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Sensors and Instrumentation
(TA1)

Project Final Review

Made by

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ACKNOWLEDGEMENT:

I would like to express my special thanks of gratitude to my teacher (Proffesor K.Govardan)as well as our College (Vellore institute of technology,Vellore)who gave me the golden opportunity to do this wonderful project on the Sensors and Instrumentation(Arduino Based Radar System), which also helped me in doing a lot of Research and i came to know about so many new things and I came to experience more struggle and learnt lots of life lessons and management of time.I am really thankful to them.

Secondly i would also like to thank my parents and friends who helped me a lot in finalizing this project within the limited time frame.

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***Abstract:**

We are gonna do a model of radar that will detect any object within its given range and an led and buzzer will alarm if an object is detected within an specific region and we can see the angle of the object with respect to the ultrasonic sensor placed in the servo motor. This is very useful in this modern world in borders of india

***Introduction:**

*Now a days terroist attack using any missiles or any weapons and even while car parking there are some accidents happening. So we came up with the idea to do a Radar with help of ultrasonic sensor and servor motor which will detect objects in front of us and alert us and we have did a working model of RADAR

***RADAR** is an object detection system which uses [radio waves](#) to determine the range, altitude, direction, or speed of objects. Radar systems come in a variety of sizes and have different performance specifications. Some radar systems are used for air-traffic control at airports and others are used for long range surveillance and early-warning systems. A radar system is the heart of a missile guidance system.

*Small portable radar systems that can be maintained and operated by one person are available as well as systems that occupy several large rooms. Radar was secretly developed by several nations before and during [World War II](#). The term RADAR itself, not the actual development, was coined in 1940 by the [United States Navy](#) as an [acronym](#) for radio Detection and Ranging. The term radar has since entered [English](#) and other languages as the common noun radar, losing all capitalization

*The modern uses of radar are highly diverse, including air traffic control, [radar astronomy](#), [air-defense systems](#), [anti-missile systems](#); [marine radar](#) to locate landmarks and other ships; aircraft anti-collision systems; [ocean surveillance](#) systems, outer space surveillance and [rendezvous](#) systems; [meteorological](#) precipitation monitoring; altimetry and [flight control systems](#); [guided missile](#) target locating systems; and [ground-penetrating radar](#) for geological

observations. High tech radarsystems are associated with [digital signal processing](#) and are capable of extracting useful information from very high [noise](#) levels.

*Ultrasonic Sensor is a device which can be used to find the distance of the object

*We will use ultrasonic sensors in this project to know the distance and we will use servomotor to rotate the ultrasonic sensor and find the object which will be in range and display the object if it located in the radar and we can see them in our radar

Components Used:

*Arduino

*Ultrasonic Sensor

*Servo Motor

*Bread Board

*Jumper Wires

*One Led

*Buzzer

Cost of the project is approximately 1000 Rs
Softwares Required:

*ARDUINO IDE

*Processing

Explanation of Components:

ULTRASONIC (HC-SR04): The HC-SR04 Ultrasonic Sensor is a very affordable proximity/distance sensor that has been used mainly for object avoidance in various robotics projects . It essentially gives your Arduino eyes / spacial awareness and can prevent your robot from crashing or falling off a

table. It has also been used in turret applications, water level sensing, and even as a parking sensor. This simple project will use the HC-SR04 sensor with an Arduino and a Processing sketch to provide a neat little interactive display on your computer screen.

SERVO: A servomotor is a rotary actuator or linear actuator that allows for precise control of angular or linear position, velocity and acceleration. It consists of a suitable motor coupled to a sensor for position feedback.

ARDUINO: Arduino is a computer hardware and software company, project, and user community that designs and manufactures microcontroller kits for building digital devices and interactive objects that can sense and control objects in the physical world.

Buzzer: buzzer is a device that can make noise if the buzzer is programmed to sound alarm at that point. Its cheap and affordable and useful for many projects

Construction:

- *Connect +5v and Ground from Arduino to the breadboard
- *Connect the +5V of servo motor to Arduino 5volt and Ground of Servo motor to Arduino ground
- *For the ultrasonic sensor connect the Trigger pin to 2 and Echo pin to pin 3 of Arduino
- *And connect VCC to 5v of Arduino and ground to ground of Arduino
- *Connect the ground of Ultrasonic sensor to Arduino ground
- *Place the ultrasonic sensor on the servo motor with any support to make it stand
- *Connect the buzzer to pin 5 of Arduino and ground it in the Arduino
- *Connect the LED With a resistor to avoid damage of LED On bread board
- *Now our Circuit is ready

Code:

The values for the angle and the distance measured by the sensor will be read from the Arduino board by the Processing IDE using the `SerialEvent()` function which reads the data from the Serial Port.

