

# Android based Robotic Fire Alert System to Save Fire Victims

M. A. Majed<sup>1</sup>, Ambreen Fatema<sup>2</sup>, S. M. A Muneer Mogni<sup>3</sup>

Associate Prof.<sup>1</sup> Assistant Prof.<sup>2</sup>, Scholar<sup>3</sup>

Dept of ECE<sup>1</sup> and EIE<sup>1,2</sup>,

Deccan College of Engineering and Technology, Hyderabad, India.

smamuneermogni@gmail.com

**Abstract** — A Robotic systems that interact among themselves and the environment in which it works. In robotics, end effectors are the devices at the end of a robotic arm, is designed to interact with the environment. Gripper is an end effector or tool to grasp any object. In this work we are going to build a fire alert system to save fire victims using Arduino microcontroller (Atmega328), which will save the victims in fire accidents. In this work the wireless connectivity is through Bluetooth modem and controlling through android application by particular commands, which then allows the Arduino to determine the position of DC motors. The fire victims are sense through PIR sensor and then information will be passes via bluetooth to android application. The robot would be controlled by the rescue team to save the fire victims. The sensitive information into text as transmitter and receiver will be perform many other functions using certain commands programmed in the arduino (Atmega328). This work can be very useful for industries, defence, surgical purposes and so on so forth.

**Keywords**— Arduino UNO R3 (Atmega328), Bluetooth, DC Motors. Fire Sensor, KEIL Compiler, L293D, PIR, Robotic Arm, Sensor.

## I. INTRODUCTION

Robotics is one of the fastest growing engineering fields of today to work in unreachable environment. With such device, people and property can be saved at a much higher rate with relatively minimal damage caused by the fire. The design of a wireless controlled robot which can perform actions intelligently by itself. Mobile robots are used in mining, military, forestry, security, etc. Robot technology can be very efficiently used in such cases to rescue much more fire victims. In this work we have two ends, namely, Transmitter end and Receiver end. On receiver end, there is a vehicle, it has Arduino Atmega328 which is interfaced with input and output devices, used to control vehicle. On the transmitter end, there is an android phone with android application, wireless signals are sent to transmitter side via Bluetooth module by android phone to control vehicle. Mobile robot control is done through mobile OS. The arm is placed on a moving vehicle and through different commands the robot is able to move in all directions. This vehicle uses four servo motors for the operation. It has arm assembly with a jaw. One servo motor allows the robotic arm to grab the object and other one allows the movement in upward and downward direction. The other two servo motors are to be attached with the robotic arm base that gives an advantage to move the base in forward and backward direction. Arduino acts as an interface to the Motors, Bluetooth modem and Android mobile which has a Bluetooth application present in the mobile. This system has 10 independent commands for the gripper to open and close, elbow upward and downward, base clockwise and counters clockwise, base forward and backward directions left, right forward and backward by arduino application.

## II. LITERATURE SURVEY

With the invention of such device, people and property can be saved at a much higher rate with relatively minimal damage caused by the fire[1]. The design of a wireless controlled robot from a distance or which can perform actions intelligently by itself, which will reduce the risk of this task of fire fighting. Mobile robots are used in mining, military, forestry, security, etc. Robot technology can be very efficiently used in such cases to rescue much more victims [2]. In present fire fighting system, fire fighters have to fight against fire from very closer technical persons had worked on it to improve it. They have used different techniques to implement this. Before deciding our method to implement innovative fire extinguishing vehicle, we have studied many research papers regarding to our topic. This work includes different methods for the purpose of fire fighting [3]. There are sensors connected on each and every side of vehicle to detect flame and according to that the vehicle navigates towards fire to extinguish it. But this method gives delayed output so takes more time to fulfil the task and has less accuracy [4]. The Idea about the Android software “Blue control” and its application in controlling Robotics is described in the Google play store website. From all these we find a different controlling technique using android device and software with a different approach for soft catching arm (electronic pressure sensor) [5]. The robotic vehicle is designed with a soft catching gripper that can be controlled by android OS based smart phone available in the market for remote operation[6]. The android application device transmitter will acts as a remote control while the receiver end Bluetooth device is fed to the microcontroller to drive DC motors via motor driver IC for necessary work. Remote operation is achieved by any Smart phone with Android OS, upon a GUI (Graphical User Interface) based touch screen operation. Users friendly and inexpensive in price are some of the advantages of Bluetooth technology used in controlling the robotic vehicle. Therefore controlling the robotic vehicle by smart phone will come true [7].

