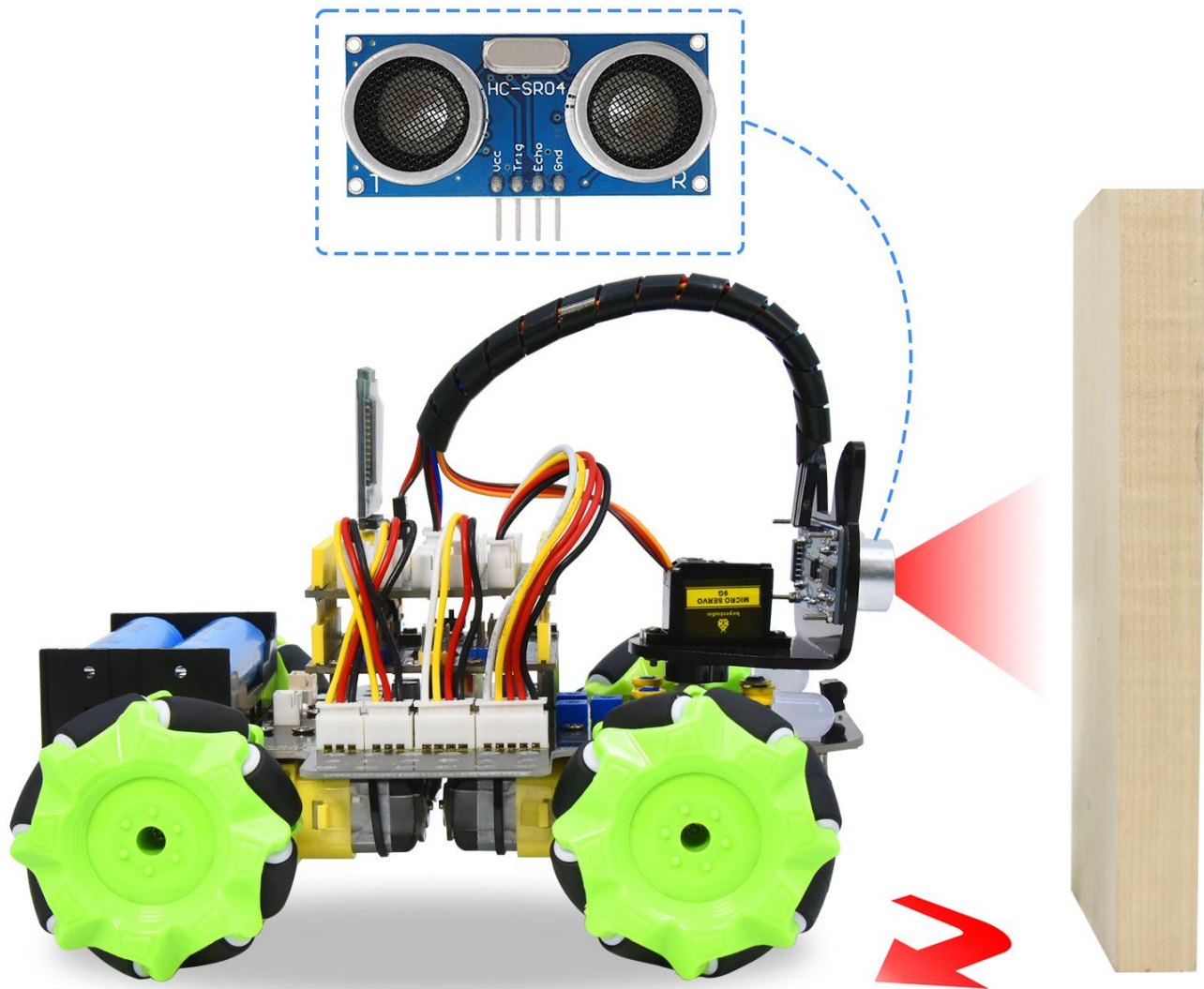


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Project 9: Ultrasonic Obstacle Avoidance Smart Car