These values will be used for drawing the lines, the detected objects and some texts. For drawing the radar display we make this function `drawRadar()` which consist of `arc()` and `line()` functions

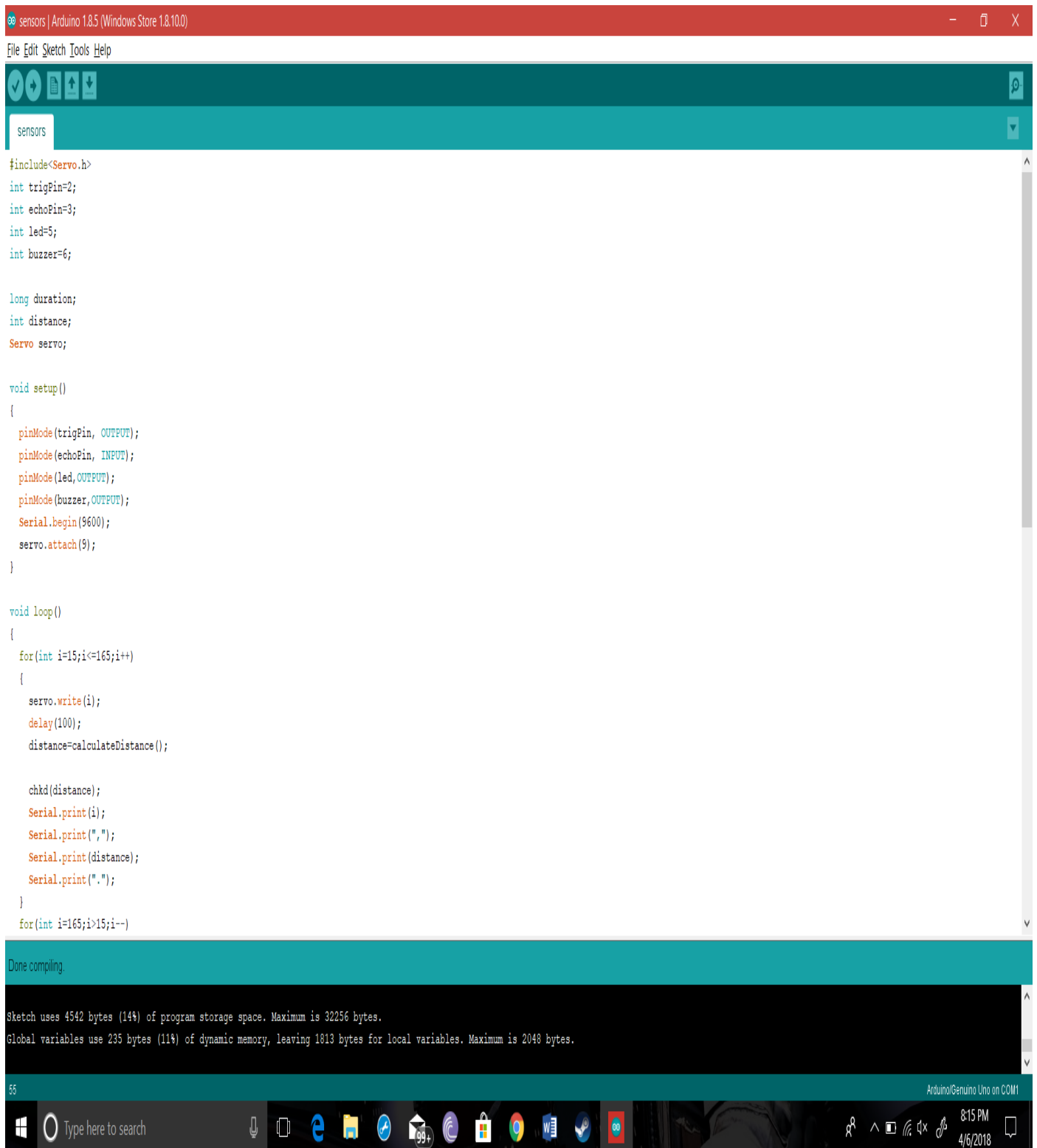
For drawing the moving lines we make this function `drawLine()`. Its center of rotation is set with the `translate()` function and using the `line()` function in which the `iAngle` variable is used to redraw the line for each degree.

For drawing the detected objects we made the `drawObject()` function. It receives the distance from the ultrasonic sensor, transforms it into pixels. Then, using the angle detected by the sensor it draws the object on the radar screen

To illustrate the text on the screen, we make the `drawText()` function that draws texts on some particular locations. All of these functions are called in the main `draw()` function which is repeated in each iteration to draw the screen details.

We are using the `fill()` function with 2 parameters for simulating motion blur and slow fade of the moving line shows the final appearance of the radar screen:

Arduino Code:



```
sensors | Arduino 1.8.5 (Windows Store 1.8.10.0)
File Edit Sketch Tools Help

sensors

#include<Servo.h>

int trigPin=2;
int echoPin=3;
int led=5;
int buzzer=6;

long duration;
int distance;
Servo servo;

void setup()
{
  pinMode(trigPin, OUTPUT);
  pinMode(echoPin, INPUT);
  pinMode(led, OUTPUT);
  pinMode(buzzer, OUTPUT);
  Serial.begin(9600);
  servo.attach(9);
}

void loop()
{
  for(int i=15;i<=165;i++)
  {
    servo.write(i);
    delay(100);
    distance=calculateDistance();

    chkd(distance);
    Serial.print(i);
    Serial.print(",");
    Serial.print(distance);
    Serial.print(".");
  }
  for(int i=165;i>15;i--)
```

Done compiling.

Sketch uses 4542 bytes (14%) of program storage space. Maximum is 32256 bytes.
Global variables use 235 bytes (11%) of dynamic memory, leaving 1813 bytes for local variables. Maximum is 2048 bytes.

