distance (mm)	Value 1	Value 2	Value 3	Value 4	Value 5	Value 6	Value 7	Mean	Std. Deviation
5	14	16	15	16	13	12	14	14.28571	1.385051
25	4	4	4	4	4	4	4	4	0
50	0	1	0	1	0	1	0	0.428571	0.494872
100	0	0	0	0	0	0	0	0	0

Ultrasonic sensor

Distance (mm)	Value 1	Value 2	Value 3	Value 4	Value 5	Value 6	Value 7	Mean	Std. Deviation
5	2550	2550	2550	2550	2550	2550	2550	2550	0
25	32	32	32	32	32	32	32	32	0
50	55	51	50	50	50	51	51	51.14286	1.641304
100	101	107	103	103	103	101	107	103.5714	2.321154
250	250	251	251	251	251	251	251	250.8571	0.349927
infinity	2550	2550	2550	2550	2550	2550	2550	2550	0

Gyroscopic sensor

Angle (degrees)	Value 1	Value 2	Value 3	Value 4	Value 5	Value 6	Value 7	Mean	Std. Deviation
90	90	89	95	91	90	83	90	89.71429	3.282607
180	187	185	183	169	184	184	183	182.1429	5.51436
270	274	270	272	264	264	251	261	265.1429	7.259055
360	333	334	345	347	345	353	365	346	10.18402
720	710	717	713	693	697	716	706	707.4286	8.633111
1080	1045	1060	1068	1044	1043	1029	1044	1047.571	11.7699

2. **Discuss the reliability of the sensors based on your findings.**

   All sensors appear to work as intended. Most of these sensors appear to be consistent with their recorded values and close to the intended value. Only exception is the gyroscopic sensor, which had varying readings from one sensor to another. This makes the gyroscopic sensor not suitable for most of the tasks in lab due to it's inconsistency.

   Another notably issue is that the ultrasonic sensor doesn't seem to pick up objects where they are incredibly close. Anywhere between 5mm and 24mm this thresehold is found. This is evident when it produces the value of the distance between and the object in front at the max distance value it can measure, though this drops back to a more excepted value at 25mm.

   The colour sensor doesn't also seem to be perfect at short distances. Though its measurements seem to be fine on the white line, likely due to its reflectivey, the colour sensor doesn't seem to pick up the carpet very well, showing a max value for 5mm, but dropping back to something more expected at 25mm.

Task 2: Testing Motors

1.**Document values from the experiments.** (4 in total):

`Repeat each experiment 7 times. Record values in a spreadsheet and compute mean and standard deviation of the recorded values.`

Straight line

Speed	Value 1(cm)	Value 2(cm)	Value 3(cm)	Value 4(cm)	Value 5(cm)	value 6(cm)	Value 7(cm)	Mean	Std. Deviation
slow (60)	135	82	293	74	164	34	128	130	77.84
medium (120)	34	125	114	140	37	73	215	105.43	59.15
fast (240)	50	60	162	30	60	56	41	65.57	40.64

2. **Discuss the reliability of the motors based on your findings.**

Task 3: Spot Finding

1. **Document selection of sensors with justification.**

   One sensor we used is the colour sensor. The purpose of the sensor is to detect when the colour changes from the current floor colour to white so it knows that it has reached the white spot and needs to change directions.

   Another sensor we used is the gyro sensor. The purpose of this sensor is to know when the driving base has turned exactly 180 degrees before moving again because once it reaches the white spot, it needs to go in the reverse direction.

2. **Provide a picture of the driving base with the selected sensor(s).**

Figure 1: image of the driving base with selected sensor

3. **Document the algorithmic idea.**

   The algorithmic idea is that the driving base is intended to go straight and while it is going straight it should continually check if the colour sensor has picked up the white spot. Once it reaches the white spot, the driving base needs to stop and continually rotate until the gyro sensor picks up the next occurrence of 180 degrees from the gyro sensor so it is able to go in the reverse of the direction it was originally going. It needs to complete all of these steps 10 times.

