**Faculty of Information Technology**

**IN – 1900 ICT Project**

**CAN CRUSHER**

Group No: 10

Index Number Name

**204092P KANAKKAHEWA Y.B.**

204140M NISHATH M.N.H.A.

204186H SANCHITHA S.P.Y.P.

204020V BASNAYAKE S.B.

204098N KAVINDA K.A.R.

Supervisor’s Name: Mr. B.H. Sudantha

Dean/Senior Lecturer

Faculty of Information Technology

University of Moratuwa

Signature of Supervisor: Date of Submission: 08/06/2022

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# 1.0 Introduction

In the last few decades, technology has progressed at a staggering rate. Smartphones, the internet, cloud computing, and hundreds of other inventions are changing every face of our lives. Communication, business, day to day life, government, travel, fundraising, and even agriculture have been affected. As because of this evolution of technology the human kind has achieved so many things as well as they have caused a lot of problems and disasters too. **Environmental Pollution** is one of those major disasters. Due to the improper disposal ways of non-biodegradable garbage such as plastic and metal materials have caused many problems when it comes to environmental pollution. In order to prevent this situation, the 3R concepts of Reduce, Recycle and Reuse has been introduced. This method is being mainly used worldwide for the plastic components such as plastic bottles, cups, containers etc. But when considering the metallic materials specially the **Alluminum** materials which people use in their day-to-day life, such as beer cans, energy drink cans and containers this 3R concept is not widely used and applied. As a result of that the aluminum disposal has been done in an improper way for ages for many reasons. So, the environmental pollution has now become a severe issue that the people have been tempted to rethink about it.

# 2.0 Literature Survey

This chapter gives a brief description of similar projects that are designed to help recycle Alluminium cans. And in common tongue these types of machines are known as Reverse Vending Machines.

**(1) Pepsi Reverse Vending Machine**

This machine has created through a partnership between Pepsi, Waste Management and Keep America Beautiful and manufactured by GreenOps. In order to use the machine people, have to scan the barcode on their PET plastic bottle or Aluminium can. Then the machine calculates how many points to be awarded for each item and a user can redeem his/her points for a prize on the host venue or at onGreenopolis.com

**(2) Tomra Reverse Vending Machines**

Tomra is a Norwegian Multinational Cooperation specializing themselves in manufacturing collection and sorting products. They have created wide range of Reverse Vending Machines depending on the scale.

**Mini Line Reverse Vending Machines**- This is their suggested reverse vending machines for small stores with small spaces.

Eg :- H10 & H11

**Standalone Line Reverse Vending Machines** – These are their Reverse Vending Machines with low to medium storage capacity. And much suitable for small and medium stores with much space.

Eg:-Tomra S1 Rugged, Tomra T70 Single & Dual ,Tomra T70 TriSort, Tomra T90

**Flexible Line Reverse Vending Machines** – There machines are tailor made to fit the customers’ requirements such as collecting items, storage capacity and the store’s layout.

Eg:- Tomra T9 with EasyPac & Tomra T9 with MultiPac

**Revolution Line Reverse Vending Machines**– In these systems’ customers can insert all of their containers at once.

Eg:-Tomra R1 & T9 with MultiPac Air

**Expert Line Reverse Vending Machines**– This is their solution for industrial level collecting and sorting. They suggest this system for beverage wholesalers, Logistic centers, System Operators, Bottle depots, Redemption Centers, Industrial facilities.

Eg:-TOMRA E1 Rücknahmezentrum

Even though, they manufacture different types of Reverse Vending Machines their technology is same in every machine. In these machines they differentiate containers by their barcode and the rewarding facility normally do depends on the owner. But mostly owners give coupons to be used in their stores.

**(3) RVM System’s Reverse Vending Machines**

RVM System is a Sweden based company specialized in manufacturing Reverse Vending Machines.

**Stand Alone Reverse Vending Machines** – These machines are designed to fit the needs of small stores or supermarkets. According to the manufactures these machines takes less space, easy to install, clean and maintain. They can scan between 50 to 60 containers per minute. And only sorts Aluminium cans, PET plastic bottles and glass containers.

Eg:- RVMX2,RVMX3, RVMX10, RVMX20 ,RVMX30, RVMX200

**Large Capacity Modular Reverse Vending Machines** – These Machines are designed to fit the needs of stores and supermarkets with high volumes of recyclable containers. These machines can sort maximum of 60 containers for minute and only takes Alluminium cans, PET plastic containers and glass bottles.

Eg:- RVM X Proline, RVM X Proline DUO, RVM X Proline Slim

**Mega/Bulk Reverse Vending Machines**

RVM Mega Proline Plus- This machine can process up to 100 containers a minute. And sorts PET plastic bottles, Aluminium cans and glass bottles. And according to the manufacturer this machine is also accessible for wheelchair and mobility scooter users.

In these machines the manufacturer sorts PET plastic bottles through a optical PET sensor and glass and Alluminium cans through scanning their barcode. And for the rewarding methods coupons or loyalty cards were used.

# 3.0 Aim & Objectives

## 3.1 Aim

* Develop an automated machine for dispose cans (ex: beer cans, soft drink cans) in an environmentally friendly method.

## 3.2 Objectives

* Protecting ecosystems and wildlife
* Influence people, not to throw cans everywhere by using a rewarding can collecting method
* Saving energy

(Producing aluminium from old products (old cans) uses less energy than making it from the scratch)

* Conserving natural resources by reducing risky, expensive and damaging mining and extraction of new metal ores
* Maintaining the beauty of the environment

# 4.0 Analysis and Design

So, In order to encourage recycling of Aluminium cans we propose an automated machine.

This invention collects used Aluminium cans and stores them in a proper way. At the first place we have used a servo motor to control the amount of cans entering at a time. Here the machine is designed and programmed in a manner to identify whether the user’s input is a proper Aluminium can or not. The validity of the Can will be checked with the help of the Inductive Proximity Sensor, weight sensor and the Ultrasonic sensor. We have used the HX711 load cell amplifier to control the weight sensor and HC-SR04 Ultrasonic sensor to determine the shape. If user’s input is a proper Can, the arm connected to the stepper motor will direct the Can to the crushing unit then the machine will crush and store it using the induction motor in the designated area. If not, the machine will return it back to the user. We have used L293d Driver motor driver in order to control the stepper motor.

The user will be rewarded according to his/her order of preference. The machine will give an option to the user through the 16\*2 LCD display to choose between a mobile reload or a donate the value to Little Hearts foundation using SIM 900A gsm module or get a timely fast charging facility according to user’s preference.

**Overall Block (Input – Output) Diagram**



Figure 1

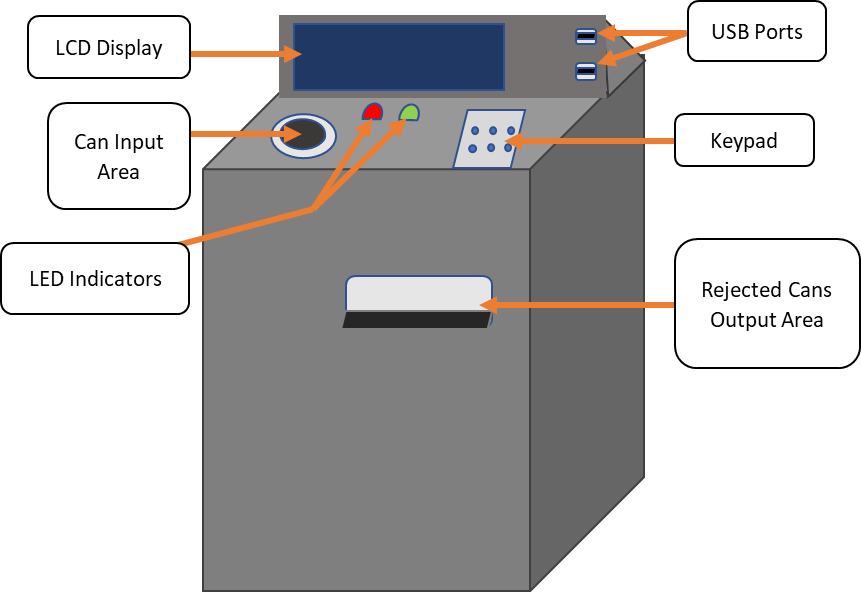
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Figure 2

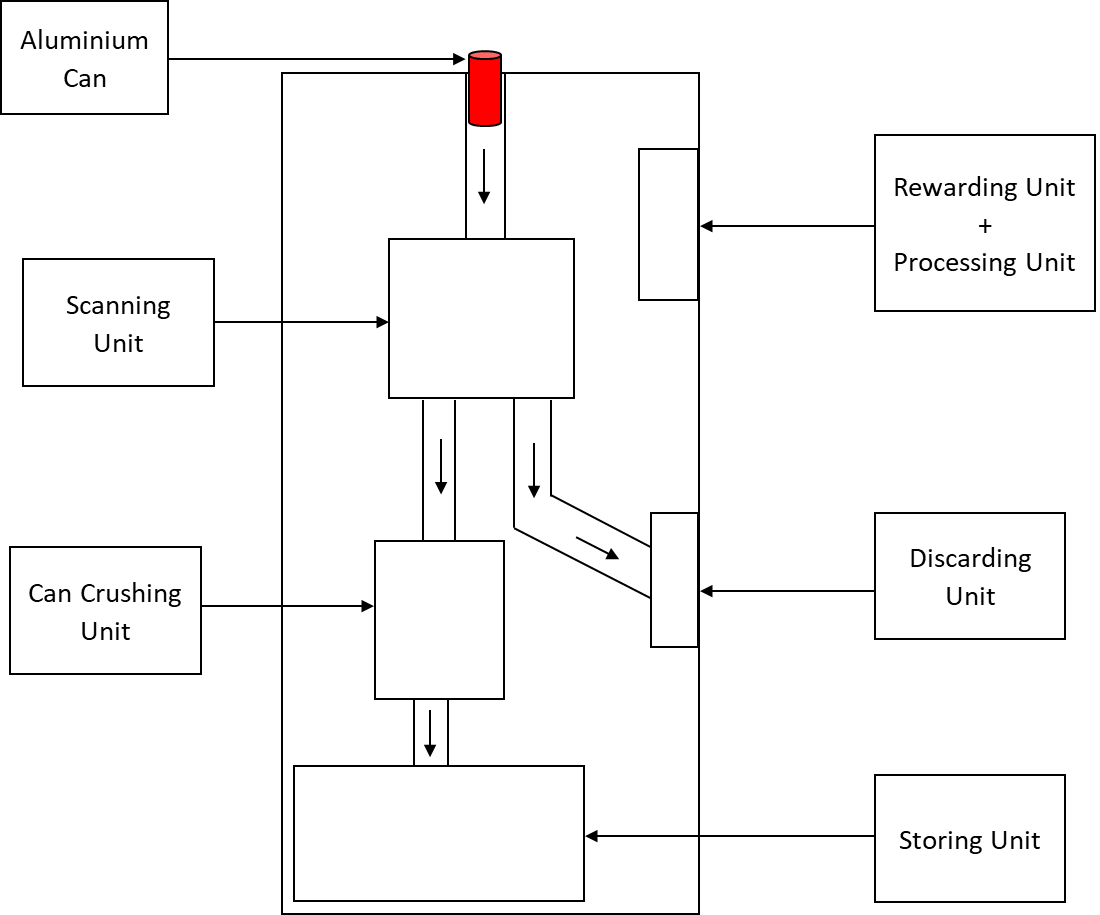
****

Figure 3

# 5.0 Testing and Implementation

We have finished the coding parts for all the components. We used Atmel Studio to write programs and all completed programs were tested using Proteus Software and used Keycad to design the PCB’s.

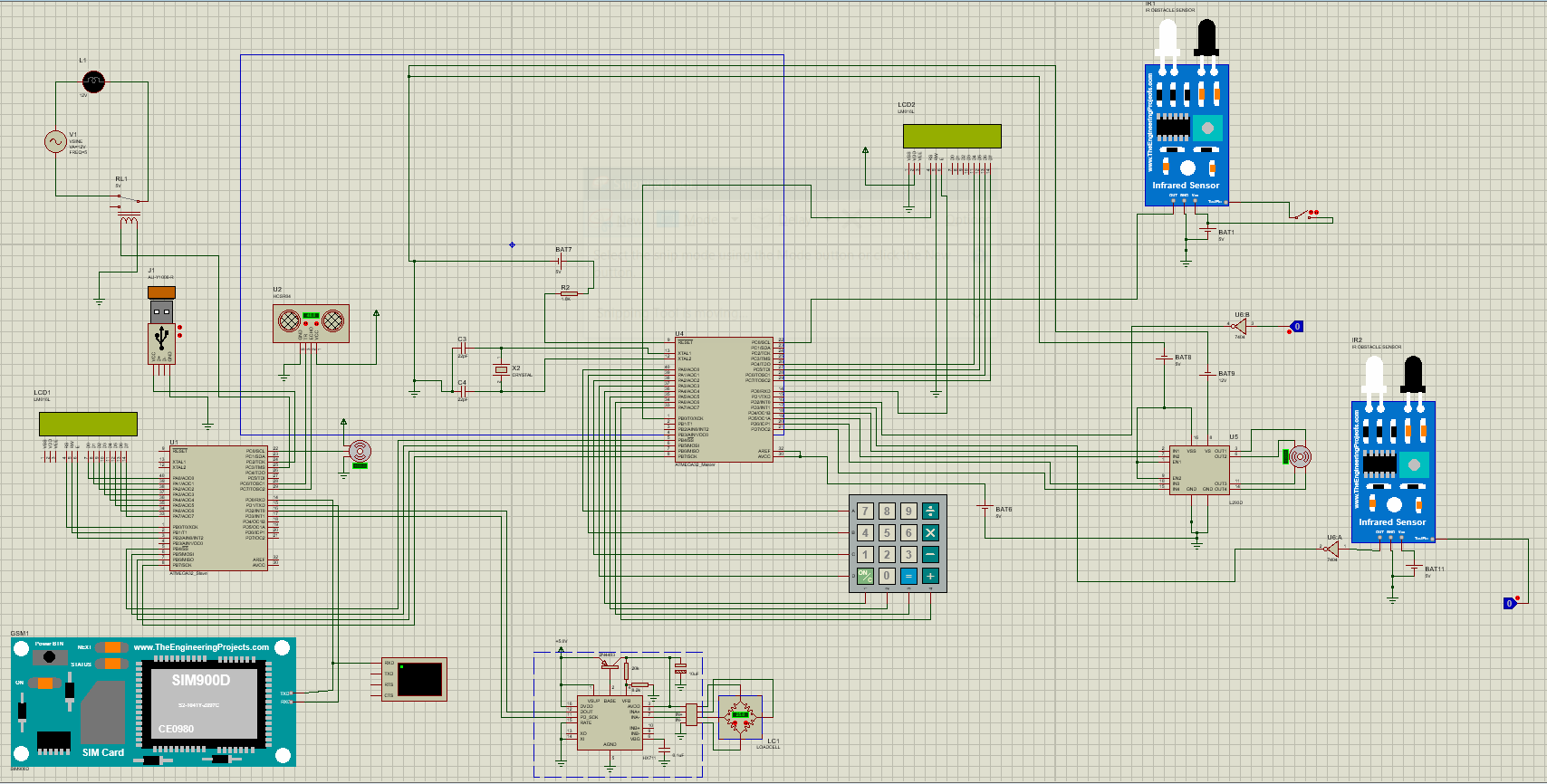
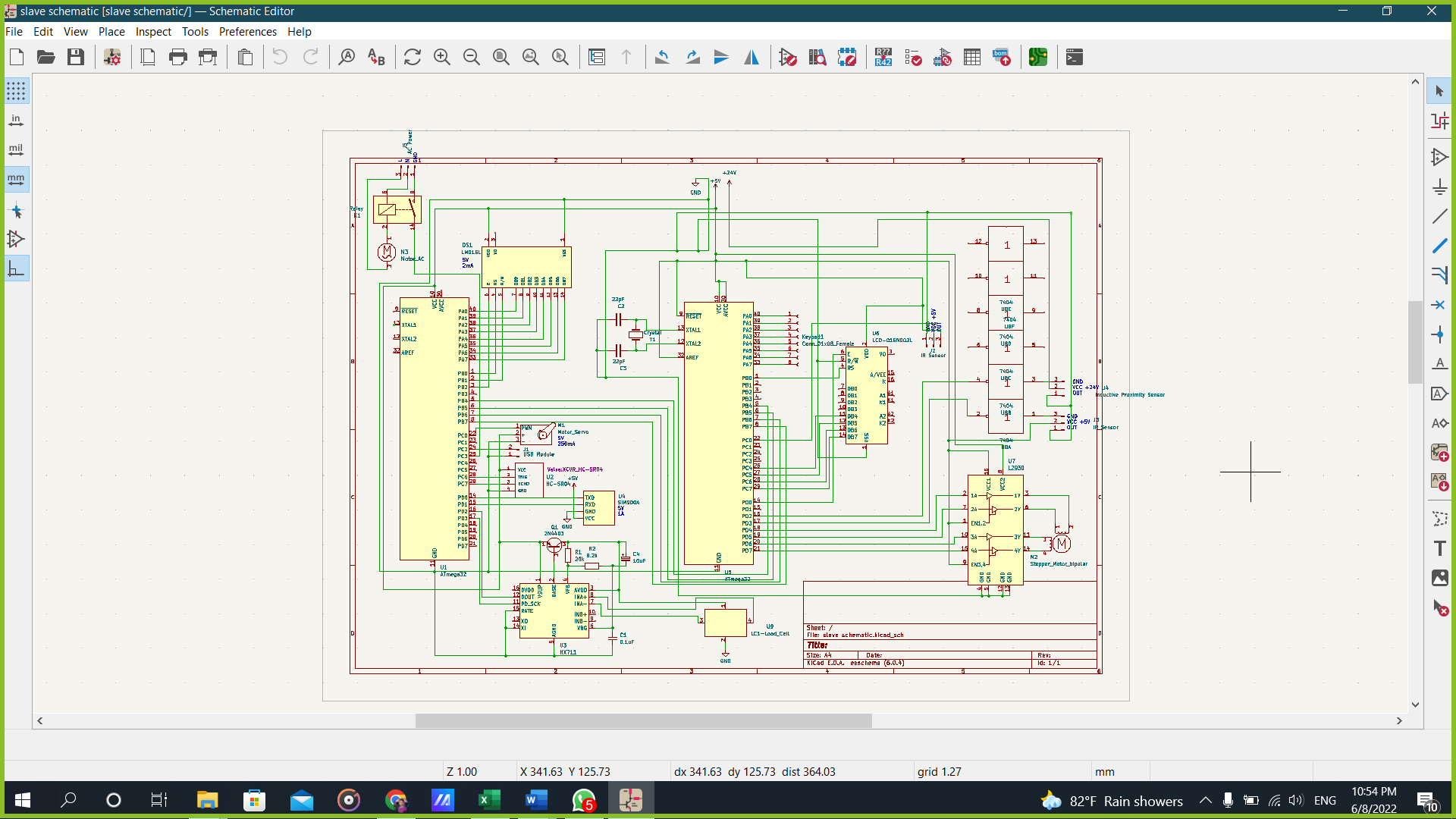