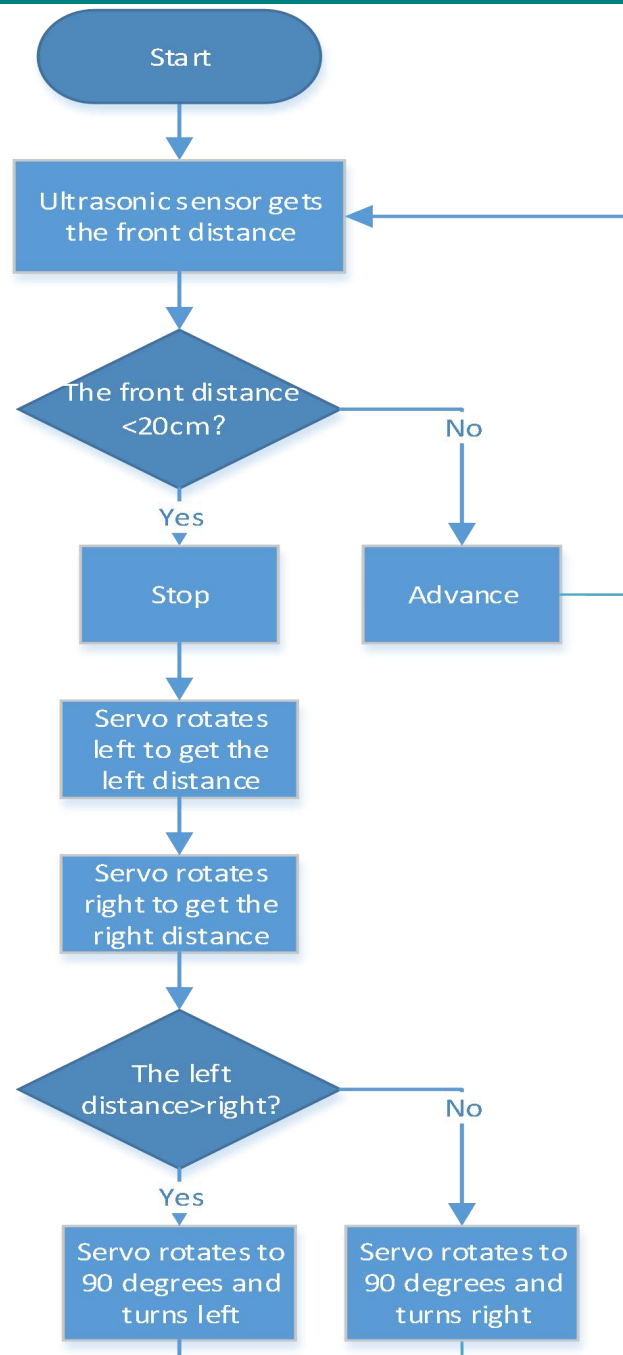


1. Description

Ultrasonic obstacle avoidance smart car is used to control the car motion state, so as to achieve obstacle avoidance by using the ultrasonic sensor detecting the obstacles distance.

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2. Flow Diagram



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3. Test Code

```
/**
 *
 * Keyestudio 4WD Mecanum Robot for Arduino
 * lesson 9
 * Ultrasonic obstacle avoidance Robot
 * http://www.keyestudio.com
 */
#include "MecanumCar_v2.h"
#include "Servo.h"

mecanumCar mecanumCar(3, 2); //sda-->D3, scl-->D2
Servo myservo; //Define an instance of a servo

/*****Ultrasonic Sensor interface*****/
#define EchoPin 13 //ECHO to GPIO13
#define TrigPin 12 //TRIG to GPIO12

int distance_M, distance_L, distance_R;

void setup() {
  myservo.attach(9); //The pins of the servo is connected to GP2
  pinMode(EchoPin, INPUT); //The ECHO pin is set to input mode
  pinMode(TrigPin, OUTPUT); //The TRIG pin is set to output mode
  myservo.write(90); //Rotate to 90 degrees
  delay(300);
}

void loop() {
  distance_M = get_distance(); //Get the distance and save in the distance variable
  if (distance_M < 20) { //When the distance in front is less than 20cm
    mecanumCar.Stop(); //Robot stops
    delay(500); //Delay in 500ms
    myservo.write(180); //Ultrasonic cradle head turns left
    delay(500); //Delay in 500ms
    distance_L = get_distance(); //Assign the left ultrasonic distance to variable a1
    delay(100); //Read values when stable
    myservo.write(0); //Ultrasonic cradle head turns right
    delay(500); //Delay in 500ms
    distance_R = get_distance(); //Assign the right ultrasonic distance to variable a2
    delay(100); //Read values when stable

    myservo.write(90); //Return to the 90 degree position
    delay(500);
    if (distance_L > distance_R) { //When the distance on the left is greater than right
      mecanumCar.Turn_Left(); //Robot turns left
      delay(300); //Turn left 700ms
    } else {
      mecanumCar.Turn_Right(); //Robot turns right
    }
  }
}
```

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```
        delay(300);
    }
}
else { //If the distance in front >=20cm, the robot will advance
    mecanumCar.Advance(); //Advance
}
}

/*****Ultrasonic detects the distance*****/
int get_distance(void) { //Ultrasonic detects the distance
    int dis;
    digitalWrite(TrigPin, LOW);
    delayMicroseconds(2);
    digitalWrite(TrigPin, HIGH); //Give the TRIG a high level of at least 10 μs to trigger
    delayMicroseconds(10);
    digitalWrite(TrigPin, LOW);
    dis = pulseIn(EchoPin, HIGH) / 58.2; //Work out the distance
    delay(30);
    return dis;
}
/*****
```

4. Test Result

After uploading the code successfully, turn the DIP switch to the ON end and power up, then the car can automatically avoid obstacles. Note that the speed can't be too large.

The car will stop when encountering obstacles in front of it and the servo cradle head will rotate left to detect the left distance, then rotate right to detect the right distance. Then judge the distance between the obstacles on the left and the right, the car will turn along the farther side, and then continue to drive.

5. Code Explanation

myservo.write(90);	Make the servo rotate to 90 degrees
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int distance = get_distance();	Define an integer variable to store the measured distance, and then control the car driving according to it
myservo.write(180); distance_L = get_distance();	Ultrasonic turns left to detect and save the distance
myservo.write(0); distance_R = get_distance();	Ultrasonic turns right to detect and save the distance
myservo.write(90);	The servo return to the 90 degrees position
if (distance_L > distance_R)	Judge the left and right distance
else { mecanumCar.Advance(); }	If the front distance is bigger than 20cm, the car will advance