4. **Document the algorithm in pseudo-code.**

```
ev3 = new EV3Brick()
leftMotor = new Motor(Port.B)
```

```
rightMotor = new Motor(Port.B)
lineSensor = new ColorSensor(Port.S1)
gyroSender = new GyroSensor(Port.S3)
speed = 300 rotatation = speed / 2

for i=0 to 9
 leftMotor.run(speed)
 rightMotor.run(speed)

 while true
     if lineSensor.color == Color.WHITE then
         leftMotor.hold()
         rightMotor.hold()
         leftMotor.run(rotation)
         rightMoto.run(0 - rotation)
         while gyroSensor.angle() < (180 * (i + 1))
             continue
         endwhile
         leftMotor.hold()
         rightMotor.hold()
         BREAK
     endif
 endwhile
next i
```

5. **Provide well-commented MicroPython source code of the implementation.**

```python
#!/usr/bin/env pybricks-micropython
from pybricks.hubs import EV3Brick
from pybricks.ev3devices import (Motor, TouchSensor, ColorSensor,
                                 InfraredSensor, UltrasonicSensor, GyroSensor)
from pybricks.parameters import Port, Stop, Direction, Button, Color
from pybricks.tools import wait, StopWatch, DataLog
from pybricks.robotics import DriveBase
from pybricks.media.ev3dev import SoundFile, ImageFile

#Variables
ev3 = EV3Brick()
left_motor = Motor(Port.B)
right_motor = Motor(Port.D)
line_sensor = ColorSensor(Port.S1)
gyro_sensor = GyroSensor(Port.S3)
gyro_sensor.reset_angle(0)
speed = 300
rotation = speed / 2

for i in range(0, 10, 1):

 #Moves straight for next turn
 ev3.speaker.say("Turn " + str(i + 1) + ", Gyro Value " + str(gyro_sensor.angle()))
 left_motor.run(speed)
 right_motor.run(speed)
```

```python
    #Continually looks for the white sport
    run = True
    while (run):
        if (line_sensor.color() == Color.WHITE):

            #Stops when finds white spot
            left_motor.hold()
            right_motor.hold()

            #Rotates 180 degress
            left_motor.run(rotation)
            right_motor.run(0 - rotation)
            while (gyro_sensor.angle() < (180 * (i + 1))):
                continue

            #Stops rotating
            left_motor.hold()
            right_motor.hold()
            run = False

ev3.speaker.say("Mission Success")
```

Task 4 : Line-with-gaps follower

Figure 2: task image

The broken line track will respect the following rules:

- Gaps will only occur on straight parts of the line
- Gaps may vary in length, but will be limited to a maximum of 30cm;
- You may again modify the hardware design, and use any sensors to solve this task.

1. **Document the Hardware Design (include a picture).**

   Hardware used:

   - Color Sensor

   In order to complete this task we were required to use a “colour sensor”. The colour sensor would try to detect the white lines and keep on following them. We also tried to use a “Gyro sensor” in order to make the micro-python coding less confusing but the “Gyro sensor” would not work, the values one the “Gyro” where not accurate values. We thought of adding a ”Gyro sensor” in order to keep/make our “EV3 robot” to move straight because most of the times the robot would go little off track when making turns or even on straight lines but unfortunately the “Gyro sensor” values were neither accurate nor sensitive enough for the application.

   We also faced some difficulties due to the duck tape placed on the floor, because at some places of the path were more darker than the other part of the tape therefore the colour sensor would easily get messed up with detecting the threshold of the white colour.

Figure 3: Task 4 hardware design.

2. **Develop the Software Design (by either a timed automaton or a StateChart).**