Figure 4 Proteus full circuit Diagram

**Schematic Diagram**



**PCB editor**

A screenshot of a computer

Description automatically generated with medium confidence

**3D viewer**

A picture containing text, electronics

Description automatically generated

# 

# 6.0 Estimated Cost & Expenditure

Table 1

****

# 7.0 References

|  |  |
| --- | --- |
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| [12] | [Online]. Available: https://www.electronicwings.com/avr-atmega/servo-motor-interfacing-with-atmega16. |
| [13] | [Online]. Available: https://www.electronicwings.com/avr-atmega/sim900a-gsm-module-interfacing-with-atmega1632-. |

# Further Work

If we are further developing this machine we can,

* Develop this machine to store plastic & glass cans/bottles.
* Offer a supermarket coupon or a voucher to the user as the reward.

**Appendix A – Individual Contribution**

1. **Student name-: Kanakkahewa Y.B – 204092P**

Learning & interfacing the,

* + - * Induction motor
      * Inductive Proximity Sensor
      * USB Ports
      * SPI communication

With and between the atmega32 microcontroller.

Inductive Proximity Sensor (LJ18A3-8-Z/AX)

In our project we use an Inductive Proximity Sensor to see whether the users can (Input) is metal or not as we are checking the physical attributes.

Proximity Sensors are used to detect objects (Ferrous and Non-Ferrous)

There are 3 types of proximity sensors

Inductive (Detect Metallic objects)

Capacitive (Detect objects)

IR (Read distances)

Here we use the Inductive Proximity Sensor to check the users input whether it is metal or not.

There are also two types of Inductive Proximity sensors as,

PNP

NPN

Here we use the NPN Inductive Proximity Sensor, and it has three wires to connect within.

Blue(GND)



Brown(VCC)

Black(Output)

Diagram, engineering drawing

Description automatically generated

**Data Sheet:** <https://www.daraz.lk/products/nickel-plated-brass-lj18a3-8-zax-npn-nc-dc-inductive-proximity-sensor-switch-detection-8mm-i108690427.html>

As this sensor is not available in Proteus, we decided to hardcode the relevant pin (PD2) which the sensors output pin will be connected. Using a **Logic Toggle**.

The output pin of the Inductive Proximity Sensor is connected to pin **PD2**.

**Inductive Proximity Sensor Circuit Diagram**

A picture containing text, shoji

Description automatically generated

**Code**

int Stepper\_motor(){

//Set a1, a2, a3, a4 as output

DDRD |= a1 | a2 | a3| a4;

//Set input & pull-up resistor

DDRD &= ~SW;

PORTD |= SW; //input pin

DDRD &= ~SW2; //pullup resistor high

PORTD |= SW2;

while(1){

if((PIND & SW) && (PIND & SW2)){

while(1){

if((!(PIND & SW2))){

while(1){

if((!(PIND & SW))){

validcan++;

PORTD |= a1;

PORTD &= ~a2;

PORTD &= ~a3;

PORTD &= ~a4;

*\_delay\_ms*(20);

PORTD |= a1;

PORTD &= ~a2;

PORTD &= ~ a3;

Here the code of the sensor is inside the stepper motor code as both functions together.

**Schematic editor**

Diagram

Description automatically generated

**PCB editor**

Diagram

Description automatically generated

**3D viewer**

Graphical user interface, application

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USB Module (SKU: 766344)

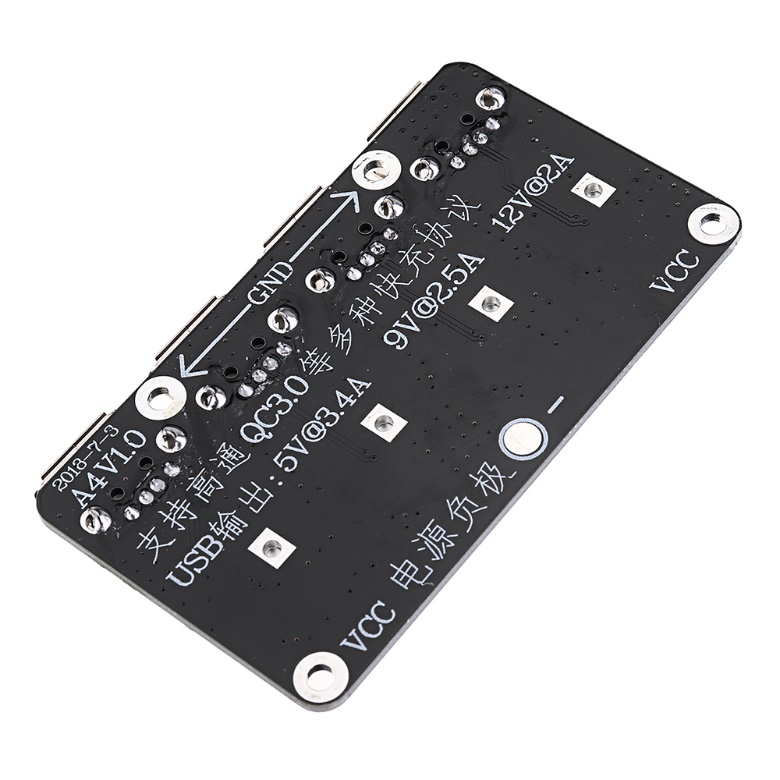
Here we have used fast charging USB ports to facilitate the fast charging.

Instead of type C we have decided to use USB type A as they are more common.

Also, we have used the 1x4 channel USB fast charging module to save space and power consumption.

A close-up of a computer chip

Description automatically generated with medium confidence



GND

VCC

Diagram

Description automatically generated

Here the D- and D+ ports inside the USB is neglected as they are for data transferring.

All we have to do is to power up the module using the supply.

Here the microcontroller acts as a switch. So the USB outlets will be powered on.

**Specifications**

Power : 2.5V – 5V

Standby current : 0.013A

Output maximum : 24W

Switching Frequency :220 kHZ

**Datasheet:** <https://www.banggood.com/4-USB-Fast-Charging-Module-Board-12V24V-to-QC2_0-QC3_0-Step-Down-Power-Supply-Module-12V-24V-p-1455615.html?cur_warehouse=CN>

**Code**

//amount=cans\*price;

amount=1000;

if(r\_choice==1) /\* fast charging \*/

{

PORTC=0b00000010; //Powerup USB s

}

else if(r\_choice==2) /\* Ez-Cash \*/

{

GSM\_Dialling();

lcd\_string("Reload send",11);

}

else if(r\_choice==3) /\* Little Hearts \*/

{

*sprintf*(lh,"LH %d",amount);

GSM\_Send\_Msg("77110",lh);

*memset*(lh,0,*strlen*(lh)); /\* clear lh array \*/

lcd\_string(".....Sending....",16);

*\_delay\_ms*(70); //original-7000

lcd\_clear();

lcd\_string("Sent to Little",14);

*\_delay\_ms*(30); // //original-500

lcd\_clear();

lcd\_string("Hearts",6);

*\_delay\_ms*(30); //original-500

lcd\_clear();

This is the code of the slave atmega microcontroller where USB powering up is included.

**USB Module Circuit Diagram**

Diagram, schematic

Description automatically generated

The above diagram is only for demonstration purposes as it cannot be simulated.

**Schematic editor**

**(USB + Induction Motor)**

Diagram, schematic

Description automatically generated

**PCB editor**

A screenshot of a computer

Description automatically generated with medium confidence

**3D viewer**

Diagram

Description automatically generated

SPI (Serial Peripheral Interface) Communication

Here we use a SPI communication method to communicate between the two atmega microcontrollers.

Chart

Description automatically generated with medium confidence

This is how we tested the code before implementing to the main system. Below is the code of the *master atmega*.

#define *F\_CPU* 8000000UL /\* Define CPU Frequency e.g. here its 8MHz \*/

#include <avr/io.h> /\* Include AVR std. library file \*/

#include <util/delay.h> /\* Include Delay header file \*/

#include <stdio.h>

#include <string.h>

//#include "LCD\_16x2\_H\_file.h" /\* Include LCD header file \*/

#include "SPI\_Master.c" /\* Include SPI master header file \*/

int main(void)

{

unsigned char count[4]="kin";

//char buffer[5];

//LCD\_Init();

SPI\_Init();

SS\_Enable;

for(int i=0;i<4;i++)

{

SPI\_Write(count[i]);

}

}

This is the code of *slave atmega*.

#define F\_CPU 8000000UL /\* Define CPU Frequency e.g. here its 8MHz \*/

#include <avr/io.h> /\* Include AVR std. library file \*/

#include <util/delay.h> /\* Include Delay header file \*/

#include <stdio.h>

#include <string.h> /\* Include string header file \*/

//#include "LCD\_16x2\_H\_file.h" /\* Include LCD header file \*/

#include "SPI\_Slave.c" /\* Include SPI slave header file \*/

int main(void)

{

unsigned char a;

//char buffer[5];

DDRA=0xff;

//LCD\_Init();

SPI\_Init();

for(int i=0;i<4;i++)

{

a = SPI\_Receive();

if(a=='k')

{

PORTA=0b00000100;

}

else if(a=='i')

{

PORTA=0b00000010;

*\_delay\_ms*(10);

}

else if(a=='n')

{

PORTA=0b00000100;

*\_delay\_ms*(10);

}

}

The codes in the final code cannot be demonstrated individually as they are all over the finished code.

Induction Motor (3Pahse)

A picture containing blue

Description automatically generated

We use an Induction motor to crush the cans.

In order to crush the the HP should be at least **0.1**

Table

Description automatically generated

**Induction Motor Circuit Diagram**

Diagram, schematic

Description automatically generated

Here a bulb is used as the motor because AC motors aren’t available in proteus.

Here we have use a 5V Relay so it can be triggered with 5V so the AC motor will get 240V from the AC current.

**Code**

int can\_number= *atoi*(can\_no);

r\_slave=SPI\_Read();

if(r\_slave)

{

for(int k=0;k<can\_number;k++){

ir2\_func();

Stepper\_motor();

if (validcan>0) //induction motor

{

PORTC=0b00000100;

}

}

}

SPI\_Write(validcan);

}

return 0;

}

**2. Student name-: Nishath M.N.H.A. – 204140M**

Learning & Interfacing the ,

• Stepper motor

• IR Sensor

• 4x4 Keypad

with the atmega32 microcontroller.

Stepper motor

For our project we use NEMA 17 bipolar stepper motor. To control the bipolar stepper motor two H-bridge circuits are required because stepper motor requires sufficient and controlled energy for phases in a precise sequence. So we are going to use L293d driver IC which can work as dual H-bridge driver to drive the stepper motor.

A picture containing text, electronics

Description automatically generated L293D Motor driver IC

Diagram, schematic

Description automatically generated

**Sequence of pulses that should send to motor in order to rotate the motor in 45° angles**

|  |  |  |  |
| --- | --- | --- | --- |
| A+ | A- | B- | B+ |
| 1 | 0 | 0 | 0 |
| 1 | 0 | 1 | 0 |
| 0 | 0 | 1 | 0 |
| 0 | 1 | 1 | 0 |
| 0 | 1 | 0 | 0 |
| 0 | 1 | 0 | 1 |
| 0 | 0 | 0 | 1 |
| 1 | 0 | 1 | 0 |

**Electrical Specification**

* + - NEMA17 have a recommended driving voltage of 12-24V.
    - Motor Type: Bipolar
    - Step Angle: is 1.8 deg

A picture containing diagram

Description automatically generated

Nema17 bipolar stepper motor

Function of the code

After the scanning process happened .If the can identified as an aluminium can then can would be send into crushing unit and if the can is rejected then it would be send into Discarding unit .We are using an arm that can rotate by a stepper motor to do the Process of moving the can into crushing unit or discarding unit.

**Code**

#ifndef *F\_CPU*

#define *F\_CPU* 16000000UL //freaquency of external crystal

#endif

#include <avr/io.h>

#include <util/delay.h>

//define interfacing pins between L293D and ATmega32

#define a1 (1<<PD4)

#define a2 (1<<PD5)

#define a3 (1<<PD6)

#define a4 (1<<PD7)

//For switch

#define SW (1<<PD3) //Ir

#define SW2 (1<<PD2) //ALL validation

int main(void){

Stepper\_motor();

return(0);

}

void Stepper\_motor(){

//Set a1, a2, a3, a4 as output

DDRD |= a1 | a2 | a3| a4;

//Set input & pull-up resistor

DDRD &= ~SW;

PORTD |= SW;

DDRD &= ~SW2;

PORTD |= SW2;

while(1){

if((PIND & SW) && (PIND & SW2)){

while(1){

if((!(PIND & SW2))){

while(1){

if((!(PIND & SW))){

PORTD |= a1;

PORTD &= ~a2;

PORTD &= ~a3;

PORTD &= ~a4;

*\_delay\_ms*(50);

PORTD |= a1;

PORTD &= ~a2;

PORTD &= ~ a3;

PORTD |= a4;

*\_delay\_ms*(20);

PORTD &= ~a1;

PORTD &= ~a2;

PORTD &= ~a3;

PORTD |= a4;

*\_delay\_ms*(50);

PORTD |= a1;

PORTD &= ~a2;

PORTD &= ~ a3;

PORTD |= a4;

*\_delay\_ms*(20);

PORTD |= a1;

PORTD &= ~a2;

PORTD &= ~a3;

PORTD &= ~a4;

*\_delay\_ms*(50);

break;

}

}

}

else if(!(PIND & SW)){

PORTD |= a1;

PORTD &= ~a2;

PORTD &= ~a3;

PORTD &= ~a4;

*\_delay\_ms*(50);

PORTD |= a1;

PORTD &= ~a2;

PORTD |= a3;

PORTD &= ~a4;

*\_delay\_ms*(20);

PORTD &= ~a1;

PORTD &= ~a2;

PORTD |= a3;

PORTD &= ~a4;

*\_delay\_ms*(50);

PORTD |= a1;

PORTD &= ~a2;

PORTD |= a3;

PORTD &= ~a4;

*\_delay\_ms*(20);

PORTD |= a1;

PORTD &= ~a2;

PORTD &= ~a3;

PORTD &= ~a4;

*\_delay\_ms*(50);

break;