55 Arduino/Genuino Uno on COM1

Type here to search 8:15 PM 4/6/2018



sensors

```
distance=calculateDistance();

chkd(distance);
Serial.print(i);
Serial.print(",");
Serial.print(distance);
Serial.print(".");
}
for(int i=165;i>15;i--)
{
  servo.write(i);
  delay(100);
  distance=calculateDistance();

  chkd(distance);
  Serial.print(i);
  Serial.print(",");
  Serial.print(distance);
  Serial.print(".");

}
}
void chkd(int d)
{
  if(d<=20)
  {
    digitalWrite(led,HIGH);
    digitalWrite(buzzer,HIGH);
  }
  else
  {
    digitalWrite(led,LOW);
    digitalWrite(buzzer,LOW);
  }
}
```

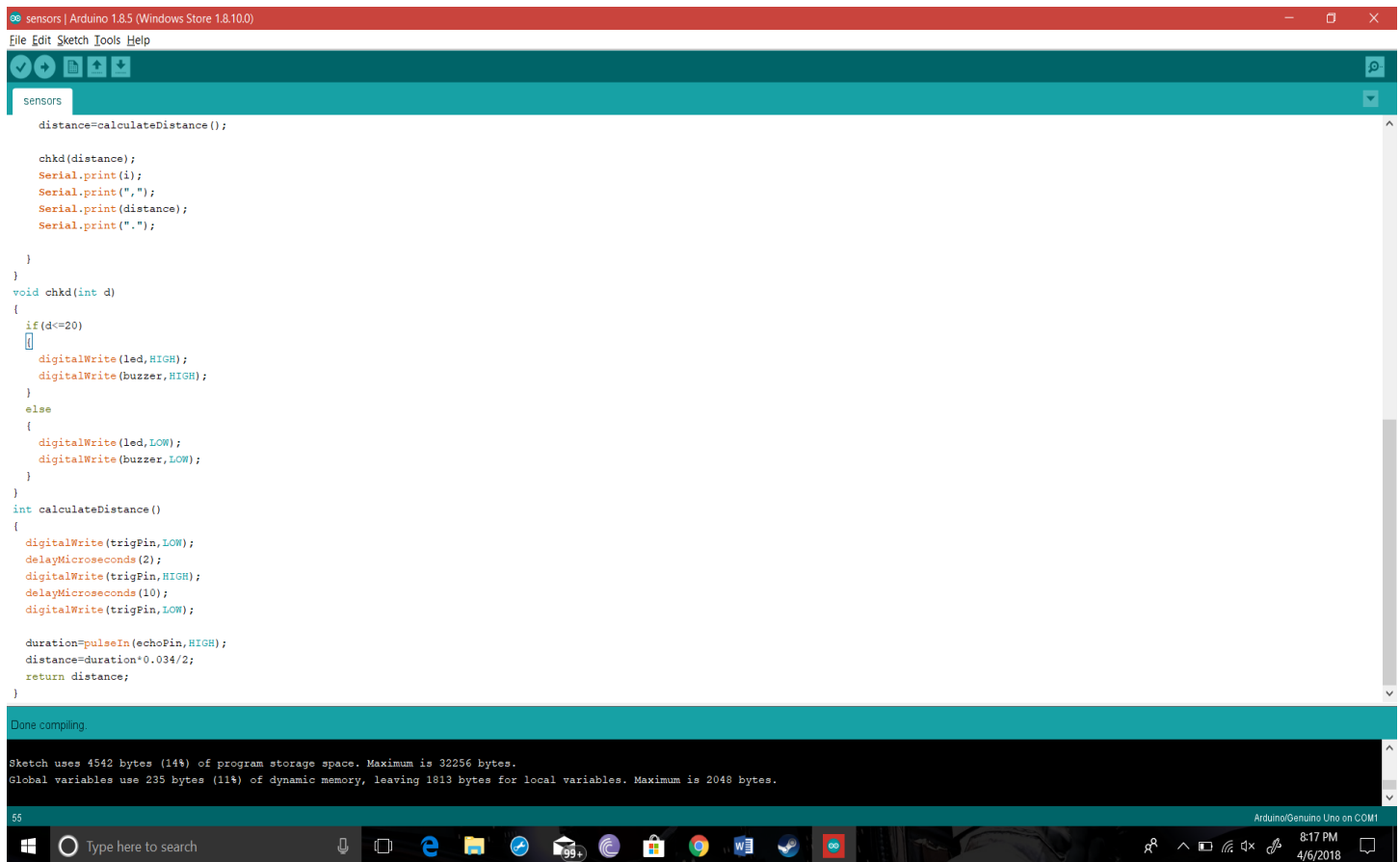
Done compiling.

Sketch uses 4542 bytes (14% of program storage space. Maximum is 32256 bytes.