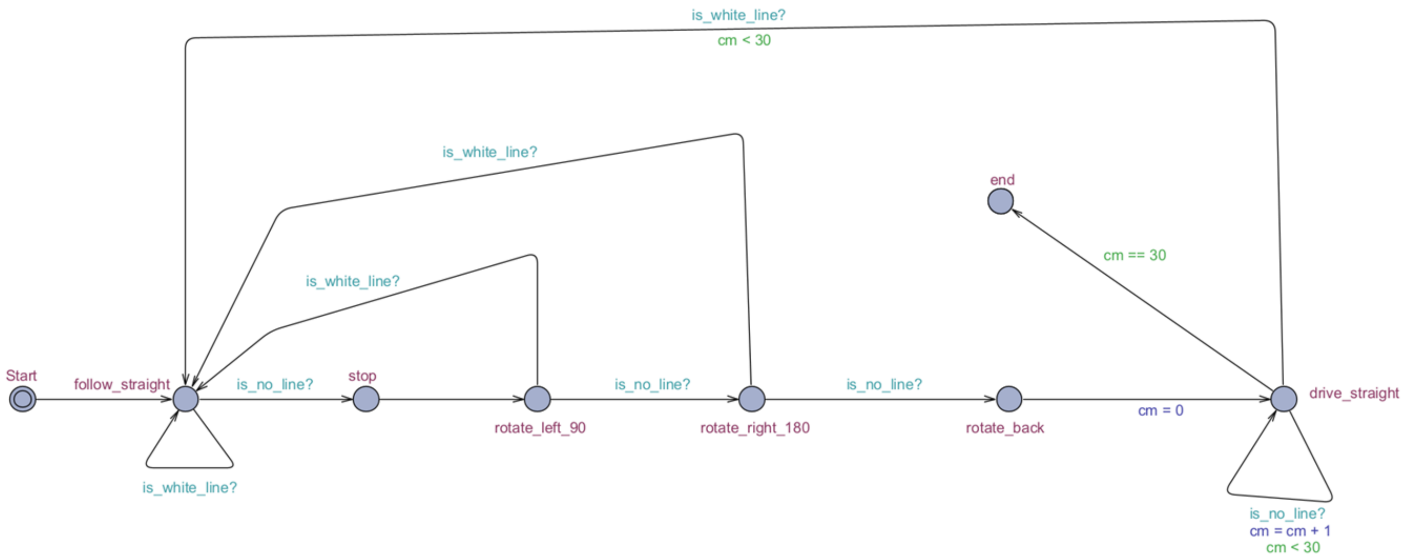

Figure 4: Task 4 timed automata.

3. **Develop the algorithm in pseudo-code (with clear association with elements in the software design).**

```
BEGIN
 CHECK color

 ::x:: <- WHILE (color IS white)
     GO straght
 TURN left
 CHECK color
 IF (color IS white)
     GOTO x

 TURN 180
 IF (color IS white)
```

```
        GOTO x
    END
```

4. Implement the algorithm in MicroPython (provide a well commented code listing).

FILE: new.py

```python
#!/usr/bin/env pybricks-micropython
from pybricks.hubs import EV3Brick
from pybricks.ev3devices import (Motor, TouchSensor, ColorSensor,
                                 InfraredSensor, UltrasonicSensor, GyroSensor)
from pybricks.parameters import Port, Stop, Direction, Button, Color
from pybricks.tools import wait, StopWatch, DataLog
from pybricks.robotics import DriveBase
from pybricks.media.ev3dev import SoundFile, ImageFile
import math

def straight():
 deviation = line_sensor.reflection() - threshold
 turn_rate = proportional_gain * deviation
 robot.drive(speed, turn_rate)
 wait(10)

def dash():
 left_motor.reset_angle(0)
 robot.drive(dashSpeed, 0)
 while(True):
     if (left_motor.angle() > dashDistance):
         robot.stop()
         break

def rotate():
 #Turn Left
 for i in range(0,9):
     robot.turn(-10)
     print(i)
     if (line_sensor.reflection() > black):
         robot.turn(-15)
         return
 robot.turn(90)

 #Turn Right
 for i in range(0,9):
     robot.turn(10)
     print(i)
     if (line_sensor.reflection() > black):
         robot.turn(15)
         return
 robot.turn(-90)

 #Drive until white line or 30cm
 for i in range(0,6):
     robot.straight(50)
     if (line_sensor.reflection() > black):
```

```
        break
  robot.stop()


#Variables
left_motor = Motor(Port.B)
right_motor = Motor(Port.C)
line_sensor = ColorSensor(Port.S4)
robot = DriveBase(left_motor, right_motor, wheel_diameter=55.5, axle_track=104)
speed = 200
turn = speed / 2
dashSpeed = speed / 2
dashDistance = 63
black = 15
white = 76
threshold = (black + white) / 2
proportional_gain = 1.4

while True:
 while (line_sensor.reflection() > black):
     straight()
 if (line_sensor.reflection() <= black):
     robot.stop()
     dash()
     rotate()
```

Task 5: Line Following

1. **Document the Hardware Design (include a picture).**

   Hardware used:

   - Color Sensor

   This task was a bit more challenging than the previous one because we had to deal with sharp turns an almost semi-circle turns. The speed of the robot played a huge role in this task, because sometimes the robot would make a turning faster than it should and the colour sensor was not able to detect the white line of the path. So we had to play with the proportionality of the wheel spin(the turnings) and the speed. As I also mentioned before a drawback was the colour or how the tape was placed on the floor