}

}

}

}

**Stepper Motor Circuit Diagram**

**Diagram, schematic

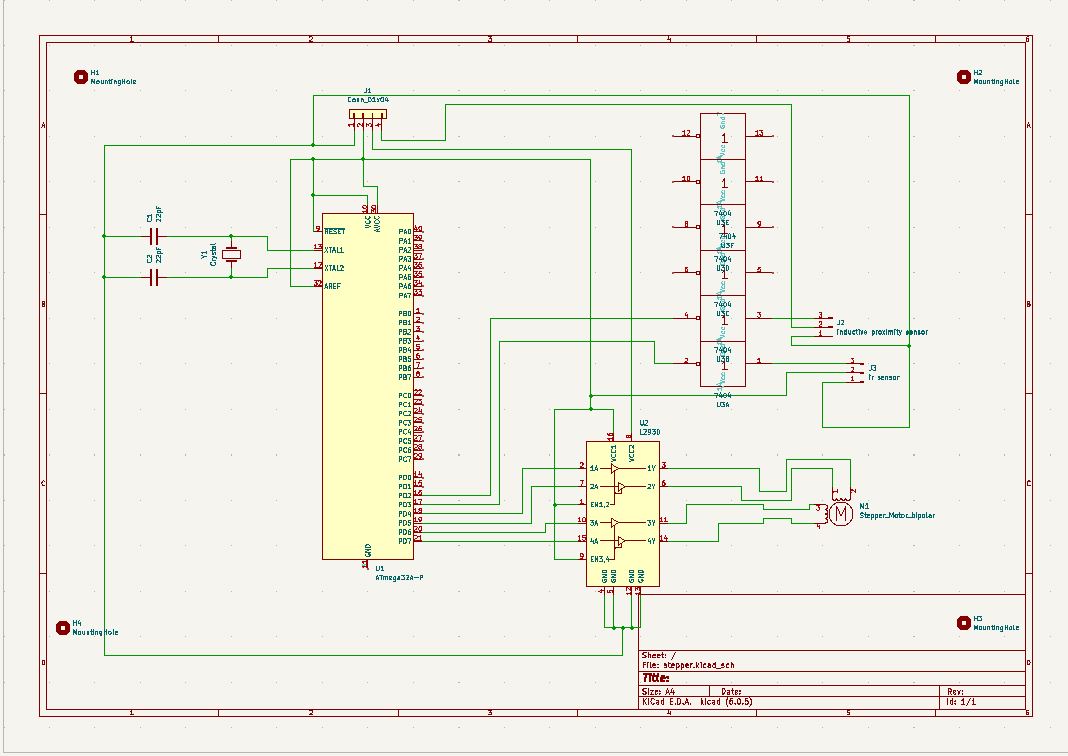
Description automatically generated**

Data sheet of Stepper motor-<https://www.omc-stepperonline.com/download/17HS15-1504S1.pdf>

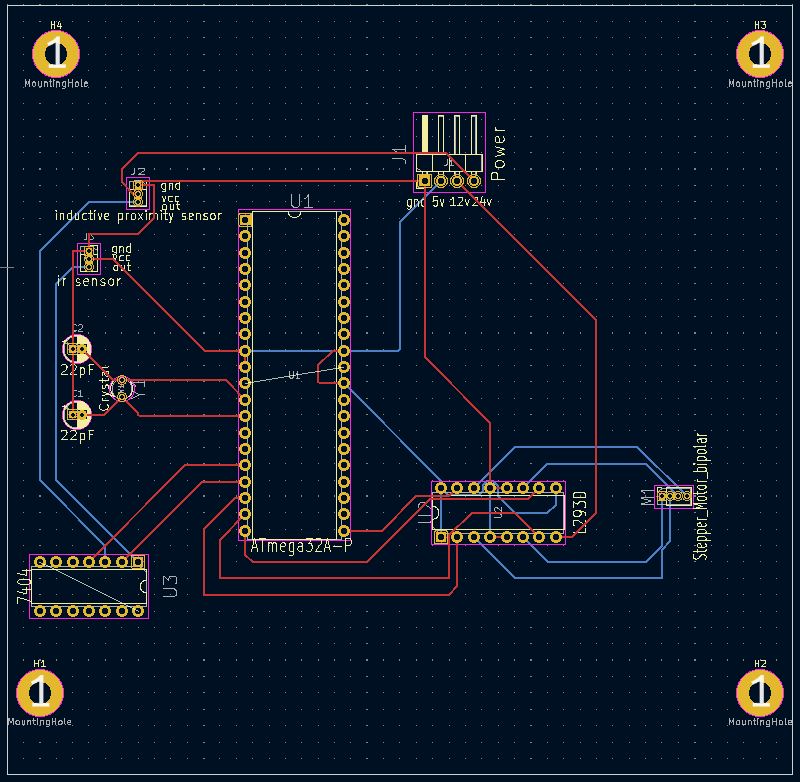
Data sheet of L293D Motor driver IC-

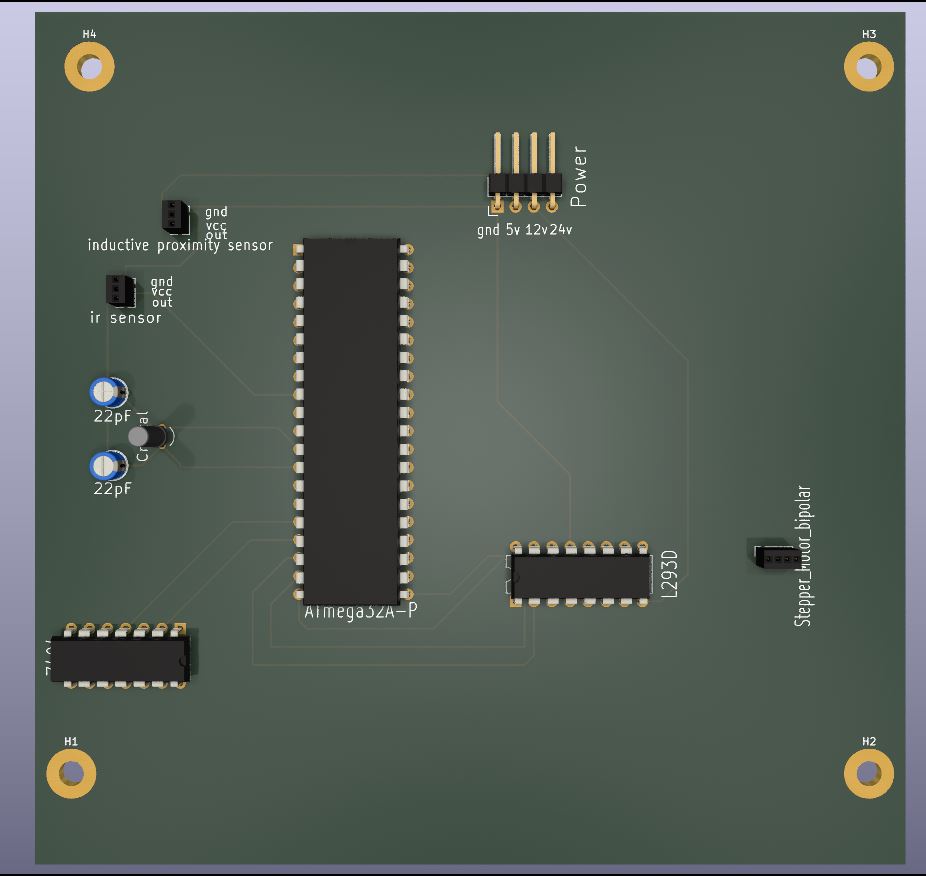
<https://components101.com/sites/default/files/component_datasheet/L293D%20Datasheet.pdf>

**Schematic editor**

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**PCB editor**

****

** 3D viewer**

**IR Sensor**

•IR obstacle sensor module has 3 wire interface with VCC , GND and an OUT pin on its tail .

•Operating voltage of the IR sensor is 3.6v to 5v and average current consumption is 0.06mA.

Diagram

Description automatically generated•IR sensor has Effective distance range of (2~30)cm

VCC : 3.3V-5V external voltage

GND: connects to the ground

OUT: connects to one of the pins that is declared as a input in the microcontroller

Function of the code

1.Detect whether discarding unit is full or not

2.Identifying the presence of the can to activate the stepper motor

**Code(Detect whether discarding unit is full or not)**

#include <avr/io.h>

#define *F\_CPU* 16000000UL

#include <avr/io.h>

#include <util/delay.h>

#define LCD PORTC

#define EN 0

#define RS 0

#define RW 1

//int check\_discard\_bin=0;

void lcdcmd(unsigned char cmd){

PORTB &=~(1<<RS); //RS=0 for command (1111 1110)

PORTB &=~(1<<RW); //RW=0 for write (1111 1101)

LCD= cmd & 0xF0; //Send upper nibble

PORTD|=(1<<EN); //EN=1 for H to L pulse

*\_delay\_ms*(1);

PORTD &= ~(1<<EN); // EN=0 for H to L pulse

LCD = cmd<<4; // send low nibble;

PORTD |=(1<<EN); //EN=0for H to L pulse

*\_delay\_ms*(1);

PORTD &= ~(1<<EN);

}

void lcd\_Print (char\*str){

int i;

for(i=0;str[i]!=0;i++) /\* Send each char of string till the NULL \*/

{

lcddata(str[i]);

}

}

void lcddata(unsigned char data){

PORTB |= (1<<RS); //RS=1 for data

PORTB &= ~(1<<RW); //RW=0 for write

LCD= data & 0xF0; //Send upper nibble

PORTD|= (1<<EN); //EN=1 for H to L pulse

*\_delay\_ms*(5);

PORTD &= ~(1<<EN); // EN=0 for H to L pulse

LCD = data<<4; // send low nibble;

PORTD |=(1<<EN); //EN=1 for H to L pulse

*\_delay\_ms*(5);

PORTD &= ~(1<<EN);

}

void lcd\_init(){

DDRC= 0xF0; // Define output LCD port

DDRD |=(1<<EN); //Define EN pin as output

DDRB=0xFF; // define RS and RW pin as output

PORTD&= ~(1<<EN); //initialize EN=0

lcdcmd(0x33);

lcdcmd(0x32);

lcdcmd(0x28); // LCD in 4 bit mode

lcdcmd(0x0E); //display on cursor on

/\*lcddata(72);

lcddata(69);

lcddata(76);

lcddata(76);

lcddata(79);\*/

lcd\_Print("WELCOME");

*\_delay\_ms*(40);

lcdcmd(0x01); //clear LCD

*\_delay\_ms*(2);

}

int ir2\_func(){

while(1){

if(PINC & 0x01){

lcdcmd(0x01); //clear LCD

lcdcmd(0x80);//set the curser to first line

lcd\_Print("Discard bin is");

lcdcmd(0xc0);//set the curser to second line

lcd\_Print("full");

lcdcmd(0x80);//set the curser to first line

*\_delay\_ms*(50);

lcdcmd(0x01); //clear LCD

lcd\_Print("Clear the");

lcdcmd(0xc0);//set the curser to second line

lcd\_Print("discard bin");

lcdcmd(0x80);//set the curser to first line

}

else{

return 0;

}

}

}

int main(void)

{

lcd\_init();

while(1){

ir2\_func();

}

}

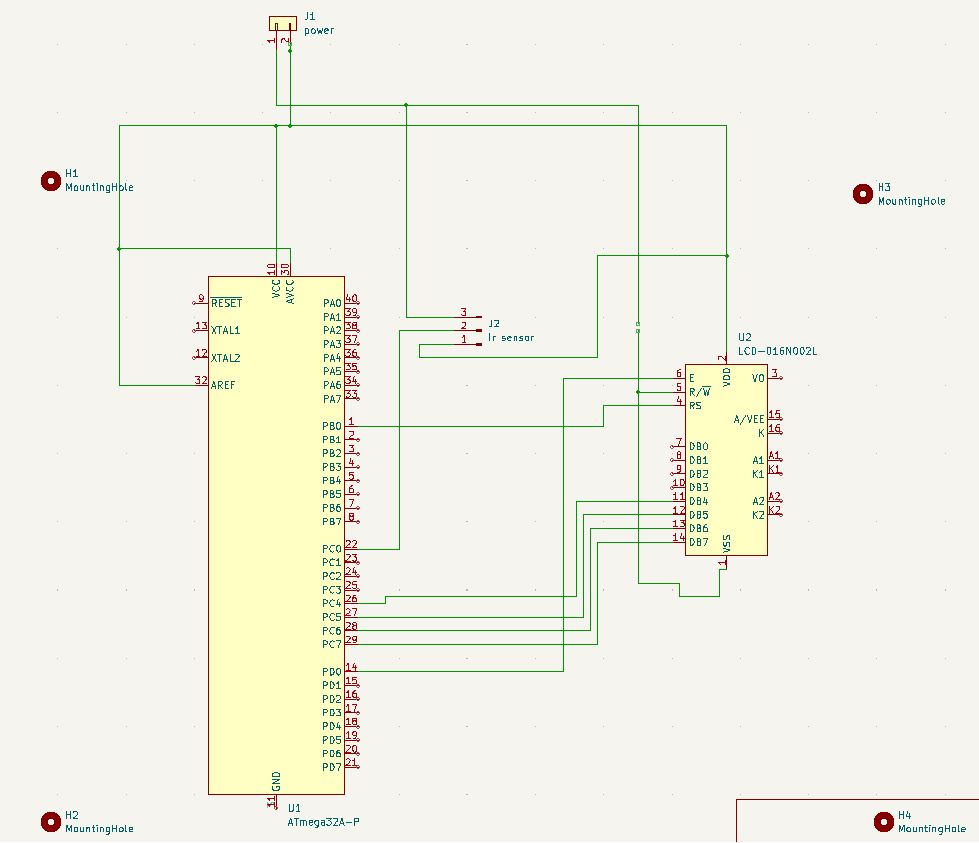
**IR Sensor Circuit Diagram**

**Diagram, schematic

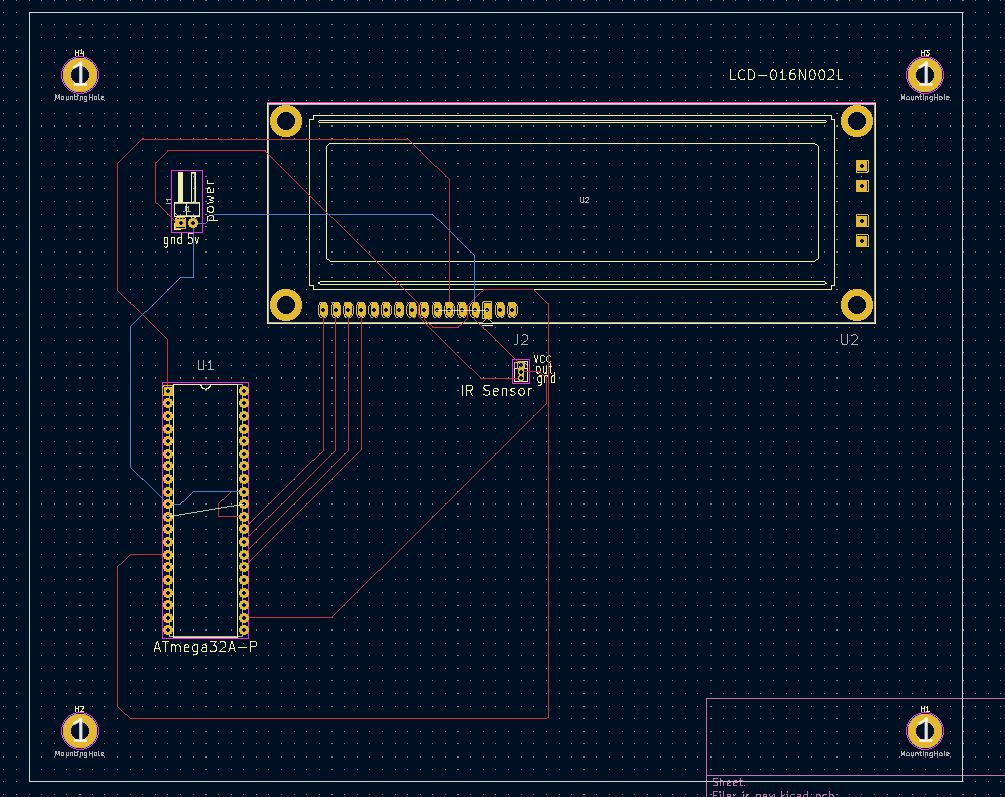
Description automatically generated**

Data sheet of IR obstacle sensor-[**file:///C:/Users/user/Downloads/arduino-ir-infrared-obstacle-avoidance-sensor-module%20(1).pdf**](file:///C:/Users/user/Downloads/arduino-ir-infrared-obstacle-avoidance-sensor-module%20(1).pdf)

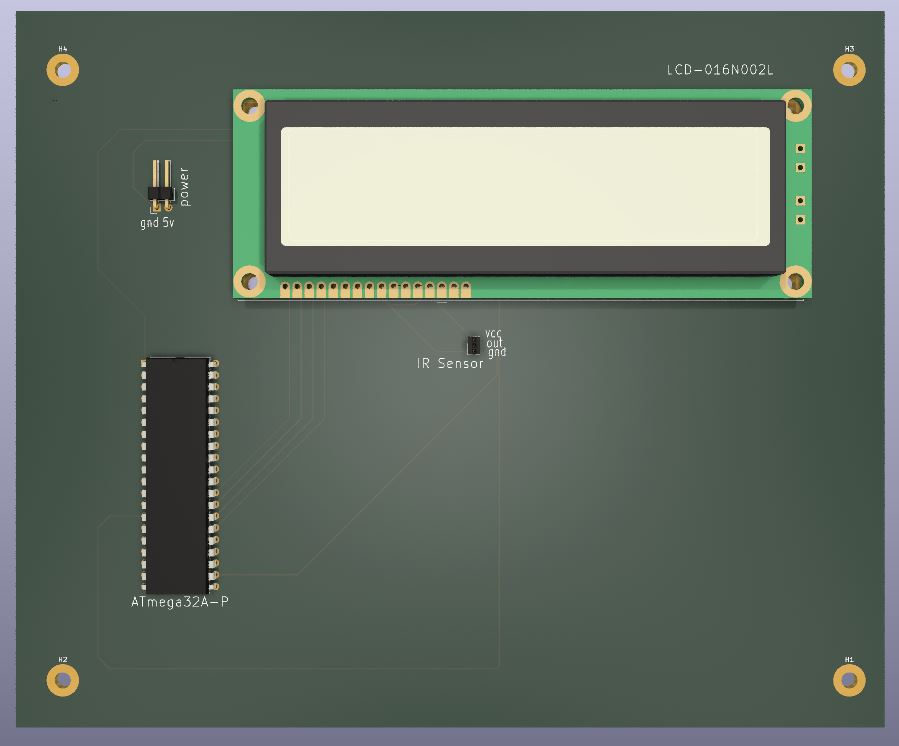
**Schematic editor**

****

**PCB editor**



**3D viewer**



**Key pad**

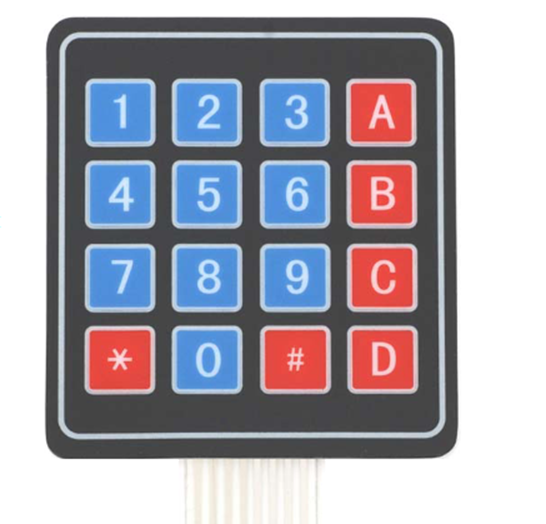
For our project we use 4x4 matrix keypad with 16 buttons .Eight pins from atmega32 microcontroller are needed to connect the 4x4 keypad

**Electrical Specification**

• 8-pin access to 4×4 matrix

• Dimensions: Keypad: 2.7 x 3.0 in (6.9 x 7.6 cm)

•Operating temp range: 32 to 122 °F



**function of the code**

1.Get the number of cans that user is going to enter.