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Arduino/Genuino Uno on COM1



The screenshot shows the Arduino IDE interface with the following code in the main editor:

```
sensors

distance=calculateDistance();

chkd(distance);
Serial.print(i);
Serial.print(",");
Serial.print(distance);
Serial.print("\n");

}

}
void chkd(int d)
{
  if(d<=20)
  {
    digitalWrite(led,HIGH);
    digitalWrite(buzzer,HIGH);
  }
  else
  {
    digitalWrite(led,LOW);
    digitalWrite(buzzer,LOW);
  }
}
int calculateDistance()
{
  digitalWrite(trigPin,LOW);
  delayMicroseconds(2);
  digitalWrite(trigPin,HIGH);
  delayMicroseconds(10);
  digitalWrite(trigPin,LOW);

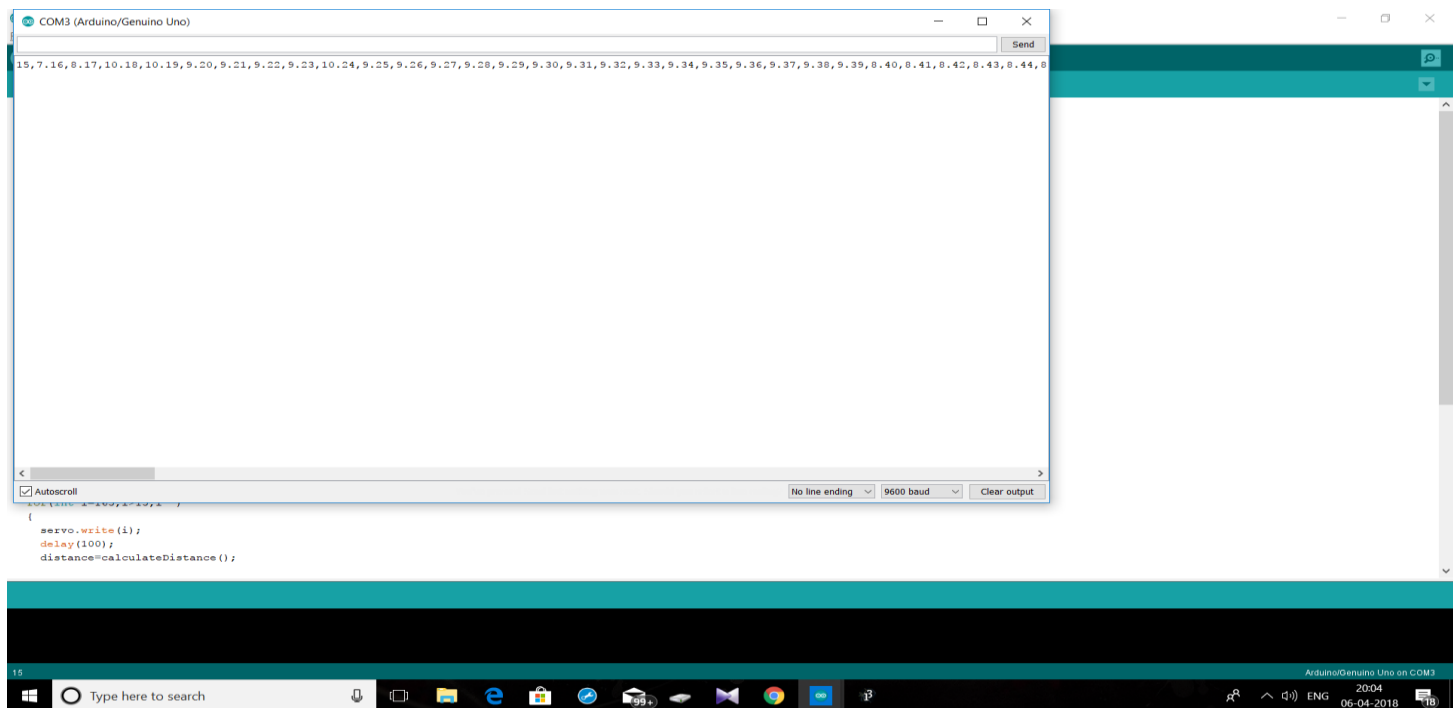
  duration=pulseIn(echoPin,HIGH);
  distance=duration*0.034/2;
  return distance;
}
```

Below the code editor, the 'Done compiling' message is displayed:

```
Done compiling.

Sketch uses 4542 bytes (14%) of program storage space. Maximum is 32256 bytes.
Global variables use 235 bytes (11%) of dynamic memory, leaving 1813 bytes for local variables. Maximum is 2048 bytes.
```

The status bar at the bottom indicates 'Arduino/Genuino Uno on COM1' and the date '4/6/2018'.