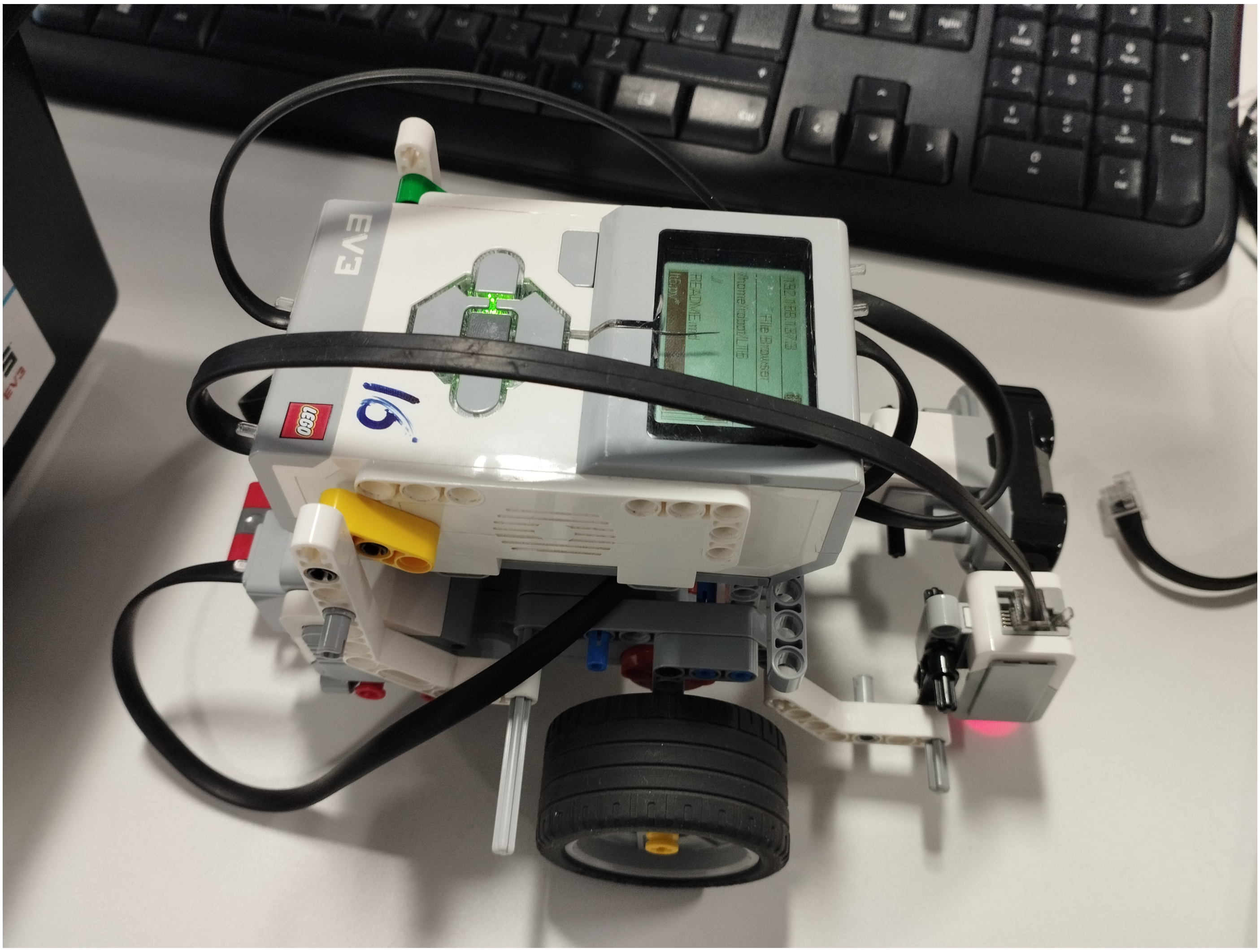

Figure 5: Task 5 hardware design.