2.After entering the cans select which reward option user wants(donate , fast charge or reload)

3.Get the phone number to process the reload option.

**code**

#define *F\_CPU* 16000000UL //freaquency of external crystal

#endif

#include <avr/io.h>

#include <util/delay.h>

//lcd and key board

#define LCD PORTC

#define EN 0

#define RS 0

#define RW 1

int get\_pn;

char can\_no[10];

unsigned char keypad();

int keypad\_func(){

unsigned char x;

char no[10];

int i=0;

int i1=0;

DDRA =0x0F; // make PA0 to PA3 = output and PA4 to PA7 = Input

lcd\_init();

while(1){

PORTA=0xF0; // make all 4 column 1 and all rows 0

if(PINA!= 0xF0){

*\_delay\_ms*(5);

x=keypad();

if (x=='\*')

{

lcdcmd(0x01);//clear lcd

lcdcmd(0x80);//set the curser to first line

lcd\_Print("1-Fast Charge");

lcdcmd(0xc0);//set the curser to second line

lcd\_Print("2-Ez Cash");

*\_delay\_ms*(100);

lcdcmd(0x01);

lcdcmd(0x80);//set the curser to first line

lcd\_Print("3-Donate");

while(1){

if(PINA!= 0xF0){

x=keypad();

//charge

if(x=='1'){

*\_delay\_ms*(5);

lcdcmd(0x80);//set the curser to first line

lcd\_Print(" ");

lcdcmd(0x01);//clear lcd

break;

}

//easy cash

else if(x=='2'){

get\_pn=1;//get phone no

*\_delay\_ms*(5);

lcdcmd(0x80);//set the curser to first line

lcd\_Print(" ");

lcdcmd(0x01);//clear lcd

lcd\_Print("Enter the Phone");

lcdcmd(0xc0);

lcd\_Print("Number");

lcdcmd(0x80);

*\_delay\_ms*(100);

lcdcmd(0x01);

lcd\_Print("Press = to");

lcdcmd(0xc0);

lcd\_Print("Finish");

lcdcmd(0x80);

*\_delay\_ms*(100);

lcdcmd(0x01);

break;

}

//donate

else if(x=='3'){

}

}

}

}

else if (x=='=')

{

get\_pn=0;

lcdcmd(0x01);

lcd\_Print("Entered phone NO.:");

lcdcmd(0xc0);

lcd\_Print(&no);//print the no

lcdcmd(0x80);

//lcd\_Print(&can\_no);//print the no

int phone\_no= *atoi*(no);//phone nimber in int

*\_delay\_ms*(100);

lcdcmd(0x01);

*\_delay\_ms*(100);

lcdcmd(0x01);

i=0;

return 0;

}

else

{

lcddata(x);

if(get\_pn==1){

no[i]=x;

i++;

}

else{

can\_no[i1]=x;

i1++;

}

}

}

}

}

void lcdcmd(unsigned char cmd){

PORTB &=~(1<<RS); //RS=0 for command (1111 1110)

PORTB &=~(1<<RW); //RW=0 for write (1111 1101)

LCD= cmd & 0xF0; //Send upper nibble

PORTD|=(1<<EN); //EN=1 for H to L pulse

*\_delay\_ms*(1);

PORTD &= ~(1<<EN); // EN=0 for H to L pulse

LCD = cmd<<4; // send low nibble;

PORTD |=(1<<EN); //EN=0for H to L pulse

*\_delay\_ms*(1);

PORTD &= ~(1<<EN);

}

void lcd\_Print (char\*str){

int i;

for(i=0;str[i]!=0;i++) /\* Send each char of string till the NULL \*/

{

lcddata(str[i]);

}

}

void lcddata(unsigned char data){

PORTB |= (1<<RS); //RS=1 for data

PORTB &= ~(1<<RW); //RW=0 for write

LCD= data & 0xF0; //Send upper nibble

PORTD|= (1<<EN); //EN=1 for H to L pulse

*\_delay\_ms*(5);

PORTD &= ~(1<<EN); // EN=0 for H to L pulse

LCD = data<<4; // send low nibble;

PORTD |=(1<<EN); //EN=1 for H to L pulse

*\_delay\_ms*(5);

PORTD &= ~(1<<EN);

}

void lcd\_init(){

//DDRC= 0xFF;

DDRC= 0xF0; // Define output LCD port(ALL c ports are outputs)

DDRD |=(1<<EN); //Define EN pin as output

DDRB=0xFF; // define RS and RW pin as output

PORTD&= ~(1<<EN); //initialize EN=0

lcdcmd(0x33);

lcdcmd(0x32);

lcdcmd(0x28); // LCD in 4 bit mode

lcdcmd(0x0E); //display on cursor on

/\*lcddata(72);

lcddata(69);

lcddata(76);

lcddata(76);

lcddata(79);\*/

lcd\_Print("WELCOME");

*\_delay\_ms*(40);

lcdcmd(0x01); //clear LCD

lcd\_Print("Enter the Number");

lcdcmd(0xc0);//set the curser to second line

lcd\_Print("of cans and");

*\_delay\_ms*(40);

lcdcmd(0x01); //clear LCD

lcdcmd(0x80);//set the curser to first line

lcd\_Print("Press + to start");

*\_delay\_ms*(40);

lcdcmd(0xc0);//set the curser to second line

lcd\_Print("the process : ");

//lcdcmd(0x80);

}

unsigned char keypad(){

PORTA=0b11111110; // make 1st row 0

if((PINA & (1<<PINA4))==0){

*\_delay\_ms*(3);

return '7';

}else if((PINA & (1<<PINA5))==0){

*\_delay\_ms*(3);

return '8';

}else if((PINA & (1<<PINA6))==0){

*\_delay\_ms*(3);

return '9';

}else if((PINA & (1<<PINA7))==0){

*\_delay\_ms*(3);

return '/';

}

PORTA=0b11111101;

if((PINA & (1<<PINA4))==0){

*\_delay\_ms*(3);

return '4';

}else if((PINA & (1<<PINA5))==0){

*\_delay\_ms*(3);

return '5';

}else if((PINA & (1<<PINA6))==0){

*\_delay\_ms*(3);

return '6';

}else if((PINA & (1<<PINA7))==0){

*\_delay\_ms*(3);

return '+';

}

PORTA=0b11111011;

if((PINA & (1<<PINA4))==0){

*\_delay\_ms*(3);

return '1';

}else if((PINA & (1<<PINA5))==0){

*\_delay\_ms*(3);

return '2';

}else if((PINA & (1<<PINA6))==0){

*\_delay\_ms*(3);

return '3';

}else if((PINA & (1<<PINA7))==0){

*\_delay\_ms*(3);

return '-';

}

PORTA=0b11110111;

if((PINA & (1<<PINA4))==0){

*\_delay\_ms*(3);

return 'C';

}else if((PINA & (1<<PINA5))==0){

*\_delay\_ms*(3);

return '0';

}else if((PINA & (1<<PINA6))==0){

*\_delay\_ms*(3);

return '=';

}else if((PINA & (1<<PINA7))==0){

*\_delay\_ms*(3);

return '\*';

}

}

int main(void){

while(1){

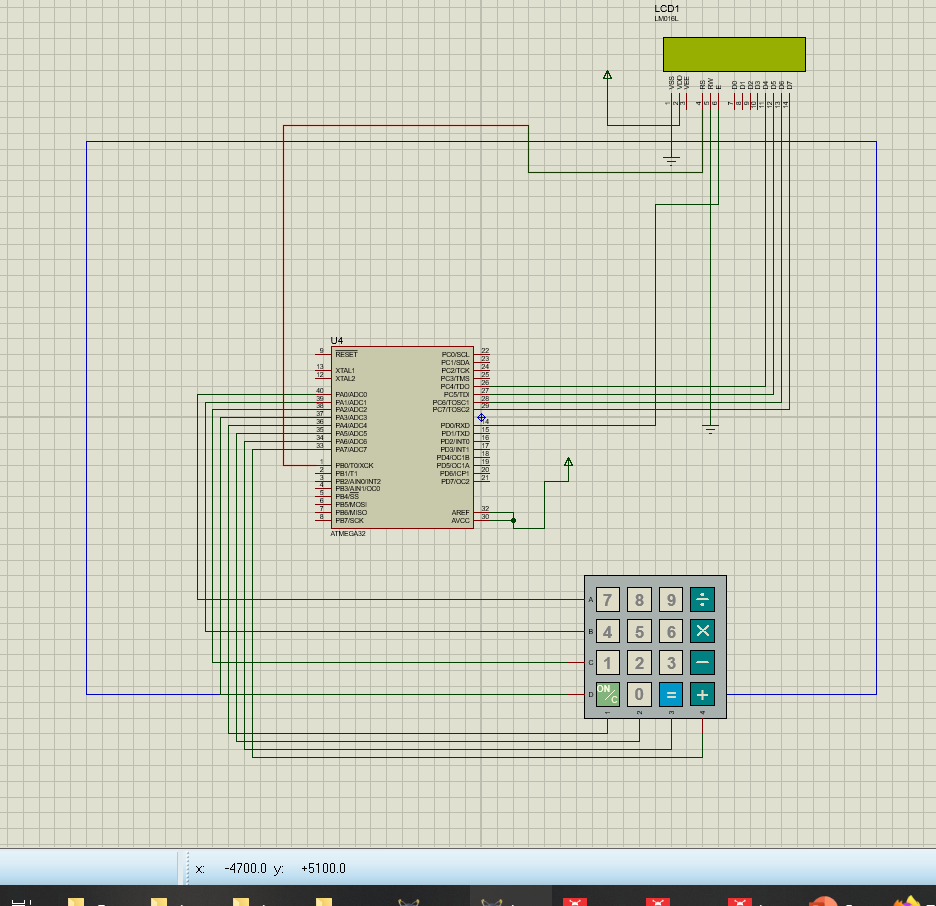
keypad\_func();

}

return 0;

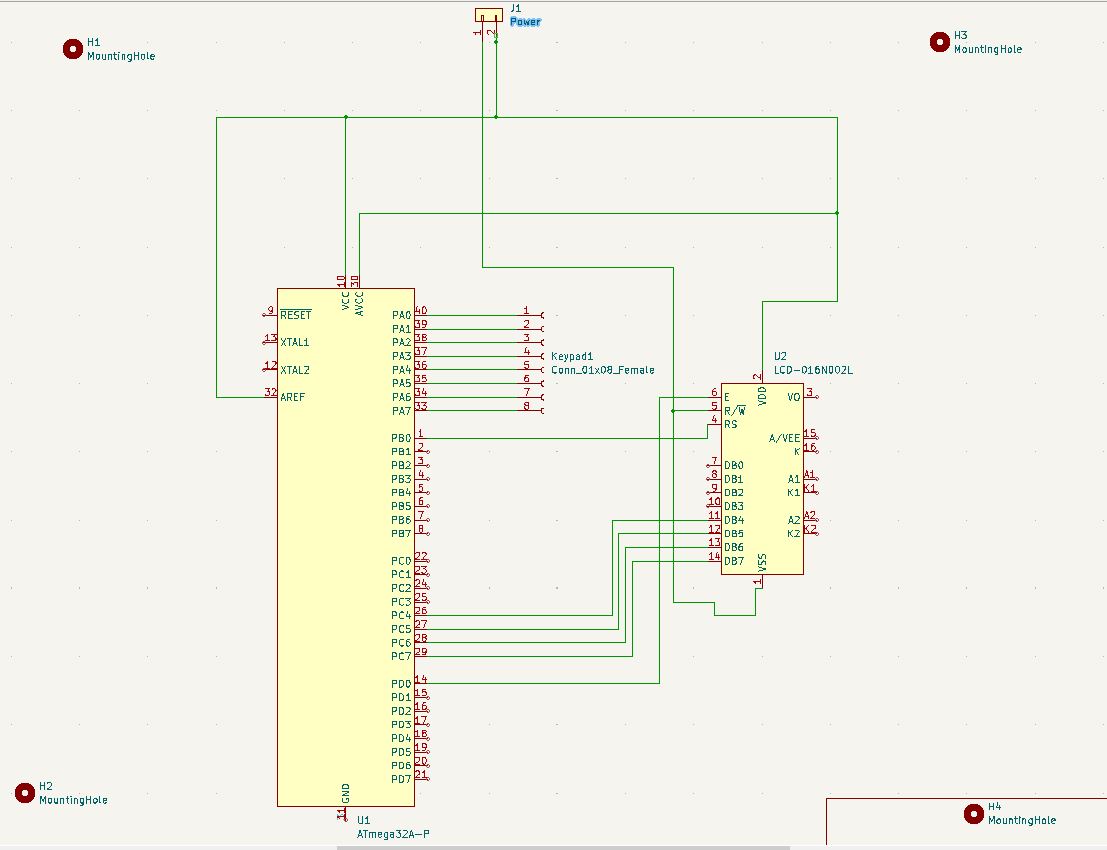
}

**Keypad Circuit Diagram**

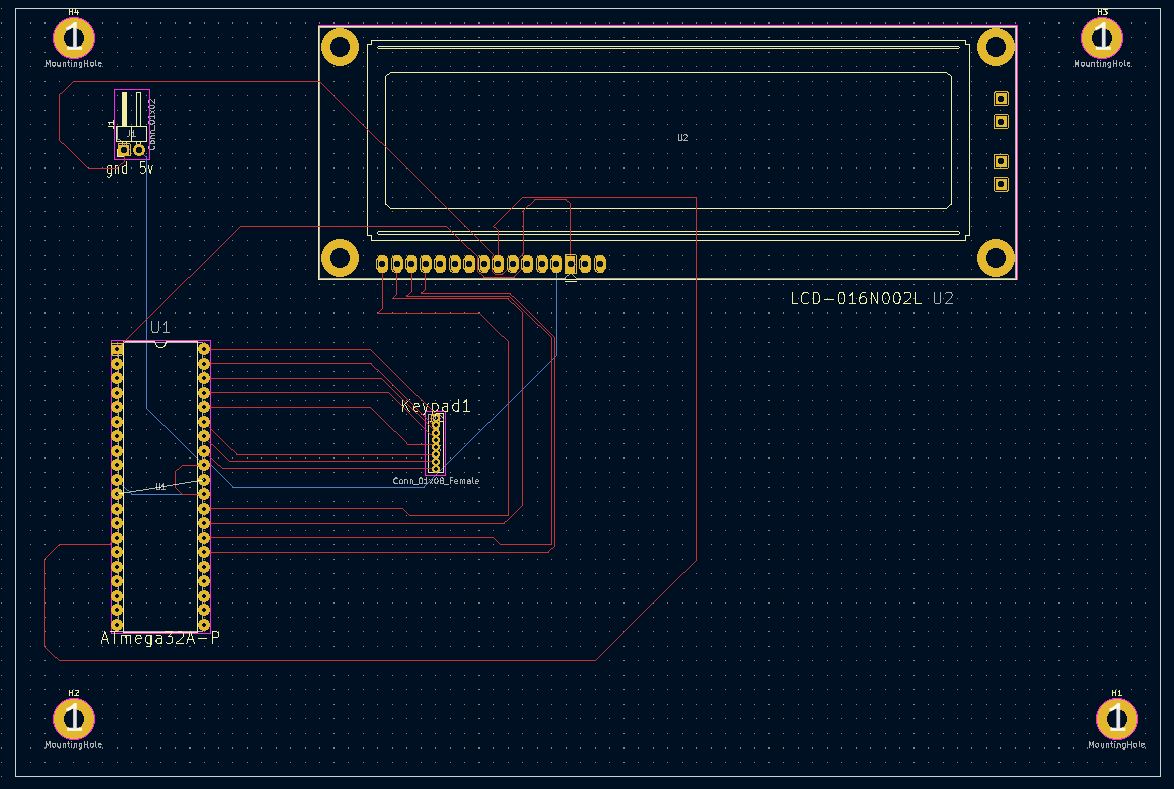


Data sheet of 4x4 keypad-<https://cdn.sparkfun.com/assets/f/f/a/5/0/DS-16038.pdf>