The screenshot shows the serial monitor window titled 'COM3 (Arduino/Genuino Uno)'. The output displays a series of distance measurements in centimeters, separated by commas. The first line of output is:

```
15,7.16,8.17,10.10,10.19,9.20,9.21,9.22,9.23,10.24,9.25,9.26,9.27,9.28,9.29,9.30,9.31,9.32,9.33,9.34,9.35,9.36,9.37,9.38,9.39,8.40,8.41,8.42,8.43,8.44,8.45,8.46,8.47,8.48,8.49,8.50,8.51,8.52,8.53,8.54,8.55,8.56,8.57,8.58,8.59,8.60,8.61,8.62,8.63,8.64,8.65,8.66,8.67,8.68,8.69,8.70,8.71,8.72,8.73,8.74,8.75,8.76,8.77,8.78,8.79,8.80,8.81,8.82,8.83,8.84,8.85,8.86,8.87,8.88,8.89,8.90,8.91,8.92,8.93,8.94,8.95,8.96,8.97,8.98,8.99,9.00,9.01,9.02,9.03,9.04,9.05,9.06,9.07,9.08,9.09,9.10,9.11,9.12,9.13,9.14,9.15,9.16,9.17,9.18,9.19,9.20,9.21,9.22,9.23,9.24,9.25,9.26,9.27,9.28,9.29,9.30,9.31,9.32,9.33,9.34,9.35,9.36,9.37,9.38,9.39,9.40,9.41,9.42,9.43,9.44,9.45,9.46,9.47,9.48,9.49,9.50,9.51,9.52,9.53,9.54,9.55,9.56,9.57,9.58,9.59,9.60,9.61,9.62,9.63,9.64,9.65,9.66,9.67,9.68,9.69,9.70,9.71,9.72,9.73,9.74,9.75,9.76,9.77,9.78,9.79,9.80,9.81,9.82,9.83,9.84,9.85,9.86,9.87,9.88,9.89,9.90,9.91,9.92,9.93,9.94,9.95,9.96,9.97,9.98,9.99,10.00,10.01,10.02,10.03,10.04,10.05,10.06,10.07,10.08,10.09,10.10,10.11,10.12,10.13,10.14,10.15,10.16,10.17,10.18,10.19,10.20,10.21,10.22,10.23,10.24,10.25,10.26,10.27,10.28,10.29,10.30,10.31,10.32,10.33,10.34,10.35,10.36,10.37,10.38,10.39,10.40,10.41,10.42,10.43,10.44,10.45,10.46,10.47,10.48,10.49,10.50,10.51,10.52,10.53,10.54,10.55,10.56,10.57,10.58,10.59,10.60,10.61,10.62,10.63,10.64,10.65,10.66,10.67,10.68,10.69,10.70,10.71,10.72,10.73,10.74,10.75,10.76,10.77,10.78,10.79,10.80,10.81,10.82,10.83,10.84,10.85,10.86,10.87,10.88,10.89,10.90,10.91,10.92,10.93,10.94,10.95,10.96,10.97,10.98,10.99,11.00,11.01,11.02,11.03,11.04,11.05,11.06,11.07,11.08,11.09,11.10,11.11,11.12,11.13,11.14,11.15,11.16,11.17,11.18,11.19,11.20,11.21,11.22,11.23,11.24,11.25,11.26,11.27,11.28,11.29,11.30,11.31,11.32,11.33,11.34,11.35,11.36,11.37,11.38,11.39,11.40,11.41,11.42,11.43,11.44,11.45,11.46,11.47,11.48,11.49,11.50,11.51,11.52,11.53,11.54,11.55,11.56,11.57,11.58,11.59,11.60,11.61,11.62,11.63,11.64,11.65,11.66,11.67,11.68,11.69,11.70,11.71,11.72,11.73,11.74,11.75,11.76,11.77,11.78,11.79,11.80,11.81,11.82,11.83,11.84,11.85,11.86,11.87,11.88,11.89,11.90,11.91,11.92,11.93,11.94,11.95,11.96,11.97,11.98,11.99,12.00,12.01,12.02,12.03,12.04,12.05,12.06,12.07,12.08,12.09,12.10,12.11,12.12,12.13,12.14,12.15,12.16,12.17,12.18,12.19,12.20,12.21,12.22,12.23,12.24,12.25,12.26,12.27,12.28,12.29,12.30,12.31,12.32,12.33,12.34,12.35,12.36,12.37,12.38,12.39,12.40,12.41,12.42,12.43,12.44,12.45,12.46,12.47,12.48,12.49,12.50,12.51,12.52,12.53,12.54,12.55,12.56,12.57,12.58,12.59,12.60,12.61,12.62,12.63,12.64,12.65,12.66,12.67,12.68,12.69,12.70,12.71,12.72,12.73,12.74,12.75,12.76,12.77,12.78,12.79,12.80,12.81,12.82,12.83,12.84,12.85,12.86,12.87,12.88,12.89,12.90,12.91,12.92,12.93,12.94,12.95,12.96,12.97,12.98,12.99,13.00,13.01,13.02,13.03,13.04,13.05,13.06,13.07,13.08,13.09,13.10,13.11,13.12,13.13,13.14,13.15,13.16,13.17,13.18,13.19,13.20,13.21,13.22,13.23,13.24,13.25,13.26,13.27,13.28,13.29,13.30,13.31,13.32,13.33,13.34,13.35,13.36,13.37,13.38,13.39,13.40,13.41,13.42,13.43,13.44,13.45,13.46,13.47,13.48,13.49,13.50,13.51,13.52,13.53,13.54,13.55,13.56,13.57,13.58,13.59,13.60,13.61,13.62,13.63,13.64,13.65,13.66,13.67,13.68,13.69,13.70,13.71,13.72,13.73,13.74,13.75,13.76,13.77,13.78,13.79,13.80,13.81,13.82,13.83,13.84,13.85,13.86,13.87,13.88,13.89,13.90,13.91,13.92,13.93,13.94,13.95,13.96,13.97,13.98,13.99,14.00,14.01,14.02,14.03,14.04,14.05,14.06,14.07,14.08,14.09,14.10,14.11,14.12,14.13,14.14,14.15,14.16,14.17,14.18,14.19,14.20,14.21,14.22,14.23,14.24,14.25,14.26,14.27,14.28,14.29,14.30,14.31,14.32,14.33,14.34,14.35,14.36,14.37,14.38,14.39,14.40,14.41,14.42,14.43,14.44,14.45,14.46,14.47,14.48,14.49,14.50,14.51,14.52,14.53,14.54,14.55,14.56,14.57,14.58,14.59,14.60,14.61,14.62,14.63,14.64,14.65,14.66,14.67,14.68,14.69,14.70,14.71,14.72,14.73,14.74,14.75,14.76,14.77,14.78,14.79,14.80,14.81,14.82,14.83,14.84,14.85,14.86,14.87,14.88,14.89,14.90,14.91,14.92,14.93,14.94,14.95,14.96,14.97,14.98,14.99,15.00,15.01,15.02,15.03,15.04,15.05,15.06,15.07,15.08,15.09,15.10,15.11,15.12,15.13,15.14,15.15,15.16,15.17,15.18,15.19,15.20,15.21,15.22,15.23,15.24,15.25,15.26,15.27,15.28,15.29,15.30,15.31,15.32,15.33,15.34,15.35,15.36,15.37,15.38,15.39,15.40,15.41,15.42,15.43,15.44,15.45,15.46,15.47,15.48,15.49,15.50,15.51,15.52,15.53,15.54,15.55,15.56,15.57,15.58,15.59,15.60,15.61,15.62,15.63,15.64,15.65,15.66,15.67,15.68,15.69,15.70,15.71,15.72,15.73,15.74,15.75,15.76,15.77,15.78,15.79,15.80,15.81,15.82,15.83,15.84,15.85,15.86,15.87,15.88,15.89,15.90,15.91,15.92,15.93,15.94,15.95,15.96,15.97,15.98,15.99,16.00,16.01,16.02,16.03,16.04,16.05,16.06,16.07,16.08,16.09,16.10,16.11,16.12,16.13,16.14,16.15,16.16,16.17,16.18,16.19,16.20,16.21,16.22,16.23,16.24,16.25,16.26,16.27,16.28,16.29,16.30,16.31,16.32,16.33,16.34,16.35,16.36,16.37,16.38,16.39,16.40,16.41,16.42,16.43,16.44,16.45,16.46,16.47,16.48,16.49,16.50,16.51,16.52,16.53,16.54,16.55,16.56,16.57,16.58,16.59,16.60,16.61,16.62,16.63,16.64,16.65,16.66,16.67,16.68,16.69,16.70,16.71,16.72,16.73,16.74,16.75,16.76,16.77,16.78,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Processing3 Code:

sketch_180405b | Processing 3.3.7

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Java ▾

sketch_180405b ▾

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1 import processing.serial.*; // imports library for serial communication
2 import java.awt.event.KeyEvent; // imports library for reading the data from the serial port
3 import java.io.IOException;
4 Serial myPort; // defines Object Serial
5 // defubes variables
6 String angle="";
7 String distance="";
8 String data="";
9 String noObject;
10 float pixsDistance;
11 int iAngle, iDistance;
12 int index1=0;
13 int index2=0;
14 PFont orcFont;
15 void setup() {
16 size(1920, 1080);
17 smooth();
18 myPort = new Serial(this,"COM3", 9600); // starts the serial communication
19 myPort.bufferUntil('.'); // reads the data from the serial port up to the character '.'. So actually it reads this: angle,distance.
20 orcFont = loadFont("OCRAExtended-30.vlw");
21 }
22 void draw() {
23 fill(98,245,31);
24 textFont(orcFont);
25 // simulating motion blur and slow fade of the moving line
26 noStroke();
27 fill(0,4);
28 rect(0, 0, width, 1010);
29 fill(98,245,31); // green color
30 // calls the functions for drawing the radar
31 drawRadar();
32 drawLine();
33 drawObject();
34 drawText();
```