### III. ROBOTIC SYSTEM DESIGN

The Functional block diagram of proposed system is as shown in Fig.1, the hardware components are Atmega 328 microcontroller, PIR sensor, DC motor, and power supply.

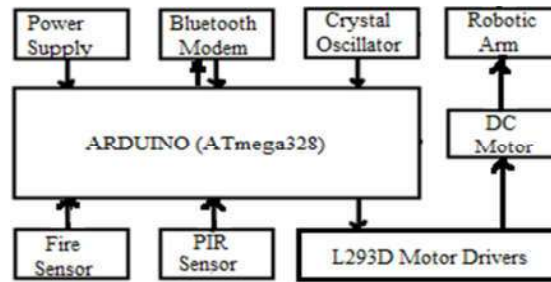


Fig. 1 Functional Block diagram

The main scope of work is to send commands from one android phone to be received by Bluetooth module mounted on the robot. The controller also connected to the Bluetooth module, which sends information to rescue person about the dangerous area where robot is running. It can send the required information in the form of text to the rescue team. The required power is of 13 Ah battery with voltage of 12 V.

#### A. Bluetooth Modem

Bluetooth serial communication module has two work modes, order-response work mode and automatic connection work mode. And there are three work roles (Master, Slave and Loopback) at the automatic connection work mode. When the module is at the automatic connection work mode, it will follow the default way set lastly to transmit the data automatically as shown in Fig. 2. When the module is at the order-response work mode, user can send the AT command to set the control parameters and send control order, specification is as shown in Table II.

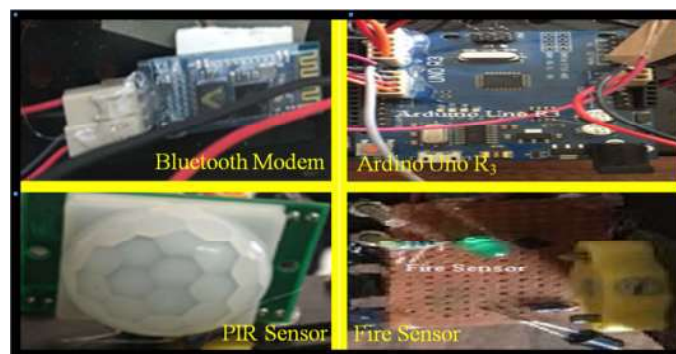


Fig. 2 Bluetooth Modem with Arduino Uno and sensors

#### B. Arduino UNO R3

The Arduino Uno is a microcontroller board based on the ATmega328. As shown in Fig. 2. It has 14 digital input/output pins, 6 analog inputs, a 16 MHz ceramic resonator, a USB connection, a power jack, an ICSP header, and a reset button. It contains everything needed to support the microcontroller, As shown in Fig. 3. Simply connect it to a computer with a USB cable or power it with an AC-to-DC adapter or battery to get started, the detail specification is shown in Table II.

#### C. PIR sensor

The detected radiations are converted into an electrical charge, which is proportional to the detected level of the radiation as shown in Fig 2. Then this charge is further improved by a built in FET and fed to the output pin of the device which becomes applicable to an external circuit for further triggering and amplification of the alarm stages.

#### D. Fire sensor

A flame sensor module, that consists of a flame sensor (IR receiver), resistor, capacitor, potentiometer, and comparator LM393 as shown in Fig. 2. It can detect infrared light with a wavelength ranging from 700nm to 1000nm. The far-infrared flame probe converts the light detected in the form of infrared light into current changes. Sensitivity is adjusted through the onboard variable resistor with a detection angle of 60° degrees. Working voltage is between 3.3v and 5.2v DC, with a digital output to indicate the presence of a signal. Sensing is conditioned by an LM393 comparator.