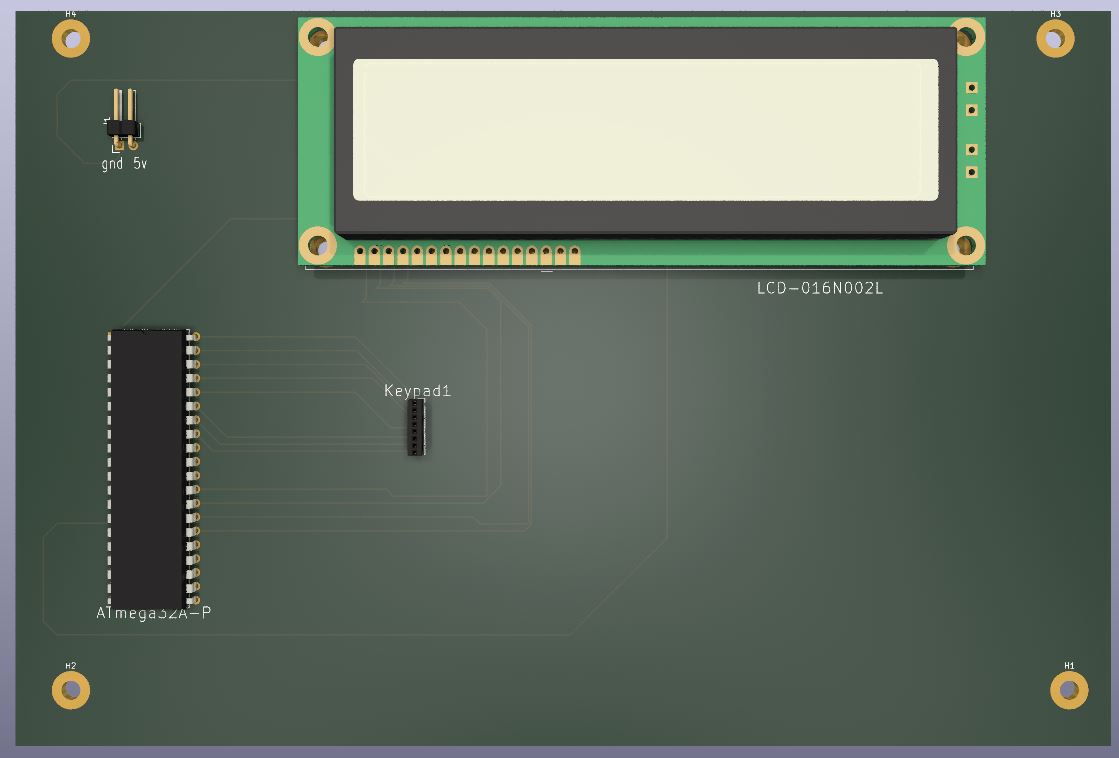
**Schematic editor**

****

**PCB editor**



**3D viewer**

****

**Code for all my components combined (code for Master atmega32)**

#ifndef F\_CPU

#define F\_CPU 16000000UL //freaquency of external crystal

#endif

#include <avr/io.h>

#include <util/delay.h>

//define interfacing pins between L293D and ATmega32

#define a1 (1<<PD4)

#define a2 (1<<PD5)

#define a3 (1<<PD6)

#define a4 (1<<PD7)

//For switch

#define SW (1<<PD3) //Ir

#define SW2 (1<<PD2) //ALL validation

//lcd and key board

#define LCD PORTC

#define EN 0

#define RS 0

#define RW 1

int get\_pn;

//int get\_cn;//number of cans

char can\_no[10];

unsigned char keypad();

int keypad\_func(){

unsigned char x;

char no[10];

int i=0;

int i1=0;

DDRA =0x0F; // make PA0 to PA3 = output and PA4 to PA7 = Input

lcd\_init();

while(1){

PORTA=0xF0; // make all 4 column 1 and all rows 0

if(PINA!= 0xF0){

*\_delay\_ms*(5);

x=keypad();

if (x=='\*')

{

lcdcmd(0x01);//clear lcd

lcdcmd(0x80);//set the curser to first line

lcd\_Print("1-Fast Charge");

lcdcmd(0xc0);//set the curser to second line

lcd\_Print("2-Ez Cash");

*\_delay\_ms*(100);

lcdcmd(0x01);

lcdcmd(0x80);//set the curser to first line

lcd\_Print("3-Donate");

while(1){

if(PINA!= 0xF0){

x=keypad();

//charge

if(x=='1'){

*\_delay\_ms*(5);

lcdcmd(0x80);//set the curser to first line

lcd\_Print(" ");

lcdcmd(0x01);//clear lcd

break;

}

//easy cash

else if(x=='2'){

get\_pn=1;//get phone no

*\_delay\_ms*(5);

lcdcmd(0x80);//set the curser to first line

lcd\_Print(" ");

lcdcmd(0x01);//clear lcd

lcd\_Print("Enter the Phone");

lcdcmd(0xc0);

lcd\_Print("Number");

lcdcmd(0x80);

*\_delay\_ms*(100);

lcdcmd(0x01);

lcd\_Print("Press = to");

lcdcmd(0xc0);

lcd\_Print("Finish");

lcdcmd(0x80);

*\_delay\_ms*(100);

lcdcmd(0x01);

break;

}

//donate

else if(x=='3'){

}

}

}

}

else if (x=='=')

{

get\_pn=0;

lcdcmd(0x01);

lcd\_Print("Entered phone NO.:");

lcdcmd(0xc0);

lcd\_Print(&no);//print the no

lcdcmd(0x80);

//lcd\_Print(&can\_no);//print the no

int phone\_no= *atoi*(no);//phone nimber in int

*\_delay\_ms*(100);

lcdcmd(0x01);

*\_delay\_ms*(100);

lcdcmd(0x01);

i=0;

return 0;

}

else

{

lcddata(x);

if(get\_pn==1){

no[i]=x;

i++;

}

else{

can\_no[i1]=x;

i1++;

}

}

}

}

}

void lcdcmd(unsigned char cmd){

PORTB &=~(1<<RS); //RS=0 for command (1111 1110)

PORTB &=~(1<<RW); //RW=0 for write (1111 1101)

LCD= cmd & 0xF0; //Send upper nibble

PORTD|=(1<<EN); //EN=1 for H to L pulse

*\_delay\_ms*(1);

PORTD &= ~(1<<EN); // EN=0 for H to L pulse

LCD = cmd<<4; // send low nibble;

PORTD |=(1<<EN); //EN=0for H to L pulse

*\_delay\_ms*(1);

PORTD &= ~(1<<EN);

}

void lcd\_Print (char\*str){

int i;

for(i=0;str[i]!=0;i++) /\* Send each char of string till the NULL \*/

{

lcddata(str[i]);

}

}

void lcddata(unsigned char data){

PORTB |= (1<<RS); //RS=1 for data

PORTB &= ~(1<<RW); //RW=0 for write

LCD= data & 0xF0; //Send upper nibble

PORTD|= (1<<EN); //EN=1 for H to L pulse

*\_delay\_ms*(2);

PORTD &= ~(1<<EN); // EN=0 for H to L pulse

LCD = data<<4; // send low nibble;

PORTD |=(1<<EN); //EN=1 for H to L pulse

*\_delay\_ms*(2);

PORTD &= ~(1<<EN);

}

void lcd\_init(){

DDRC= 0xFF;

DDRD |=(1<<EN); //Define EN pin as output

DDRB=0b11110111; //0xff define RS and RW pin as output

PORTD&= ~(1<<EN); //initialize EN=0

lcdcmd(0x33);

lcdcmd(0x32);

lcdcmd(0x28); // LCD in 4 bit mode

lcdcmd(0x0E); //display on cursor on

/\*lcddata(72);

lcddata(69);

lcddata(76);

lcddata(76);

lcddata(79);\*/

lcd\_Print("WELCOME");

*\_delay\_ms*(40);

lcdcmd(0x01); //clear LCD

lcd\_Print("Enter the Number");

lcdcmd(0xc0);//set the curser to second line

lcd\_Print("of cans and");

*\_delay\_ms*(40);

lcdcmd(0x01); //clear LCD

lcdcmd(0x80);//set the curser to first line

lcd\_Print("Press + to start");

*\_delay\_ms*(40);

lcdcmd(0xc0);//set the curser to second line

lcd\_Print("the process : ");

//lcdcmd(0x80);

}

unsigned char keypad(){

PORTA=0b11111110; // make 1st row 0

if((PINA & (1<<PINA4))==0){

*\_delay\_ms*(3);

return '7';

}else if((PINA & (1<<PINA5))==0){

*\_delay\_ms*(3);

return '8';

}else if((PINA & (1<<PINA6))==0){

*\_delay\_ms*(3);

return '9';

}else if((PINA & (1<<PINA7))==0){

*\_delay\_ms*(3);

return '/';

}

PORTA=0b11111101;

if((PINA & (1<<PINA4))==0){

*\_delay\_ms*(3);

return '4';

}else if((PINA & (1<<PINA5))==0){

*\_delay\_ms*(3);

return '5';

}else if((PINA & (1<<PINA6))==0){

*\_delay\_ms*(3);

return '6';

}else if((PINA & (1<<PINA7))==0){

*\_delay\_ms*(3);

return '+';

}

PORTA=0b11111011;

if((PINA & (1<<PINA4))==0){

*\_delay\_ms*(3);

return '1';

}else if((PINA & (1<<PINA5))==0){

*\_delay\_ms*(3);

return '2';

}else if((PINA & (1<<PINA6))==0){

*\_delay\_ms*(3);

return '3';

}else if((PINA & (1<<PINA7))==0){

*\_delay\_ms*(3);

return '-';

}

PORTA=0b11110111;

if((PINA & (1<<PINA4))==0){

*\_delay\_ms*(3);

return 'C';

}else if((PINA & (1<<PINA5))==0){

*\_delay\_ms*(3);

return '0';

}else if((PINA & (1<<PINA6))==0){

*\_delay\_ms*(3);

return '=';

}else if((PINA & (1<<PINA7))==0){

*\_delay\_ms*(3);

return '\*';

}

}

int Stepper\_motor(){

//Set a1, a2, a3, a4 as output

DDRD |= a1 | a2 | a3| a4;

//Set input & pull-up resistor

DDRD &= ~SW;

PORTD |= SW;

DDRD &= ~SW2;

PORTD |= SW2;

while(1){

if((PIND & SW) && (PIND & SW2)){

while(1){

if((!(PIND & SW2))){

while(1){

if((!(PIND & SW))){

PORTD |= a1;

PORTD &= ~a2;

PORTD &= ~a3;

PORTD &= ~a4;

*\_delay\_ms*(20);

PORTD |= a1;

PORTD &= ~a2;

PORTD &= ~ a3;

PORTD |= a4;

*\_delay\_ms*(4);

PORTD &= ~a1;

PORTD &= ~a2;

PORTD &= ~a3;

PORTD |= a4;

*\_delay\_ms*(20);

PORTD |= a1;

PORTD &= ~a2;

PORTD &= ~ a3;

PORTD |= a4;

*\_delay\_ms*(4);

PORTD |= a1;

PORTD &= ~a2;

PORTD &= ~a3;

PORTD &= ~a4;

*\_delay\_ms*(20);

return 0;

}

}

}

else if(!(PIND & SW)){

PORTD |= a1;

PORTD &= ~a2;

PORTD &= ~a3;

PORTD &= ~a4;

*\_delay\_ms*(20);

PORTD |= a1;

PORTD &= ~a2;

PORTD |= a3;

PORTD &= ~a4;

*\_delay\_ms*(4);

PORTD &= ~a1;

PORTD &= ~a2;

PORTD |= a3;

PORTD &= ~a4;

*\_delay\_ms*(20);

PORTD |= a1;

PORTD &= ~a2;

PORTD |= a3;

PORTD &= ~a4;

*\_delay\_ms*(4);

PORTD |= a1;

PORTD &= ~a2;

PORTD &= ~a3;

PORTD &= ~a4;

*\_delay\_ms*(20);

return 0;

}

}

}

}

}

int ir2\_func(){

while(1){

if(PINB & 0b00001000){

lcdcmd(0x01); //clear LCD

lcdcmd(0x80);//set the curser to first line

lcd\_Print("Discard bin is");

lcdcmd(0xc0);//set the curser to second line

lcd\_Print("full");

lcdcmd(0x80);//set the curser to first line

*\_delay\_ms*(50);

lcdcmd(0x01); //clear LCD

lcd\_Print("Clear the");

lcdcmd(0xc0);//set the curser to second line

lcd\_Print("discard bin");

lcdcmd(0x80);//set the curser to first line

}

else{

return 0;

}

}

}

int main(void){

while(1){

keypad\_func();

int can\_number= *atoi*(can\_no);

for(int k=0;k<can\_number;k++){

ir2\_func();

Stepper\_motor();

}

}

return 0;