Console

Errors

Type here to search



16 cm 20 cm 30 cm 2007 06-04-2018 18



Java ▾

sketch_180405b ▾

```
31 drawRadar();
32 drawLine();
33 drawObject();
34 drawText();
35 }
36 void serialEvent (Serial myPort) { // starts reading data from the Serial Port
37 // reads the data from the Serial Port up to the character '.' and puts it into the String variable "data".
38 data = myPort.readStringUntil('.');
39 data = data.substring(0,data.length()-1);
40 index1 = data.indexOf(","); // find the character ',' and puts it into the variable "index1"
41 angle= data.substring(0, index1); // read the data from position "0" to position of the variable index1 or thats the value of the angle the Arduino Board sent into the Serial Port
42 distance= data.substring(index1+1, data.length()); // read the data from position "index1" to the end of the data pr thats the value of the distance
43 // converts the String variables into Integer
44 iAngle = int(angle);
45 iDistance = int(distance);
46 }
47 void drawRadar() {
48 pushMatrix();
49 translate(960,1000); // moves the starting coordinats to new location
50 noFill();
51 strokeWeight(2);
52 stroke(98,245,31);
53 // draws the arc lines
54 arc(0,0,1800,1800,PI,TWO_PI);
55 arc(0,0,1400,1400,PI,TWO_PI);
56 arc(0,0,1000,1000,PI,TWO_PI);
57 arc(0,0,600,600,PI,TWO_PI);
58 // draws the angle lines
59 line(-960,0,960,0);
60 line(0,0,-960*cos(radians(30)),-960*sin(radians(30)));
61 line(0,0,-960*cos(radians(60)),-960*sin(radians(60)));
62 line(0,0,-960*cos(radians(90)),-960*sin(radians(90)));
63 line(0,0,-960*cos(radians(120)),-960*sin(radians(120)));
64 line(0,0,-960*cos(radians(150)),-960*sin(radians(150)));
```

Console

Errors

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sketch_180405b

```
64 line(0,0,-960*cos(radians(150)),-960*sin(radians(150)));
65 line(-960*cos(radians(30)),0,960,0);
66 popMatrix();
67 }
68 void drawObject() {
69   pushMatrix();
70   translate(960,1000); // moves the starting coordinats to new location
71   strokeWeight(9);
72   stroke(255,10,10); // red color
73   pixsDistance = iDistance*22.5; // covers the distance from the sensor from cm to pixels
74   // limiting the range to 40 cms
75   if(iDistance<40){
76     // draws the object according to the angle and the distance
77     line(pixsDistance*cos(radians(iAngle)),-pixsDistance*sin(radians(iAngle)),950*cos(radians(iAngle)),-950*sin(radians(iAngle)));
78   }
79   popMatrix();
80 }
81 void drawLine() {
82   pushMatrix();
83   strokeWeight(9);
84   stroke(30,250,60);
85   translate(960,1000); // moves the starting coordinats to new location
86   line(0,0,950*cos(radians(iAngle)),-950*sin(radians(iAngle))); // draws the line according to the angle
87   popMatrix();
88 }
89 void drawText() { // draws the texts on the screen
90   pushMatrix();
91   if(iDistance>40) {
92     noObject = "Out of Range";
93   }
94   else {
95     noObject = "In Range";
96   }
97   fill(A A A);
```