2. **Develop the Software Design (by either a timed automaton or a StateChart).**

   Task 5 StateChart

3. Develop the algorithm in pseudo-code (with clear association with elements in the software design).

4. Implement the algorithm in MicroPython (provide a well commented code listing).

   `FILE: lt5.py`

```python
#!/usr/bin/env pybricks-micropython

# Import the necessary libraries
from pybricks.parameters import *
from pybricks.hubs import EV3Brick
from pybricks.ev3devices import *
from pybricks.tools import wait
from pybricks.robotics import DriveBase

# Create the sensors and motors objects
ev3 = EV3Brick()

motorA = Motor(Port.A)
motorB = Motor(Port.B)
left_motor = motorA
right_motor = motorB

color_sensor_in1 = ColorSensor(Port.S1)


def move_tank_dc(left, right):
    left_motor.dc(left)
    right_motor.dc(right)


def move_tank(left, right):
    left_motor.run(left)
    right_motor.run(right)


def move_steer(speed, steer):
    # init l_speed and r_speed to same values
    l_speed = speed
    r_speed = speed

    gain = (threshold - abs(float(steer))) / threshold

    if steer >= 0:
        r_speed *= gain
    else:
        l_speed *= gain

    if abs(steer) < 2.0:
        # full speed
        move_tank_dc(70.0, 70.0)
    else:
        move_tank_dc(l_speed, r_speed)


# Here is where your code starts
# colour values for line detection. Calibrate these for every sensor.
BLACK = 3
```

```python
WHITE = 60
threshold = (BLACK + WHITE) / 2.0

# drive speed and proportional gain for turning rate
DRIVE_SPEED = 160.0
PROPORTIONAL_GAIN = 1.60


# ==================== MAIN LOOP ====================
while True:
    # Calculate the deviation from the threshold.
    deviation = threshold - color_sensor_in1.reflection()

    # Calculate the turn rate. e.g. 2.5 * 10 = 25 deg/s
    turn_rate = PROPORTIONAL_GAIN * deviation
    speed = DRIVE_SPEED

    move_steer(speed, turn_rate)

    # wait(10)
```

Task 6: Maze Solver

1. **Document the Hardware Design (include a picture).**

   Hardware used

   - Ultrasonic sensor
   - Color sensor

   In this task we have used the “Ultrasonic sensor” to detect the distance from each block while the EV3 is moving towards it. A “Colour sensor” is used because on the ground there is a white tape for each rectangle. Therefore, we are using the light sensor to as soon as it catches a white line to move 2-3 cm more forward and then try to scan the area by turning left, right or forwards to scan the place to see which distance is the greatest in order to continue its journey. This will make the robot move to the greatest distance not to hit the blocks.