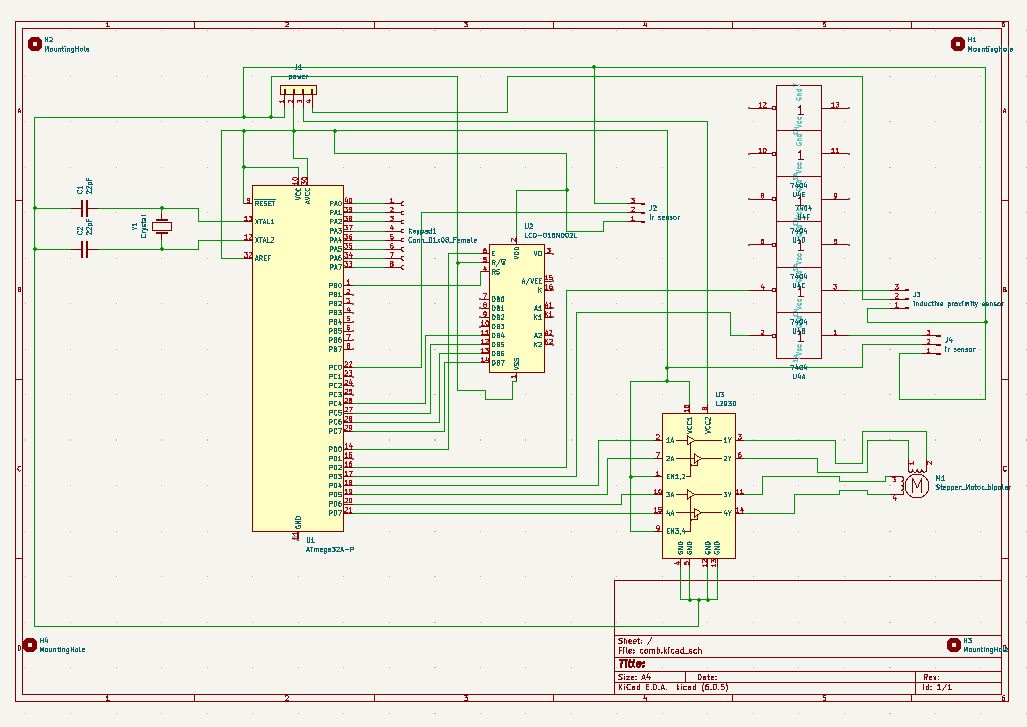
}

**Circuit diagram for all my components combined (code for Master atmega32)**

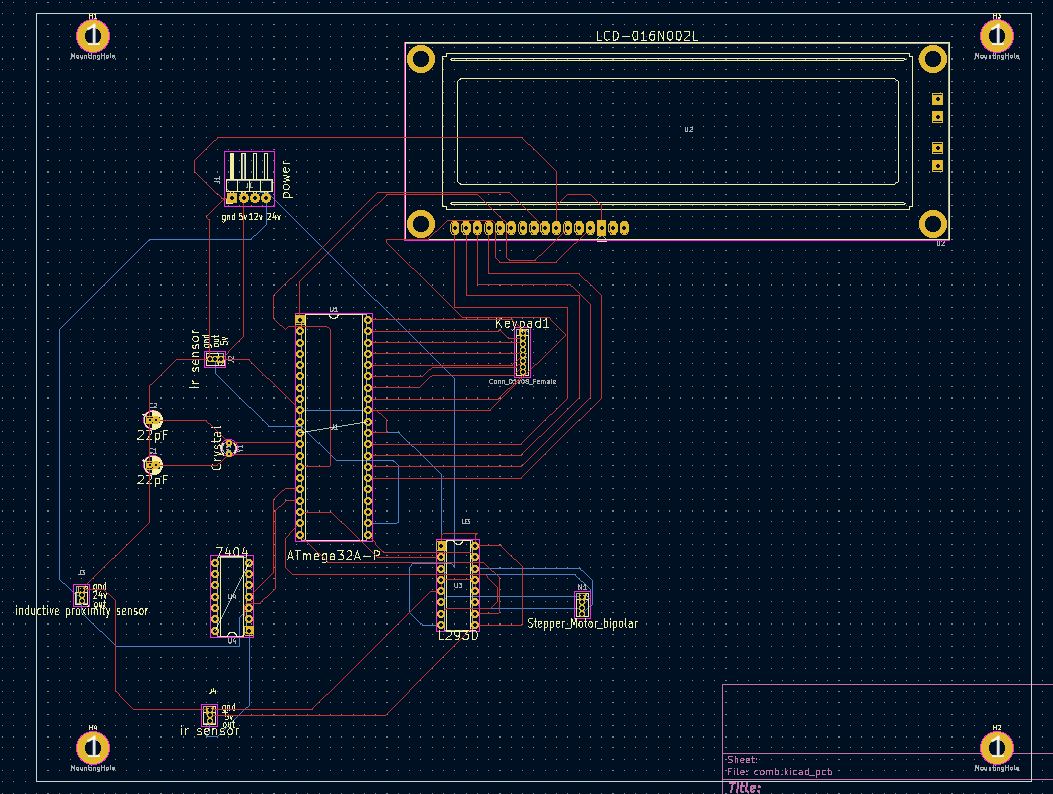
![Diagram, schematic

Description automatically generated](data:image/jpeg;base64,/9j/4AAQSkZJRgABAQEAeAB4AAD/4RDiRXhpZgAATU0AKgAAAAgABAE7AAIAAAAIAAAISodpAAQAAAABAAAIUpydAAEAAAAQAAAQyuocAAcAAAgMAAAAPgAAAAAc6gAAAAgAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAE5pc2hhdGgAAAWQAwACAAAAFAAAEKCQBAACAAAAFAAAELSSkQACAAAAAzYxAACSkgACAAAAAzYxAADqHAAHAAAIDAAACJQAAAAAHOoAAAAIAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAyMDIyOjA2OjA3IDE4OjI3OjQxADIwMjI6MDY6MDcgMTg6Mjc6NDEAAABOAGkAcwBoAGEAdABoAAAA/+ELGmh0dHA6Ly9ucy5hZG9iZS5jb20veGFwLzEuMC8APD94cGFja2V0IGJlZ2luPSfvu78nIGlkPSdXNU0wTXBDZWhpSHpyZVN6TlRjemtjOWQnPz4NCjx4OnhtcG1ldGEgeG1sbnM6eD0iYWRvYmU6bnM6bWV0YS8iPjxyZGY6UkRGIHhtbG5zOnJkZj0iaHR0cDovL3d3dy53My5vcmcvMTk5OS8wMi8yMi1yZGYtc3ludGF4LW5zIyI+PHJkZjpEZXNjcmlwdGlvbiByZGY6YWJvdXQ9InV1aWQ6ZmFmNWJkZDUtYmEzZC0xMWRhLWFkMzEtZDMzZDc1MTgyZjFiIiB4bWxuczpkYz0iaHR0cDovL3B1cmwub3JnL2RjL2VsZW1lbnRzLzEuMS8iLz48cmRmOkRlc2NyaXB0aW9uIHJkZjphYm91dD0idXVpZDpmYWY1YmRkNS1iYTNkLTExZGEtYWQzMS1kMzNkNzUxODJmMWIiIHhtbG5zOnhtcD0iaHR0cDovL25zLmFkb2JlLmNvbS94YXAvMS4wLyI+PHhtcDpDcmVhdGVEYXRlPjIwMjItMDYtMDdUMTg6Mjc6NDEuNjA2PC94bXA6Q3JlYXRlRGF0ZT48L3JkZjpEZXNjcmlwdGlvbj48cmRmOkRlc2NyaXB0aW9uIHJkZjphYm91dD0idXVpZDpmYWY1YmRkNS1iYTNkLTExZGEtYWQzMS1kMzNkNzUxODJmMWIiIHhtbG5zOmRjPSJodHRwOi8vcHVybC5vcmcvZGMvZWxlbWVudHMvMS4xLyI+PGRjOmNyZWF0b3I+PHJkZjpTZXEgeG1sbnM6cmRmPSJodHRwOi8vd3d3LnczLm9yZy8xOTk5LzAyLzIyLXJkZi1zeW50YXgtbnMjIj48cmRmOmxpPk5pc2hhdGg8L3JkZjpsaT48L3JkZjpTZXE+DQoJCQk8L2RjOmNyZWF0b3I+PC9yZGY6RGVzY3JpcHRpb24+PC9yZGY6UkRGPjwveDp4bXBtZXRhPg0KICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgIAogICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgCiAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAKICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgIAogICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgCiAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAKICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgIAogICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgCiAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAKICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgIAogICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgCiAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAKICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgIAogICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgCiAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAKICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgIAogICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgCiAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAKICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgIAogICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgICAgCiAgICAgICAgICAgICAgICAgICAgICAgICAgICA8P3hwYWNrZXQgZW5kPSd3Jz8+/9sAQwAHBQUGBQQHBgUGCAcHCAoRCwoJCQoVDxAMERgVGhkYFRgXGx4nIRsdJR0XGCIuIiUoKSssKxogLzMvKjInKisq/9sAQwEHCAgKCQoUCwsUKhwYHCoqKioqKioqKioqKioqKioqKioqKioqKioqKioqKioqKioqKioqKioqKioqKioqKioq/8AAEQgDYgZ2AwEiAAIRAQMRAf/EAB8AAAEFAQEBAQEBAAAAAAAAAAABAgMEBQYHCAkKC//EALUQAAIBAwMCBAMFBQQEAAABfQECAwAEEQUSITFBBhNRYQcicRQygZGhCCNCscEVUtHwJDNicoIJChYXGBkaJSYnKCkqNDU2Nzg5OkNERUZHSElKU1RVVldYWVpjZG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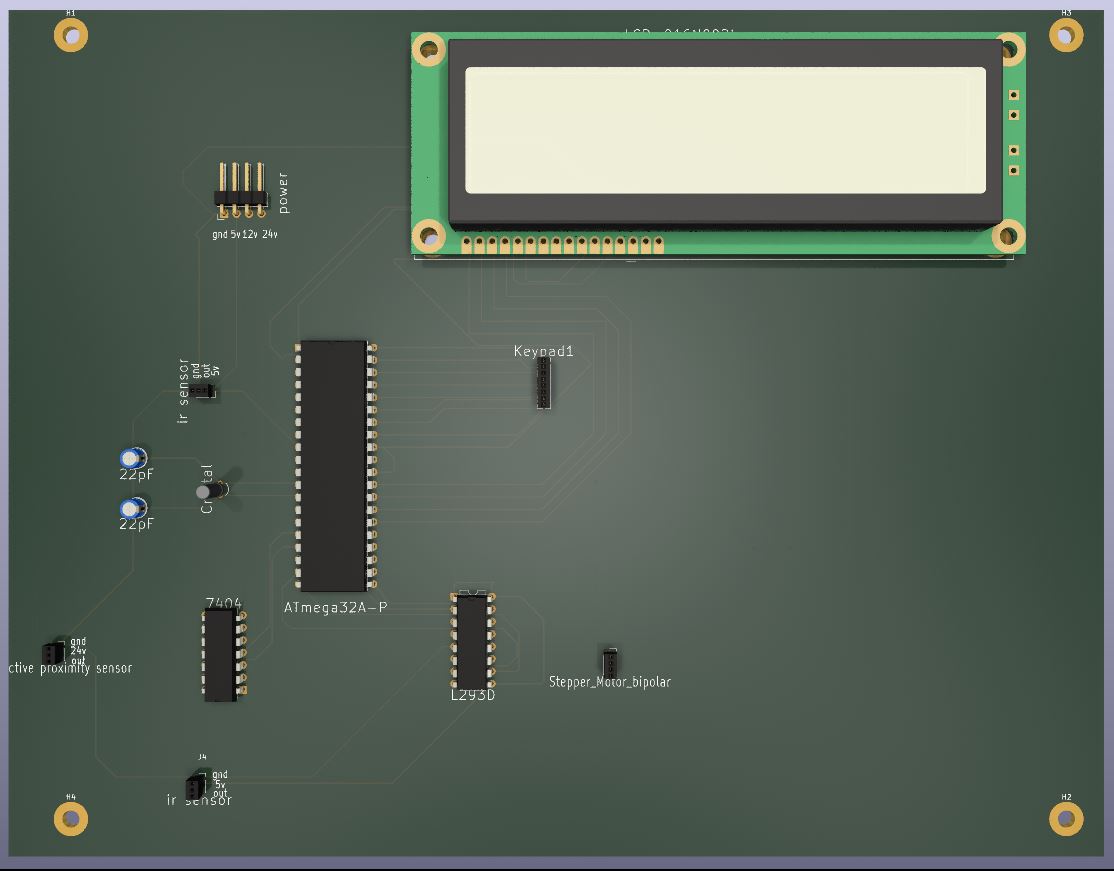
**Schematic editor**



**PCB editor**

****

**3D viewer**



**3.Student name-: Basnayake S.B. – 204020V**

**Servo motor (SG90)**

Servo Motor is used to rotate the can in order to detect whether the can is valid or not. The shape of the object is detected with the combination of Ultrasonic sensors and the rotation of the servo motor. When the microcontroller signals some type of object have been detected I programmed the servo motor to rotate 180 degrees.

Servo motors are used to perform precise rotations.

Servo motors usually have a rotation angle that varies between 0 and 180 degrees. The rotation angle of the servo motor is controlled by applying a PWM signal to it.

Usually there are 3 pins in a servo.

Diagram

Description automatically generated

VCC (Red) – connects +VCC supply to the pin.

GROUND (Brown) – connects to the ground.

Control Signal (Orange) – connects PWM of 20ms(50Hz) period to this pin.

**Power requirement**

SG90 servo motor requires a voltage supply of 4.8V (~5V). And it can handle a maximum voltage of 6V and a maximum current of 250mA

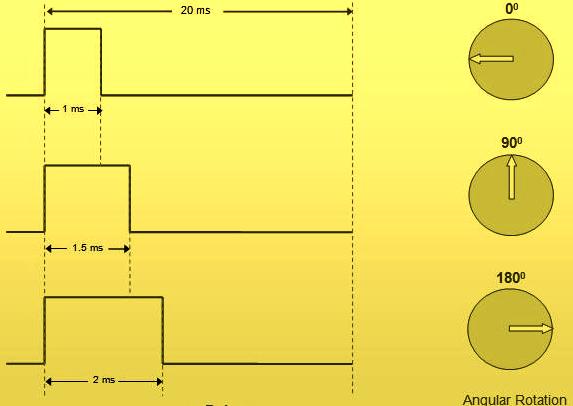
**Other Specifications**

* Torque :2.5kg/cm
* Operating speed :0.1s/60
* Rotation : 0-180 degrees
* Weight : 9g

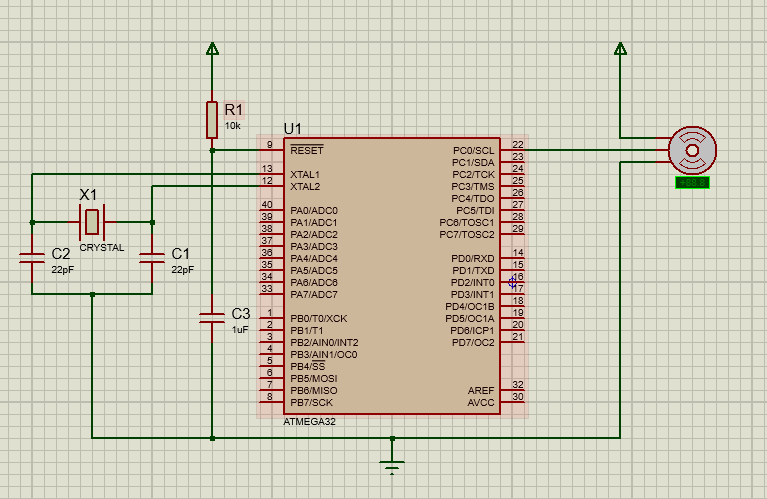
Diagram

Description automatically generated

The user can changed the rotation angle of the servo motor by changing the pulse width of the PWM signal. The below image shows the approximate duty cycle and it’s related rotation of the shaft.



**Circuit Diagram for the Servo Motor**



**Schematic Diagram**

**Diagram, schematic

Description automatically generated**

**PCB Design**

**Diagram, schematic

Description automatically generated**

**Graphical user interface

Description automatically generated**

**Servo motor code**

#ifndef *F\_CPU*

#define *F\_CPU* 16000000UL

#endif

#include <avr/io.h>

#include <util/delay.h>

void servo()

{

DDRC = 0x01; //Makes PC0 output pin

PORTC = 0x00;

for (int i=0;i<4;i++)

{

//Rotate Motor to 0 degree

PORTC = 0x01;

*\_delay\_us*(1000);

PORTC = 0x00;

*\_delay\_ms*(1000);

//Rotate Motor to 90 degree

PORTC = 0x01;

*\_delay\_us*(1500);

PORTC = 0x00;

*\_delay\_ms*(1000);

//Rotate Motor to 180 degree

PORTC = 0x01;

*\_delay\_us*(2000);

PORTC = 0x00;

*\_delay\_ms*(1000);

}

}

int main(void)

{

servo();

}

[SG90 datasheet](http://www.ee.ic.ac.uk/pcheung/teaching/DE1_EE/stores/sg90_datasheet.pdf)- <http://www.ee.ic.ac.uk/pcheung/teaching/DE1_EE/stores/sg90_datasheet.pdf>

**GSM module (SIM900A)**

* There are many GSM modules are in the market
  + - Ex: - SIM900, SIM700, SIM800, SIM808, SIM5320
* SIM 900A can work with any GSM Network Operator.
* But in order to connect to a cellular network the modem requires a SIM card provided by a network provider.
* SIM 900A is a plug and play modem with RS232 serial communication support.

**Power Requirement**

* SIM900A requires an external supply of ~5V and can draw up to ~2A at its peak. And the minimum current requirement is 1A.

**Indicators**

* It has two LED indicators as,

**ON** – It indicates that the module is powered and switched on.

**Network LED** – When module is powered up, network LED blink every second and after registration it will start to blink after every 3 seconds. And this shows that the modem is registered with the network.

GSM Module is used for the rewarding process. I programmed the GSM module to

1. Give money according to the value of the cans
2. Donate entire money to the Little Hearts Foundation

The user has to choose between these 3 options including a fast charging option.

If the user selects the option to get the money he/she have to enter a mobile phone number. And according to the phone number entered he/she will receive the money using the **ezCash** method.

**Picture of the GSM module and all pins**

AT commands are used to work with supported features of SIM 900A.

After sending the command a respond will be send by the GSM module. And every time user will receive the response in the form of

**<CL><LF>response<CR><LF>**

Diagram, schematic

Description automatically generated

Given below are the AT commands used when building our project.(<CR><LF> are removed intentionally.

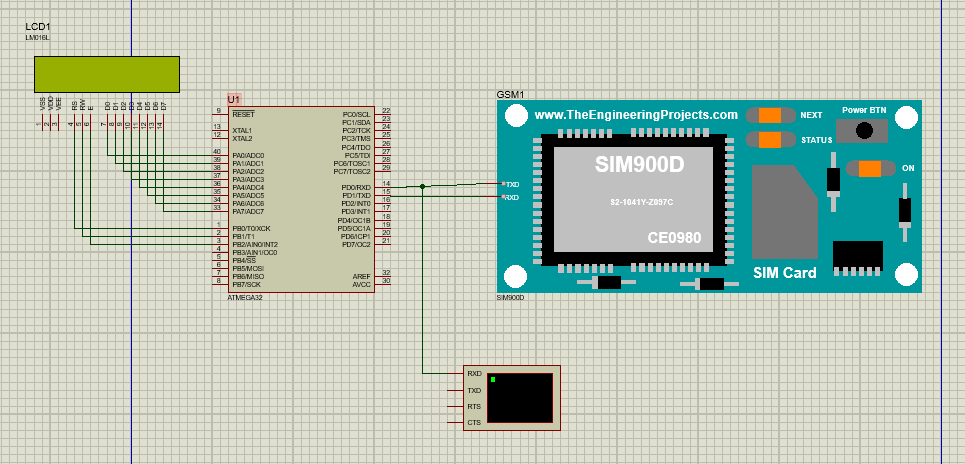
|  |  |  |
| --- | --- | --- |
| **Command** | **Function** | **Expected Response** |
| ATE0 | Set echo mode | OK |
| AT+CMGF=<index>  Index - 0: PDU  1: Text | Select message format | OK |
| AT+CMGS=”Mobile Number” | Send message | > ”Type message here”  Press ‘Ctrl+z’ to end message or ‘ESC’ to exit without sending  OK |
| ATD**MobileNumber**; | Calling | OK |

The GSM module uses USART communication to communicate with a microcontroller.

TXD 5V pin of the GSM module connects to the pin 14(RXD) of the ATMega 32.

RXD 5V pin of the GSM module connects to the pin 15(TXD) of the ATMega 32.