Console

Errors

Type here to search





Java ▾

sketch_180405b ▾

```
94 else {
95   noObject = "In Range";
96 }
97 fill(0,0,0);
98 noStroke();
99 rect(0, 1010, width, 1000);
100 fill(98,245,31);
101 textSize(25);
102 text("10cm",1180,990);
103 text("20cm",1380,990);
104 text("30cm",1580,990);
105 text("40cm",1780,990);
106 textSize(40);
107 text("Object: " + noObject, 240, 1050);
108 text("Angle: " + iAngle + " °", 1050, 1050);
109 text("Distance: ", 1380, 1050);
110 if(iDistance<40) {
111   text(" " + iDistance + " cm", 1400, 1050);
112 }
113 textSize(25);
114 fill(98,245,60);
115 translate(961+960*cos(radians(30)),982-960*sin(radians(30)));
116 rotate(-radians(-60));
117 text("30°",0,0);
118 resetMatrix();
119 translate(954+960*cos(radians(60)),984-960*sin(radians(60)));
120 rotate(-radians(-30));
121 text("60°",0,0);
122 resetMatrix();
123 translate(945+960*cos(radians(90)),990-960*sin(radians(90)));
124 rotate(radians(0));
125 text("90°",0,0);
126 resetMatrix();
127 translate(935+960*cos(radians(120)),1002-960*sin(radians(120)));
```

Console

Errors

Type here to search



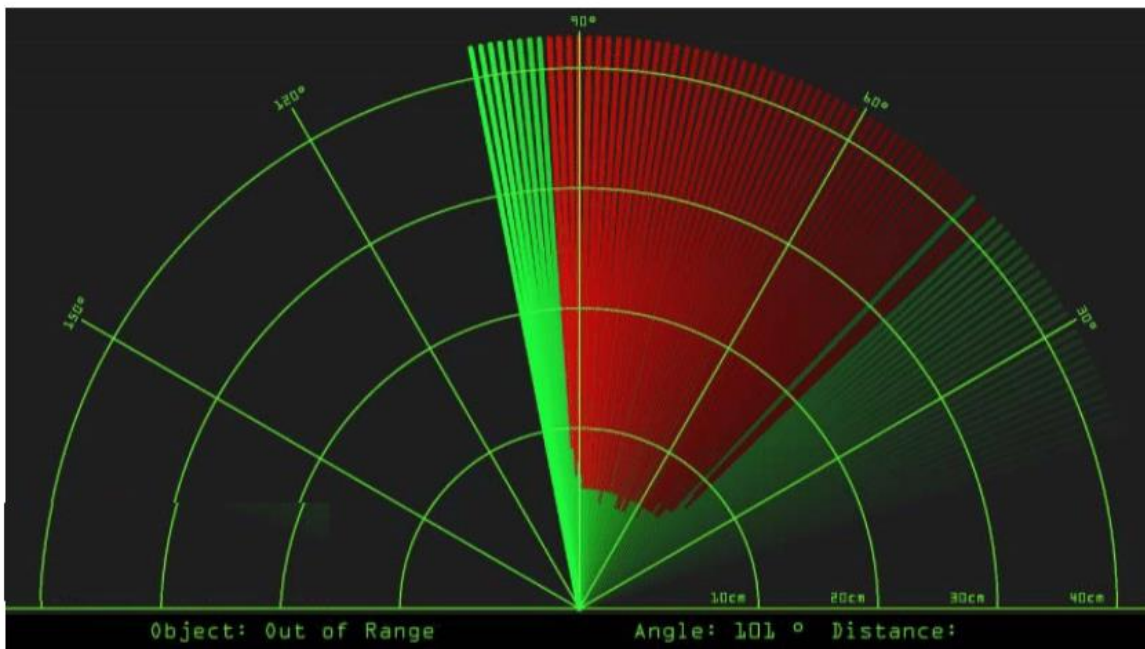
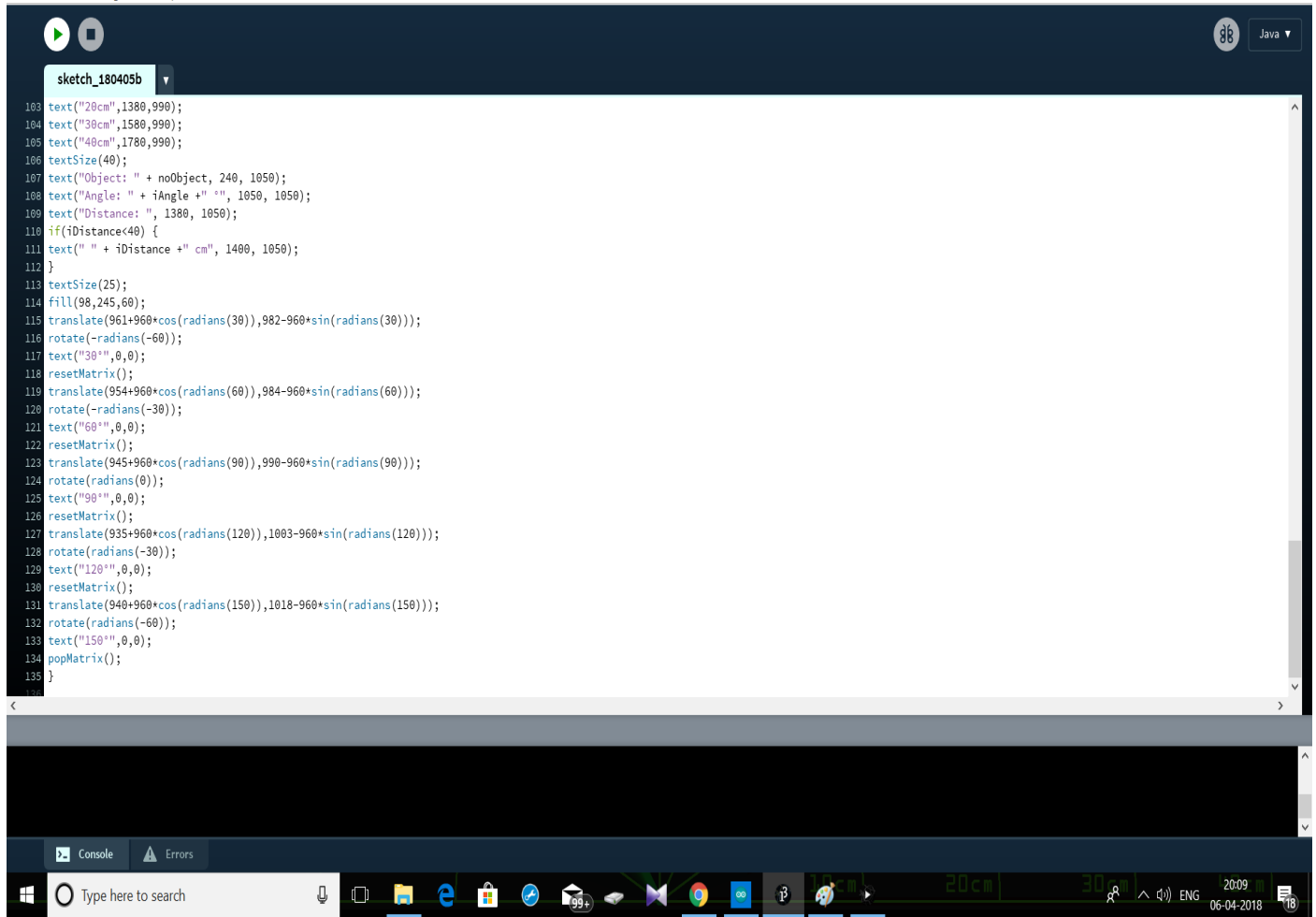