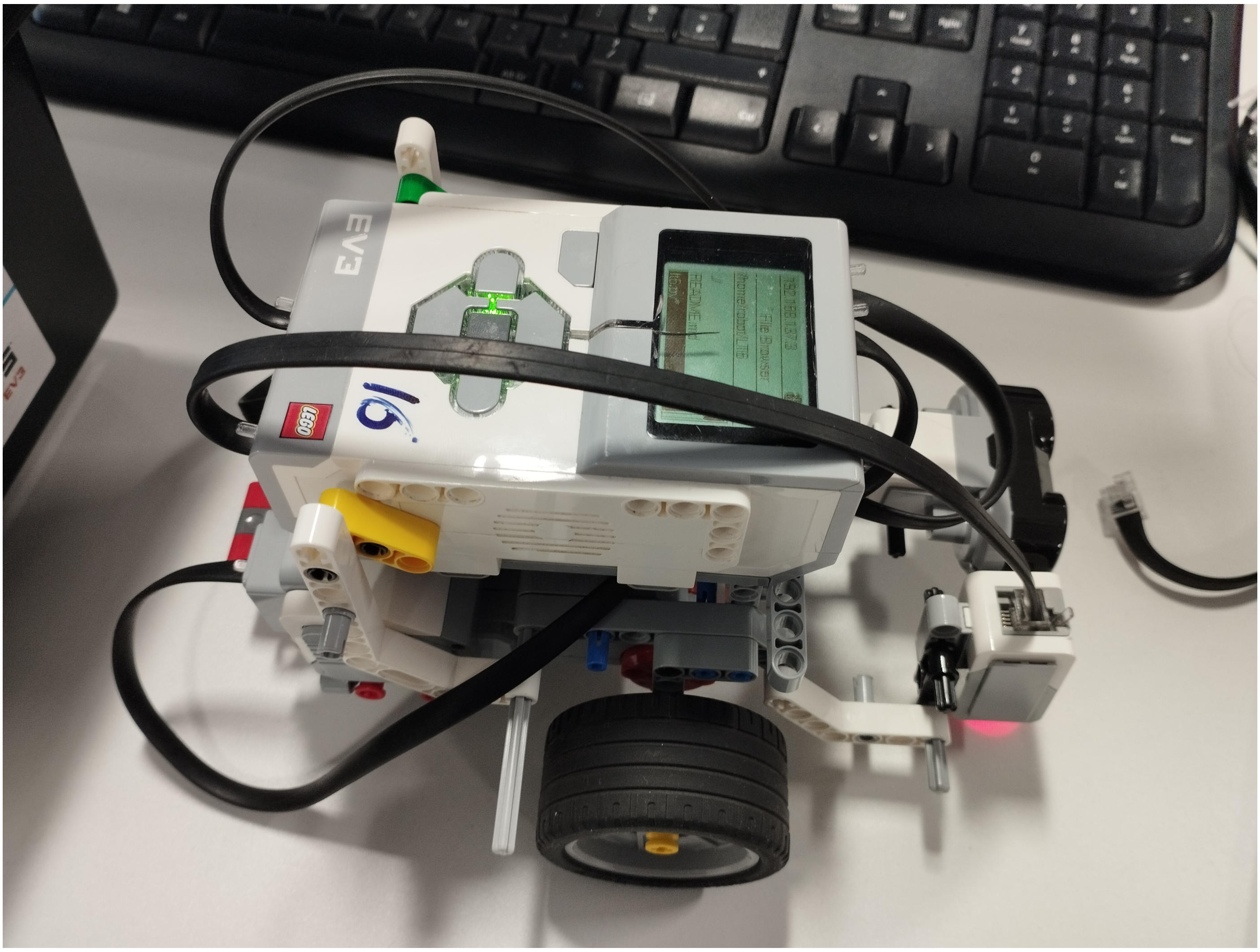

Figure 6: Task 6 hardware design

2. **Develop the Software Design (by either a timed automaton or a StateChart).**