### E. Wrist and End effectors

It has a spur gear meshing with a worm gear with a 12V stepper motor and two end effectors out of which one is fixed and another is movable, as shown in Fig. 3.



Fig. 3 Wrist and end effectors with Stepper Motor

### F. Motors

There are two magnetic fields produced in the motor as shown in Fig.3. One magnetic field is produced by the permanent magnets and the other magnetic field is produced by the electrical current flowing in the motor windings. These two fields result in a torque which tends to rotate the rotor. As the rotor turns, the current in the windings is commutated to produce a continuous

Table II  
COMPONENTS SPECIFICATION

Components	Specifications	
<b>Bluetooth</b>	Frequency	v2.0+EDR
	Modulation	2.4GHz ISM band
	Sensitivity	Less than 4 dBm,
	Speed	Less than 84 dBm
	Asynchronous	2.1Mbps(Max)
	Synchronous	1Mbps/1Mbps
	Power supply	+3.3VDC 50mA
	Working temperature	20 ~ + 75° Centigrade
<b>Arduino</b>	Dimension	26.9mm x 13mm x 2.2 mm
	Microcontroller	ATmega328
	Operating Voltage	5V
	Input Voltage	7-12V
	Digital I/O Pins	14
	Analog Input Pins	6
	DC Current per I/O Pin	40 mA
	Flash Memory	32 KB of which 0.5 KB
<b>PIR Sensor</b>	SRAM	2 KB (ATmega328)
	EEPROM	1 KB (ATmega328)
	Clock Speed	16 MHz
	Size	Rectangular
<b>Fire Sensor</b>	Output	3V up to 20 feet (6m)
	Sensitivity range	110° x 70° range
	Power supply	5V-12V input voltage
	Wavelength	700nm to 1000nm
<b>Arm Manipulator</b>	Temperature	60 degrees
	Voltage	3.3v and 5.2v
	Weight	30x2=60 gm for big arm 10x2=20 gm for small arm
<b>Motors</b>	Length	25 cm for big arm 5cm for small arm 2.33
	Step angle	1.8degrees
	Speed	100 rpm
	Voltage	9 V
<b>Shaft</b>	Supply current	0.5 A DC
	Diameter of shaft	15 cm
	Length of shaft	28 cm
	Bearing type	Ball bearing

### G. Robotic system of gripper links

The object to be lifted is by Metal Plates and weight of the object is 50-80gm the link has two parts, Part1 and Part2. The Arm manipulator has length as Part1 = 25 cm and Part 2 = 5 cm. Therefore, the ratio of the length of the two links is Link1: Link 2 = 5: 1. Design Length of shaft = 24mm, Torque (T) = 42 N-m and Tangential force on gear =  $\frac{2T}{D}$ , Where, (D) = Diameter of gear = (2x42)/0.025 = 3360 N, Twisting moment (T) = 47.18 N-m.

Normal load acts on gear teeth is,

$$\frac{F_t}{\cos 20} = (3360/0.937) = 3585 \text{ N} \quad (1)$$

Maximum bending moment,

$$(M) = \frac{WL}{4} = (3585 \times 0.025)/4 = 21.51 \text{ N-m} \quad (2)$$

Power and Torque Transmitted,

If Voltage = 220 V, Current = 0.4 A and Speed = 20 rpm, then Power transmitted =  $VI \cdot P = (220 \times 0.4) = 88 \text{ watt}$

Torque calculations,

$$\text{Torque} = \frac{P \cdot 60}{2\pi N} = \frac{88 \times 60}{2\pi \times 20} = 42 \text{ Nm} \quad (3)$$

#### H. Force calculation of joints

This will provide a fundamental understanding of moment arm calculations for statics and dynamics. Choose these parameters weight of each linkage weight of each joint weight of object to lift length of each linkage. This particular design has just two degree of freedom (DOF) that requires lifting, and the centre of mass of each linkage is assumed to be acting at half of the length.