Fig:Radar Image

Output screen of Proccessing will be like this..This is the Radar

Working:

*After Steuping the circuit upload the Arduino code to Arduino and then run the processing code.

*When it Starts running the servor motor will rotate and ultrasonic sensor will also rotate along with it and servo motor starts roating from the specified angle and now the ultrasonic sensor send and receives waves and calculates the distance and if there is no obstacle for its specified distance then it would be green in the radar which will be displayed on computer or Mobile phone using processor software and it displays the angle of ultrasonic sensor and distance of object also

*Then if the sensor detects any object within a specific range then the LED glows up and buzzer in our Arduino starts ringing and we can know that some object is that specific region and we can know the distance from the Radar in our computer

*Thus we can know the object which may be incoming without knowing to us

*Our Project idea is just a basic working model still there are lots of applications used by radar

*This is a important application in all parts of science

*We could even use MAT LAB to display radar instead of processing3 application.

Application:

*My Radar Object can be used near by doors to detect any person walking through the door and then to identify angle of object with respect to the servo motor and can be used to find distance or angle of any object from the sensor.

→Now some application of usual sensors are,

Military Applications:

The RADAR has 3 major applications in Military:

- In air defense it is used for target detection, target recognition and weapon control (directing the weapon to the tracked targets).
- In missile system to guide the weapon.
- Identifying enemy locations in map.

Air Traffic Control:

The RADAR has 3 major applications in Air Traffic control:

- To control air traffic near airports. The Air Surveillance RADAR is used to detect and display the aircraft's position in the airport terminals.
- To guide the aircraft to land in bad weather using Precision Approach RADAR.
- To scan the airport surface for aircraft and ground vehicle positions

Remote Sensing: RADAR can be used for observing weather or observing planetary positions and monitoring sea ice to ensure smooth route for ships.

Ground Traffic Control: RADAR can also be used by traffic police to determine speed of the vehicle, controlling the movement of vehicles by giving warnings about presence of other vehicles or any other obstacles behind them.

Space: RADAR has 3 major applications:

- To guide the space vehicle for safe landing on moon
- To observe the planetary systems
- To detect and track satellites
- To monitor the meteors

Conclusion:

Radar is normally used to determine velocity, range, and position of an object. In this technical project, we read the distance and angles of detected objects in order to convert these data into visual information. The performance of our project is so good. It works smoothly to detect objects within the designed

range. The screen shows the information clearly with enough delay for the user to read it. This project could be helpful for object avoidance/ detection applications. This project could easily be extended and could be used in any systems may need it.

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THANK YOU!!!!!!!