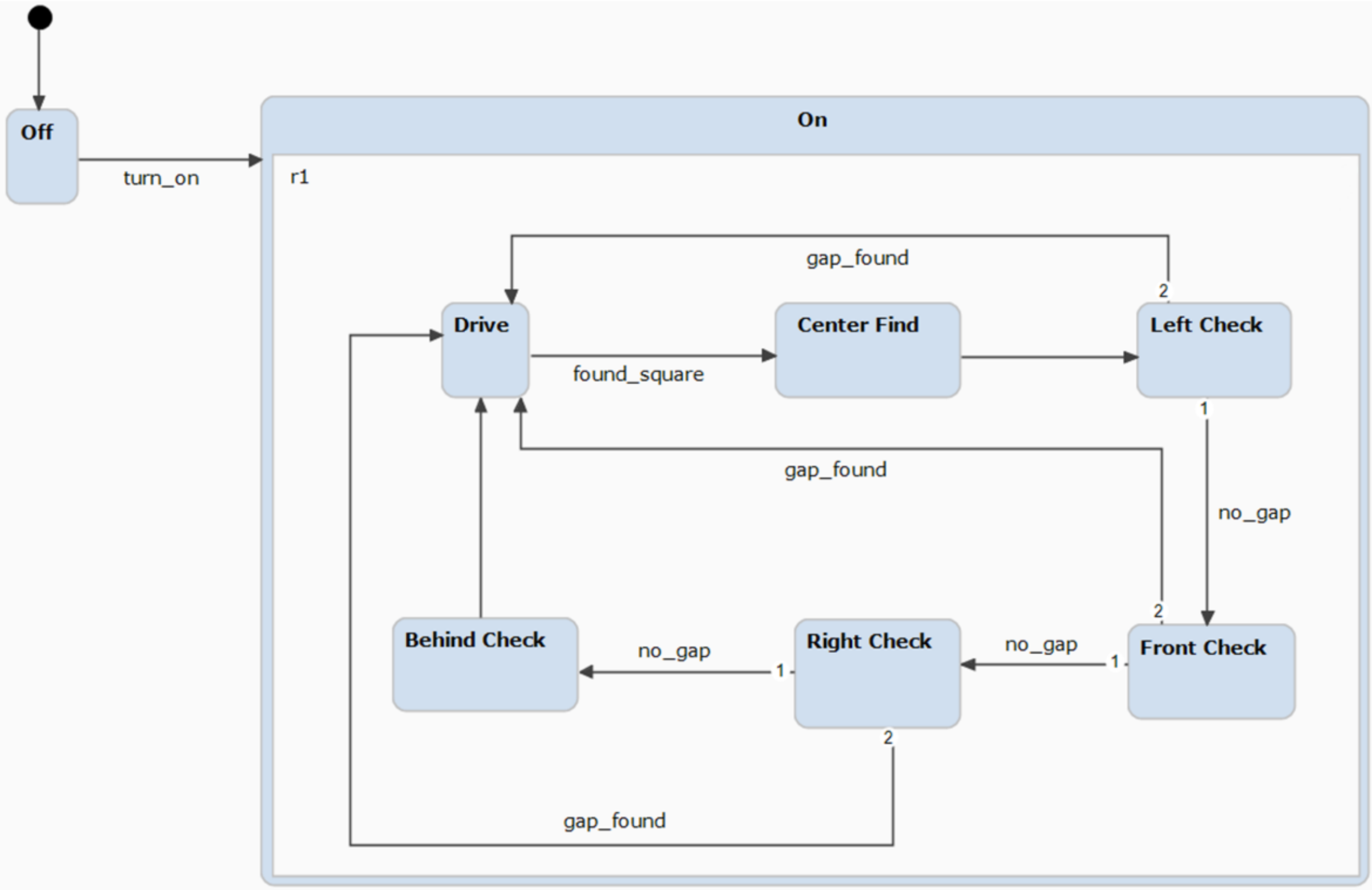

Figure 7: Task 6 StateChart

3. **Develop the algorithm in pseudo-code (with clear association with elements in the software design).**

4. **Implement the algorithm in MicroPython (provide a well commented code listing).**

FILE: lt6.py

```python
#!/usr/bin/env pybricks-micropython
from pybricks.hubs import EV3Brick
from pybricks.ev3devices import (Motor, TouchSensor, ColorSensor,
                                 InfraredSensor, UltrasonicSensor, GyroSensor)
from pybricks.parameters import Port, Stop, Direction, Button, Color
from pybricks.tools import wait, StopWatch, DataLog
from pybricks.robotics import DriveBase
from pybricks.media.ev3dev import SoundFile, ImageFile

# Turn
def check():

    #Left
    robot.turn(first_turn)
    robot.turn(first_turn)
    robot.turn(first_turn)
    print(ultrasonic.distance())
```

```python
    if (ultrasonic.distance() > wall):
        print("LEFT")
        print(" ")
        return

    #Forward
    robot.turn(second_turn)
    robot.turn(second_turn)
    robot.turn(second_turn)
    print(ultrasonic.distance())
    if (ultrasonic.distance() > wall):
        print("FORWARD")
        print(" ")
        return

    #Right
    robot.turn(second_turn)
    robot.turn(second_turn)
    robot.turn(second_turn)
    print(ultrasonic.distance())
    if (ultrasonic.distance() > wall):
        print("RIGHT")
        print(" ")
        return

    #Back
    robot.turn(second_turn)
    robot.turn(second_turn)
    robot.turn(second_turn)
    print(ultrasonic.distance())
    if (ultrasonic.distance() > wall):
        print("BACK")
        print(" ")
        return

    print("ERROR!!!")
    print(" ")

# Components
left_motor = Motor(Port.A)
right_motor = Motor(Port.B)
ultrasonic = UltrasonicSensor(Port.S2)
line_sensor = ColorSensor(Port.S1)
robot = DriveBase(left_motor, right_motor, wheel_diameter=55, axle_track=142)

# Values
speed = 200
white = 20
middle = 28
wall = 250
right = 30
left = - right
```

```python
first_turn = 0
second_turn = 0

# while True:
#     robot.turn(left)
#     robot.turn(left)
#     robot.turn(left)
#     robot.turn(right)
#     robot.turn(right)
#     robot.turn(right)

# Hardcode
robot.drive(speed, 0)
while True:
    if (line_sensor.reflection() > white):
        robot.straight(middle)
        print(ultrasonic.distance())
        if (ultrasonic.distance() < wall):
            robot.turn(left)
            robot.turn(left)
            robot.turn(left)
            first_turn = left
            second_turn = right
        else:
            first_turn = right
            second_turn = left
        break

# Main
while True:
    robot.drive(speed, 0)
    if (line_sensor.reflection() > white):
        robot.straight(middle)
        check()
```