Torque about Joint 1

$$M_1 = \frac{L_1}{2} \cdot W_1 + L_1 \cdot W_4 + \left(L_1 + \frac{L_2}{2}\right) W_2 + (L_1 + L_3) W_3 \quad (4)$$

Torque about Joint 2

$$M_2 = \frac{L_2}{2} \cdot W_2 + L_3 \cdot W_3 \quad (5)$$

For each DOF we add the math, gets more complicated, and the joint weights get heavier. We will also see that shorter arm lengths allow for smaller torque requirements as shown in Fig.4. Where  $W_1 = 0.5 \text{ N}$ ,  $W_2 = 0.25 \text{ N}$ ,  $W_3 = 0.25 \text{ N}$ ,  $W_4 = 0.5 \text{ N}$ .  $L_1 = 20 \text{ cm}$ ,  $L_2 = 10 \text{ cm}$ ,  $L_3 = 15 \text{ cm}$  and  $M_1 = 180^\circ$ ,  $M_2 = 90^\circ$

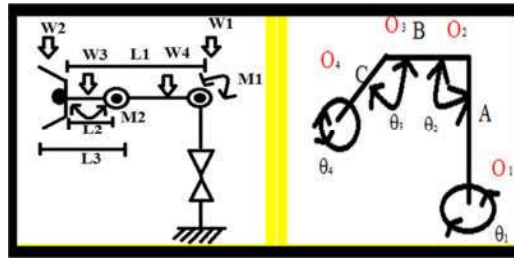


Fig. 4 Load on joints and DOF

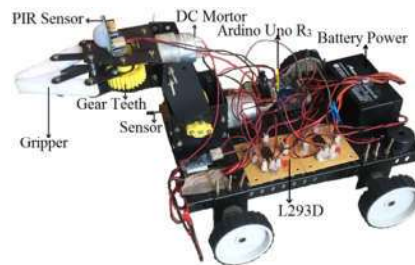
Where, as shown in Fig. 4 has  $\theta_1 = 360^\circ$ ,  $\theta_2 = 270^\circ$ ,  $\theta_3 = 180^\circ$  and  $\theta_4 = 90^\circ$ . Generally arms are described by their degree of freedom (DOF). This number typically refers to the number of single-axis rotational joints in the arm. Higher DOF indicates an increased flexibility. There are mainly 6 degrees of freedom per robotic arm. Six degrees of freedom (6DoF) refers to the freedom of movement of a rigid body in three-dimensional space.

DOF = Number of joints in robotic arm

Robotic arm is designed with two servo motors, so there are two joints in arm, can be called 2 degree of freedom. Here the arm is designed with 2 DOF, which is sufficient for this application. They are up-down, open-close. According to datasheet of servo motor stall torque is 11 kg/cm for 4.8V (operating voltage) and 13.5 kg/cm for 6V. Hence maximum load on both the motors should be 0.51kg approximately.

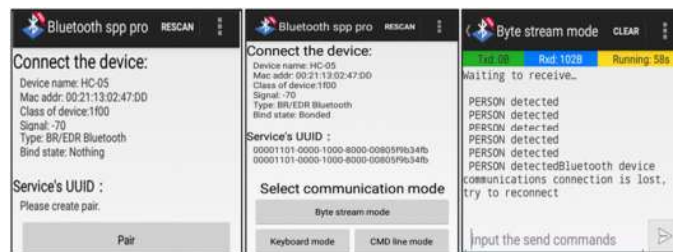
## V. RESULTS

This android robot vehicle is designed by metal plates. The prototype design of vehicle is shown Fig.5. This vehicle is guided by operator with android phone. Wireless signals are, sent from android and are received by HC-05 Bluetooth module to the microcontroller Atmega 328. Vehicle follows commands from android, after it reaches to fire, command of program stops the vehicle and sends information of victims in fire accidents.



**Fig. 5 Prototype Design Setup**

This is the dataflow of the system. For this purpose an android application is developed and it is a snapshot of Android application as shown in Fig.11. We have implemented innovative fire alarming system to save victims in fire accidents using android and also android application is designed to control the vehicle remotely with the help of Android application and result of it is shown in Fig. 6. Use of this vehicle can save number of fire victims.



**Fig. 6 Robot controlling by Bluetooth operation**

This vehicle is based on android phone. But there are many other ways to control it. Other technique is self operated by using sensors, but it may result in delayed output and accuracy is also less. Hence the android control technique is superior.

**Table III**  
**ROBOTIC COMMANDS**

Sr. No.	Commands	Particulars
1.	Griper Open	Gripper starts opening
2.	Griper Close	Gripper starts closing
3.	Forward	Vehicle starts moving forward
4.	Backward	Vehicle starts moving backward
5.	Left Forward	Vehicle left side wheel starts moving forward
6.	Left Backward	Vehicle left side wheel starts moving backward
7.	Right Forward	Vehicle right side wheel starts moving forward
8.	Right Backward	Vehicle right side wheel starts moving backward
9.	Elbow Upward	Robotic arm elbow starts moving upward
10.	Elbow Downward	Robotic arm elbow starts moving downward.

It starts alarming with the help of IR flame sensor and buzzer which gives alert. Also victims are saved by PIR sensor. Vehicle is controlled by android phone. The relation between input from android phone and corresponding outputs are shown in below table III. conclude that main objective of this work is to develop an embedded system based application to operate the robotic arm. It has been developed by integrating features of all the hardware components used.

## VI. CONCLUSIONS

We Presence of every module has been reasoned out and placed carefully, thus contributing to the best working of the unit. Robot is protected from fire and obstacles by sensors but one can use wireless camera for this purpose.

## REFERENCES

- [1] Akshay Deshmukh, Nikhil More, Shubham Nagare, V.B. Sarode "A Survey on Fire Detector and Extinguisher Robot Controlled using Android Application – Blucontrol", 5<sup>th</sup> International conference on recent development in engineering science, humanities and management ISBN 978-93-86171-39-9.
- [2] John Iovine., "Robots, Androids, and Animations 12 Incredible Projects You Can Build", Second Edition, McGraw-Hill.2002. © 2016 IJEDR | Volume 4, Issue 2, ISSN- 2321-9939.
- [3] Naga Sudheer Ravela, Sainath Somisetty, Nagaraju Uralagunta, SambaSiva Rao Kopanaty, "Pick and Place Arm and Robotic Movement by using Android" international journal of innovative research in electrical, electronics,

*instrumentation and control engineering Vol. 4, Issue 3, March 2016 ISSN (Online) 2321 – 2004 ISSN (Print) 2321 – 5526.*

- [4] Dr. Mostafa Ranjbar, Dr. Davut Solyal, “Autonomous Fire Detection and Extinguishing Vehicle”. MENG 411 Capstone Team Project Eastern Mediterranean University Faculty of Engineering.
- [5] Babu Ganesh.K, Hari Shankar.K, Kolanchi Mani.V, Thennarasu.S, Ramu. S. “Android Controlled Robotic Arm Vehicle” In *Advances in Natural and Applied Sciences*, ISSN: 1995-0772, EISSN: 1998-1090 ANAS 2017 February 11(2), pages 127-132
- [6] Butkar Vinayak D. B. E. Devikar Sandip, Jaybhaye Vikas, Prof. Shilpa Patharwalkar, “Android Based Pick and Place Robot”. *IJIFR/ V2/ E4/ 011*, Page No. 859-867.
- [7] Low Kot Hau, Gowrishankar Kasilingam, K. Nithiyananthan, “Development Of Prototype Model For Wireless Based Controlled Pick And Place Robotic Vehicle” *TELKOMNIKA Indonesian Journal of Electrical Engineering Vol. 14, No. 1, April 2015*, pp. 110 ~ 115 DOI: 10.11591/telkomnika.v14i1.7370.