**Circuit Diagram for the GSM**



**Schematic Diagram**

**Diagram, schematic

Description automatically generated**

**A screenshot of a computer

Description automatically generated with medium confidence** **PCB Design**

Graphical user interface

Description automatically generated

**Code**

USART\_Interrupt c file

include "USART\_Interrupt.h"

void USART\_Init(unsigned long BAUDRATE) /\* USART initialize function \*/

{

UCSRB |= (1 << RXEN) | (1 << TXEN) | (1 << RXCIE); /\* Enable USART transmitter and receiver \*/

UCSRC |= (1 << URSEL)| (1 << UCSZ0) | (1 << UCSZ1); /\* Write USCRC for 8 bit data and 1 stop bit \*/

UBRRL = BAUD\_PRESCALE; /\* Load UBRRL with lower 8 bit of prescale value \*/

UBRRH = (BAUD\_PRESCALE >> 8); /\* Load UBRRH with upper 8 bit of prescale value \*/

}

char USART\_RxChar() /\* Data receiving function \*/

{

while (!(UCSRA & (1 << RXC))); /\* Wait until new data receive \*/

return(UDR); /\* Get and return received data \*/

}

void USART\_TxChar(char data) /\* Data transmitting function \*/

{

UDR = data; /\* Write data to be transmitting in UDR \*/

while (!(UCSRA & (1<<UDRE))); /\* Wait until data transmit and buffer get empty \*/

}

void USART\_SendString(char \*str) /\* Send string of USART data function \*/

{

int i=0;

while (str[i]!=0)

{

USART\_TxChar(str[i]); /\* Send each char of string till the NULL \*/

i++;

}

}

USART\_INTERRUPT file

#ifndef USART\_INTERRUPT\_H\_

#define USART\_INTERRUPT\_H\_

#define F\_CPU 1000000UL

#include <avr/io.h> /\* Include AVR std. library file \*/

#include <avr/interrupt.h>

#include "USART\_Interrupt.h"

#define BAUD\_PRESCALE (((F\_CPU / (BAUDRATE \* 2UL))) - 1) /\* Define prescale value \*/

void USART\_Init(unsigned long); /\* USART initialize function \*/

char USART\_RxChar(); /\* Data receiving function \*/

void USART\_TxChar(char); /\* Data transmitting function \*/

void USART\_SendString(char\*); /\* Send string of USART data function \*/

#endif /\* USART\_INTERRUPT\_H\_ \*/

Lcd.c file

#include <stdio.h>

#include <math.h>

#include <avr/io.h>

#define lcdport PORTA

#define \_signal PORTB

#define en PB2

#define rw PB1

#define rs PB0

#define LCD\_Data\_Dir DDRA /\* Define LCD data port direction \*/

#define LCD\_Command\_Dir DDRB /\* Define LCD command port direction register \*/

#define LCD\_Data\_Port PORTA /\* Define LCD data port \*/

#define LCD\_Command\_Port PORTB

#define EN PB2 /\* Define Enable signal pin \*/

#define RW PB1 /\* Define Read/Write signal pin \*/

#define RS PB0

char key;

void lcdcmd(unsigned char cmd);//lcd commands

void lcdint();//initialize lcd

void lcddata(unsigned char data);

void lcd\_string(const unsigned char \*str, unsigned char length);//display in lcd

int charToInt(char c);//character to integer

int displayKey();//save input

void lcd\_clear();//lcd clear

void lcd\_line\_one();//lcd line one

void lcd\_line\_two();//lcd line two

void lcdint()

{

lcdcmd(0x38);

\_delay\_ms(1);

lcdcmd(0x01);

\_delay\_ms(1);

lcdcmd(0x0E);

\_delay\_ms(1);

}

void lcdcmd(unsigned char x)

{

lcdport=x;

\_signal=(0<<rs)|(0<<rw)|(1<<en);

\_delay\_ms(1);

\_signal=(0<<rs)|(0<<rw)|(0<<en);

\_delay\_ms(10); /\* original-50 \*/

}

void lcddata(unsigned char data)

{

lcdport= data;

\_signal= (1<<rs)|(0<<rw)|(1<<en);

\_delay\_ms(1);

\_signal= (1<<rs)|(0<<rw)|(0<<en);

\_delay\_ms(10); /\* original-50 \*/

}

void lcd\_string(const unsigned char \*str, unsigned char length)

{

for(int i=0; i<length; i++)

{

lcddata(str[i]);

}

}

int charToInt(char c){

int num = 0;

num = c - '0';

return num;

}

void lcd\_clear()

{

lcdcmd(0x01);

}

void lcd\_line\_one()

{

lcdcmd(0x80);

}

void lcd\_line\_two()

{

lcdcmd(0xC0);

}

void LCD\_Char (char char\_data) /\* LCD data write function \*/

{

LCD\_Data\_Port = char\_data; /\* Write data to LCD data port \*/

LCD\_Command\_Port &= ~(1<<RW); /\* Make RW LOW (Write) \*/

LCD\_Command\_Port |= (1<<EN)|(1<<RS); /\* Make RS HIGH (data reg.) and High to Low transition on EN (Enable) \*/

\_delay\_us(1);

LCD\_Command\_Port &= ~(1<<EN);

\_delay\_ms(1); /\* Wait little bit \*/

}

Main.c file

#define F\_CPU 16000000UL /\* define Clock Frequency \*/

#include <avr/io.h>

#include <avr/interrupt.h>

#include <stdio.h>

#include <string.h>

#include <stdlib.h>

#include <stdbool.h>

#include <util/delay.h>

#include "lcd.c" /\* include 16x2 LCD Header file \*/

#include "USART\_Interrupt.c" /\* include USART Header file \*/

#define SREG \_SFR\_IO8(0x3F)

void GSM\_Begin();

void GSM\_Dialling();

void GSM\_Response();

void GSM\_Response\_Display();

void GSM\_Send\_Msg(char\* ,char\*);

char buff[160]; /\* buffer to store responses and messages \*/

char status\_flag = 0; /\* for checking any new message \*/

volatile int buffer\_pointer;

int price=2; /\*price given to a single can\*/

int cans; /\* amount of cans inserted by the user \*/

int amount; /\* total value user will receive \*/

char mob\_no[11]="0775499920"; /\*user's phone number \*/

int main(void)

{

char lh[10];

DDRA=0xff;

DDRB=0x07;

buffer\_pointer = 0;

lcdint();

USART\_Init(9600); /\* initialize USART communication \*/

sei();

lcd\_line\_one();

lcd\_string("GSM Initializing",16);

\_delay\_ms(90); //original-3000

lcd\_clear();

lcd\_line\_one();

lcd\_string("AT",2);

GSM\_Begin(); /\* check GSM responses and initialize GSM \*/

lcd\_clear();

//amount=cans\*price;

amount=1000;

sprintf(lh,"LH %d",amount);

GSM\_Send\_Msg("77110",lh);

memset(lh,0,strlen(lh)); /\* clear lh array \*/

lcd\_string(".....Sending....",16); /\* lcd print function \*/

\_delay\_ms(70); //original-7000

lcd\_clear(); /\* function to clear lcd \*/

lcd\_string("Sent to Little",14);

\_delay\_ms(30); // //original-500

lcd\_clear();

lcd\_string("Hearts",6);

\_delay\_ms(30); //original-500

lcd\_clear();

GSM\_Dialling();

lcd\_string("Reload send",11);

}

void GSM\_Begin()

{

while(1)

{

lcdcmd(0xc0);

USART\_SendString("ATE0\r"); /\* send ATE0 to check module is ready or not \*/

\_delay\_ms(30); //original-500

if(strstr(buff,"OK"))

{

GSM\_Response(); /\* get Response \*/

memset(buff,0,160);

break;

}

else

{

lcd\_line\_one();

lcd\_string("Error",5);

}

}

\_delay\_ms(50); // original-1000

lcd\_clear();

lcd\_line\_one();

lcd\_string("Text Mode",9);

lcdcmd(0xc0);

USART\_SendString("AT+CMGF=1\r");/\* select message format as text \*/

GSM\_Response();

\_delay\_ms(40); // original-1000

}

/\* ISR routine to save responses/new message \*/

ISR(USART\_RXC\_vect)

{

buff[buffer\_pointer] = UDR; /\* copy UDR(received value) to buffer \*/

buffer\_pointer++;

status\_flag = 1; /\* flag for new message arrival \*/

}

void GSM\_Send\_Msg(char\* num,char \*sms)

{

char sms\_buffer[35];

buffer\_pointer=0;

sprintf(sms\_buffer,"AT+CMGS=\"%s\"\r",num);

USART\_SendString(sms\_buffer); /\*send command AT+CMGS="Mobile No."\r \*/

\_delay\_ms(20); // original-200

while(1)

{

if(buff[buffer\_pointer]==0x3e) /\* wait for '>' character\*/

{

buffer\_pointer = 0;

memset(buff,0,strlen(buff)); /\* emptying "buff" \*/

USART\_SendString(sms); /\* send msg to 77110 \*/

USART\_TxChar(0x1a); /\* send Ctrl+Z then only message will transmit\*/

break;

}

buffer\_pointer++;

}

\_delay\_ms(30); // original-300

buffer\_pointer = 0;

memset(buff,0,strlen(buff)); /\* emptying "buff" \*/

memset(sms\_buffer,0,strlen(sms\_buffer)); /\* emptying "sms\_buffer" \*/

}

void GSM\_Dialling()

{

char call[35];

sprintf(call,"ATD#111#2#%s#%d#1234#;\r",mob\_no,amount); /\* build command \*/

USART\_SendString(call); /\* send command ATD<Dial\_code> \*/

}

void GSM\_Response()

{

unsigned int timeout=0;

int CRLF\_Found=0; /\* character elements found CL & LF \*/

char CRLF\_buff[2]; /\* store the CL & LF) \*/

int Response\_Length=0;

while(1)

{

if(timeout>=60000) /\*if timeout occur then return \*/

return;

Response\_Length = strlen(buff); /\* getting the length of the response \*/

if(Response\_Length) /\* checking the availability of the response \*/

{

\_delay\_ms(2);

timeout++;

if(Response\_Length==strlen(buff))

{

for(int i=0;i<Response\_Length;i++)

{

memmove(CRLF\_buff,CRLF\_buff+1,1); /\* changing the memory location of the response \*/

CRLF\_buff[1]=buff[i];

if(strncmp(CRLF\_buff,"\r\n",2))

{

if(CRLF\_Found++==2) /\* search for \r\n in string \*/

{

GSM\_Response\_Display(); /\* display response \*/

return;

}

}

}

CRLF\_Found = 0;

}

}

\_delay\_ms(1);

timeout++;

}

status\_flag=0;

}

void GSM\_Response\_Display()

{

buffer\_pointer = 0;

int lcd\_pointer = 0;

while(1)

{

if(buff[buffer\_pointer]== '\r' || buff[buffer\_pointer]== '\n') /\*search for \r\n in string \*/

{

buffer\_pointer++;

}

else

break;

}

lcdcmd(0xc0);

while(buff[buffer\_pointer]!='\r') /\* display response till "\r" \*/

{

LCD\_Char(buff[buffer\_pointer]);

buffer\_pointer++;

lcd\_pointer++;

if(lcd\_pointer==15) /\* check for end of LCD line \*/

lcdcmd(0x80);

}

buffer\_pointer=0;

memset(buff,0,strlen(buff)); /\* emptying memory block \*/

}

GSM command manual - <https://www.espruino.com/datasheets/SIM900_AT.pdf>

GSM datasheet - https://researchdesignlab.com/projects/GPRSGSM%20SIM900A%20MODEM.pdf

ATMEGA 32 Full Data sheet - <https://ww1.microchip.com/downloads/en/DeviceDoc/doc2503.pdf>

ATMEGA 32 Summery Data sheet - <https://ww1.microchip.com/downloads/en/DeviceDoc/2503S.pdf>

**4.Name of Student: Sanchitha S.P.Y.P. - 204186H**

**Load Cell**

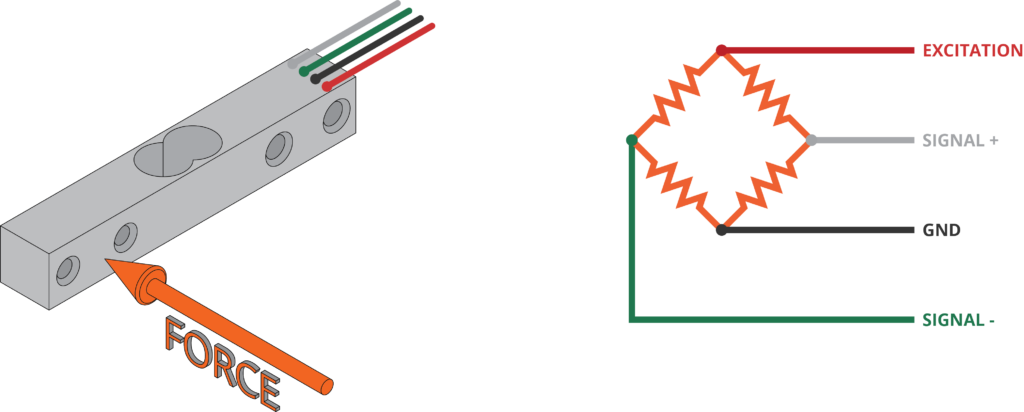
First, I choose the Strain Gauge load cells as the most suitable load cell type for this project. The reason is these type load cells are high accuracy, Cost-effective and very sturdy. As the load cell amplifier, I choose HX711 amplifier.

Strain Gauge Load Cell

Load cell is a device which use to measure weight. Main part of the load cell is Strain Gauge.

Strain Gauge is a device which used to measure strain of an object. The resistance of a strain gauge changes when force is applied and this change will give a different electrical output.

So in the load cell, there are 4 strain gauges connected like a Wheatstone Bridge. When the bridge is in balanced position there is no voltage difference, but when bridge is not balanced there is voltage difference. By using this method, we can find the weight of an object.



Specifications -:

Housing Material - Aluminum Alloy

Load Cell Type Strain Gauge Capacity - 20g

Cable - no. of leads - 4

Excitation Voltage - 5 VDC

Operating Temperature Range - -10 to ~+40°C

Safe Overload - 120% Capacity Ultimate Overload - 150% Capacity

**HX-711 load cell amplifier**

HX711 is a precision 24-bit analog- to-digital converter (ADC) designed for weigh scales and industrial control applications to interface directly with a bridge sensor

Specifications -:

Operating voltage (v) - 2.7V to 10VDC

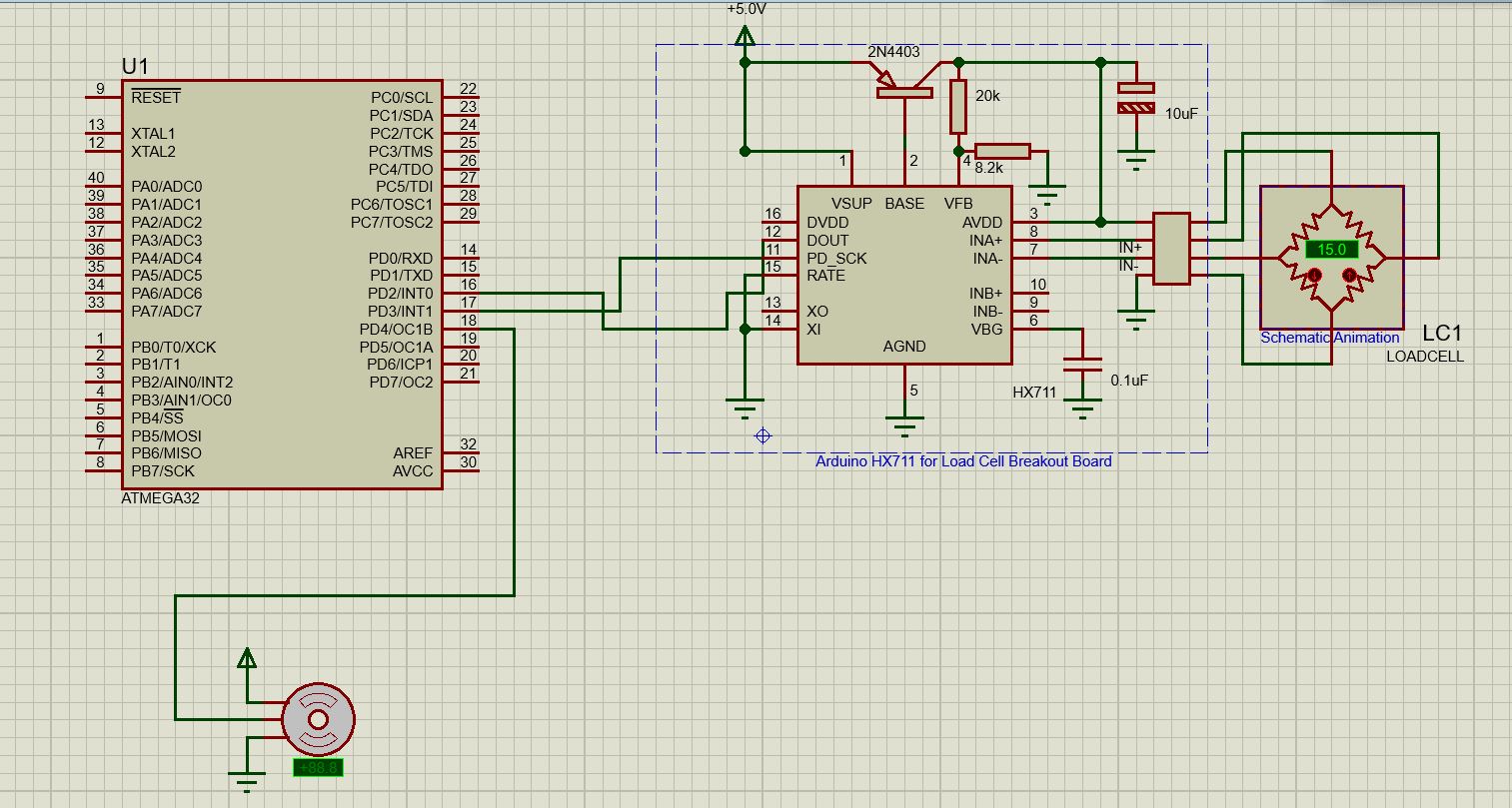
Operating Current - <10 mA

Data Accuracy - 24 bit

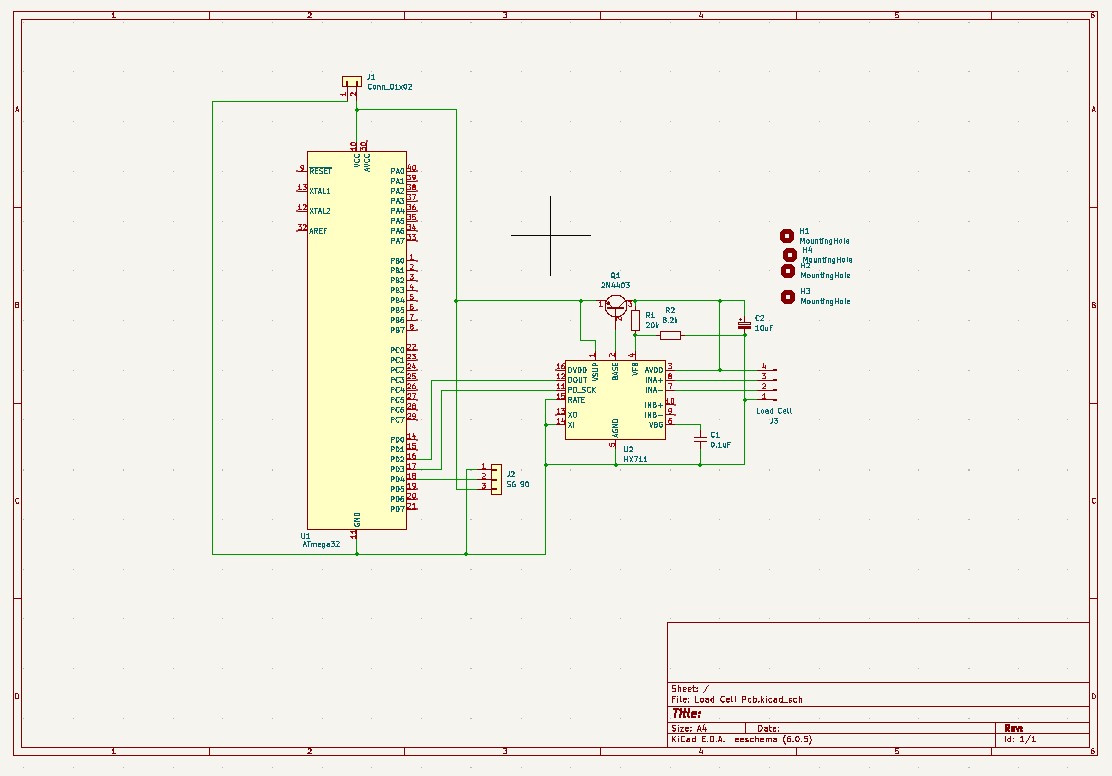
A picture containing text, electronics, circuit

Description automatically generated

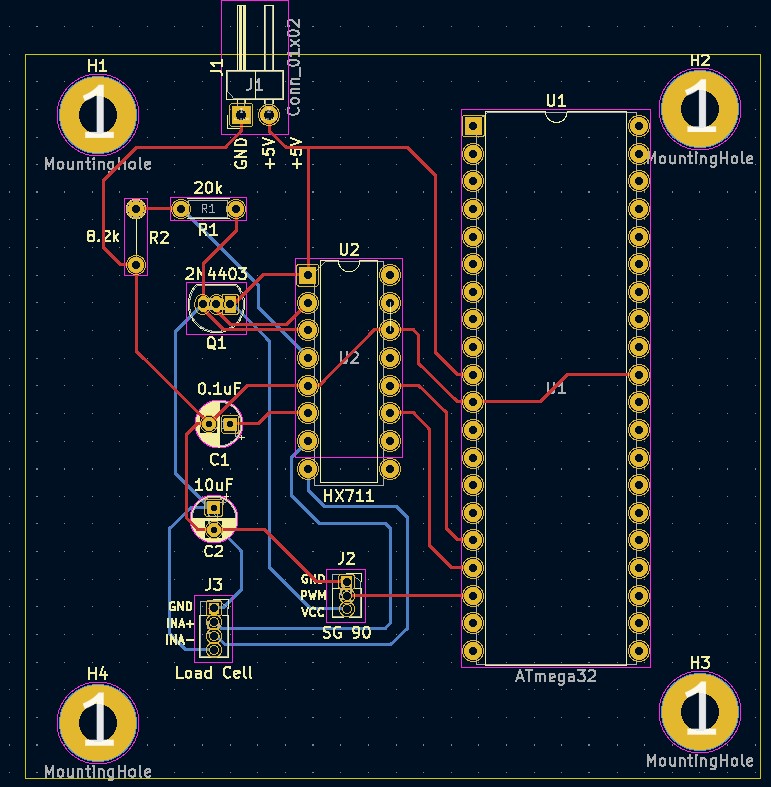
**Circuit Diagram**

****

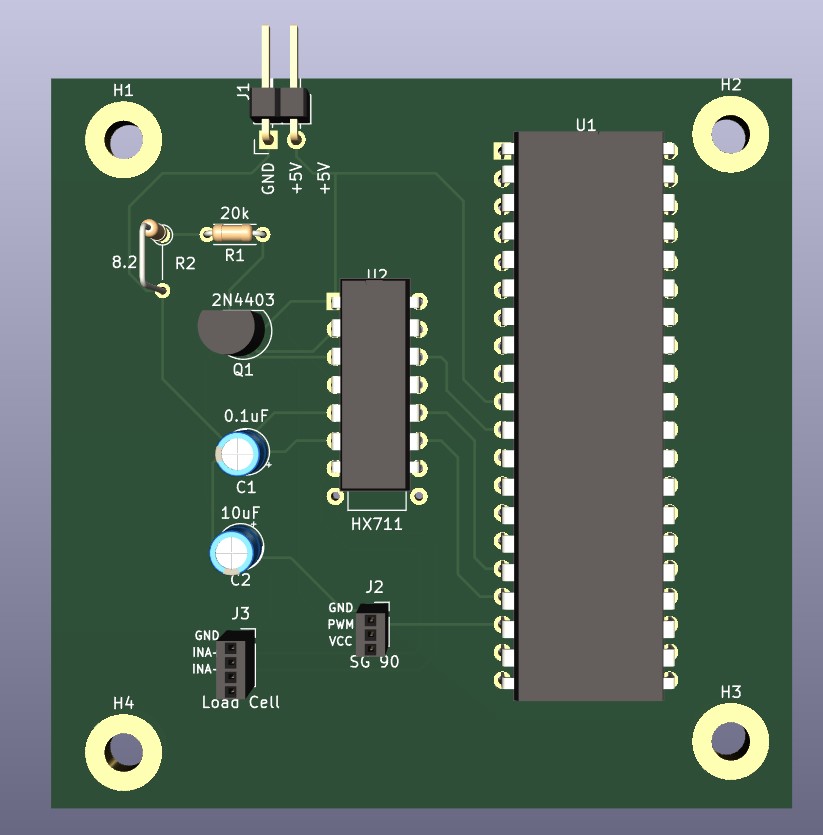
**Schematic Diagram**

****

**PCB Design**

****

**3d view**

****

**Code**

#define *F\_CPU* 8000000

#include <avr/io.h>

#include <util/delay.h>

*uint8\_t* hx711H=0; //Load Scale High Bits

*uint16\_t* hx711L=0;//Load Scale Low Bits

float loadCellRead();

#define Load\_data 2

#define Load\_clk 3

float loadCellRead();

float hx=0;

void servoangle(*uint8\_t* pin);

int main(void)

{

DDRD|=(1<<Load\_clk); //Load cell clock pin

PORTD&=~(1<<Load\_clk);//Clock pin low

DDRD|=(1<<4);

while (1)

{

hx=loadCellRead();

if (hx>15)

{servoangle(0);

}

else

{servoangle(1);

}

*\_delay\_ms*(100);

}

}

float loadCellRead(){

hx711H=0;hx711L=0; //clear variables

for(*uint8\_t* i=0;i<8;i++){ // Load cell data high 8 bits

PORTD|=(1<<Load\_clk); //Clock pin high

*\_delay\_us*(10);

if ((PIND&(1<<Load\_data))>>Load\_data) //read data pin

{hx711H|=(1<<(7-i));//set hx 711 varible

}

else

{hx711H&=~(1<<(7-i));

}

PORTD&=~(1<<Load\_clk); //Clock pin low

*\_delay\_us*(5);

}

for(*uint8\_t* i=0;i<16;i++){ // Load cell data low 16 bits

PORTD|=(1<<Load\_clk); //Clock pin high

*\_delay\_us*(10);

if ((PIND&(1<<Load\_data))>>Load\_data) //read data pin

{hx711L|=(1<<(15-i));

}

else

{hx711L&=~(1<<(15-i));

}

PORTD&=~(1<<Load\_clk); //Clock pin low

*\_delay\_us*(5);

}

hx711L=hx711L>>1; //shift bits

if (hx711H&1) //bit setup

{hx711L|=(1<<15);

}

else

{hx711L&=~(1<<15);

}

hx711H=hx711H>>1;

return (hx711H\*(65536/18029.6))+hx711L/18029.6; //load cell calibration

}

void servoangle(*uint8\_t* pin){

if (pin)

{

for(*uint8\_t* j=0;j<100;j++){

PORTD|=(1<<4);

for(*uint8\_t* i=0;i<10;i++){

*\_delay\_us*(100);

}

PORTD&=~(1<<4);

*uint8\_t* ser=200-10;

for(*uint8\_t* i=0;i<ser;i++){

*\_delay\_us*(100);

}

}

}

else

{for(*uint8\_t* j=0;j<100;j++){

PORTD|=(1<<4);

for(*uint8\_t* i=0;i<15;i++){

*\_delay\_us*(100);

}

PORTD&=~(1<<4);

*uint8\_t* ser=200-15;

for(*uint8\_t* i=0;i<15;i++){

*\_delay\_us*(100);

}

}

}

}

**5.Name of Student: Kavinda K.A.R. – 204098N**

**ULTRASONIC SENSOR**

A picture containing electronics, projector

Description automatically generated

**Ultrasonic Sensor (HC-SR04)**

The ultrasonic sensor works on the principle of SONAR and RADAR system which is used to determine the distance to an object.

An ultrasonic sensor generates the high-frequency sound (ultrasound) waves. When this ultrasound hits the object, it reflects as echo. By using that we can measure the distance to the object

**Distance measuring**

Distance = speed \* time

The speed of sound waves is 340 m/s. (34000 cm/s)

So,

Total Distance = (Tx34000 x 10-6)/2

= (17/1000)

= T/58

**HC-SR04 ultrasonic sensor has 4 pins which are VCC, Trigger, Echo, GND**

VCC - Connects to the VCC supply

Trigger -Creates 8 pulses of 10µsec or more

Echo -Starts a single clock when trigger activated

GND -Connects to the ground

**Specifications -:**

Model : HC-SR04

Power : 5V

Working Current : 15mA

Ranging distance : 0.2- 400 cm

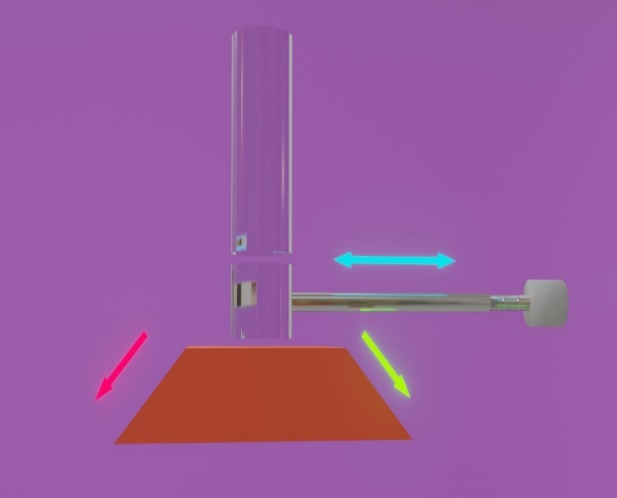
Measuring Angle : 30 º

Trigger input pulse width : 10 µS

Weight : 10g

Modulation frequency :40Hz

**physically location**



Ultrasonic Sensor

**Schematic diagram of ultrasonic sensor**

Diagram, schematic

Description automatically generated

**PCB design**

Diagram

Description automatically generated

**Code for ultrasonic sensor**

#define F\_CPU 16000000UL

#include <avr/io.h> // Include AVR std. library file

#include <util/delay.h>

#include <style> //convert integer to character array

#define lcd\_port PORTD // connected lcd on to the port D

#define lcd\_data\_dir DDRD // difinding the direction of the pins- input/out

#define rs PD0

#define en PD1

#define US\_PORT PORTC // connected ultrasonic to port C

#define US\_PIN PINC // initialization of pin register

#define US\_DDR DDRC // data direction register to set the data direction flow

#define US\_TRIG\_POS PC0

#define US\_ECHO\_POS PC1

#define US\_ERROR -1 //difinding variable to working or not

#define US\_NO\_OBSTACLE -2

int distance, previous\_distance;

void HCSR04Init();

void HCSR04Trigger();

void lcd\_command( unsigned char );

void HCSR04Init()

{

US\_DDR|=(1<<US\_TRIG\_POS);

}

void HCSR04Trigger()

{

US\_PORT|=(1<<US\_TRIG\_POS);

\_delay\_us(15);

US\_PORT&=~(1<<US\_TRIG\_POS);

}

uint16\_t GetPulseWidth()

{

uint32\_t i,result;

for(i=0;i<600000;i++)

{

if(!(US\_PIN & (1<<US\_ECHO\_POS)))

continue;

else

break;

}

if(i==600000)

return US\_ERROR;

TCCR1A=0X00;

TCCR1B=(1<<CS11);

TCNT1=0x00;

for(i=0;i<600000;i++)

{

if(US\_PIN & (1<<US\_ECHO\_POS))

{

if(TCNT1 > 60000) break; else continue;

}

else

break;

}

if(i==600000)

return US\_NO\_OBSTACLE;

result=TCNT1;

TCCR1B=0x00;

if(result > 60000)

return US\_NO\_OBSTACLE;

else

return (result>>1);

}

void initialize (void)

{

lcd\_data\_dir = 0xFF; //lcd pins that connected to micro-controller as out puts

\_delay\_ms(15);

lcd\_command(0x02);

lcd\_command(0x28);

lcd\_command(0x0c);

lcd\_command(0x06);

lcd\_command(0x01);

\_delay\_ms(2);

}

void lcd\_command( unsigned char cmnd )

{

lcd\_port = (lcd\_port & 0x0F) | (cmnd & 0xF0);

lcd\_port &= ~ (1<<rs);

lcd\_port |= (1<<en);

\_delay\_us(1);

lcd\_port &= ~ (1<<en);

\_delay\_us(200);

lcd\_port = (lcd\_port & 0x0F) | (cmnd << 4);

lcd\_port |= (1<<en);

\_delay\_us(1);

lcd\_port &= ~ (1<<en);

\_delay\_ms(2);

}

void lcd\_clear()

{

lcd\_command (0x01);

\_delay\_ms(2);

lcd\_command (0x80);

}

void lcd\_print (char \*str)

{

int i;

for(i=0; str[i]!=0; i++)

{

lcd\_port = (lcd\_port & 0x0F) | (str[i] & 0xF0);

lcd\_port |= (1<<rs);

lcd\_port|= (1<<en);

\_delay\_us(1);

lcd\_port &= ~ (1<<en);

\_delay\_us(200);

lcd\_port = (lcd\_port & 0x0F) | (str[i] << 4);

lcd\_port |= (1<<en);

\_delay\_us(1);

lcd\_port &= ~ (1<<en);

\_delay\_ms(2);

}

}

void lcd\_setCursor(unsigned char x, unsigned char y){

unsigned char adr[] = {0x80, 0xC0};

lcd\_command(adr[y-1] + x-1);

\_delay\_us(100);

}

int main()

{

initialize();

char numberString[4];

while(1) {

uint16\_t r;

\_delay\_ms(100);

HCSR04Init(); // set io port direction of sensor

lcd\_print("hello customer !");

\_delay\_ms(10);

lcd\_setCursor(1, 2);

lcd\_print("enter your can");

\_delay\_ms(1000);

lcd\_clear();

while(1)

{

HCSR04Trigger(); // calling the ultrasonic sound wave generator function

r=GetPulseWidth(); // getting the duration of the ultrasound took echo back

// handle errors

if(r==US\_ERROR)

{

lcd\_setCursor(1, 1);

lcd\_print("Error!");

}

else

{

distance=(r\*0.034/2.0);

if (distance != previous\_distance)

{

lcd\_clear();

}

lcd\_setCursor(1, 1);

if((distance>45)&&(distance<50))

{

lcd\_setCursor(1, 1);

lcd\_print("can detected");

}

else

{

lcd\_setCursor(3, 1);

lcd\_print("can not detected");

}

itoa(distance, numberString, 10); // converting

lcd\_setCursor(8, 2);

lcd\_print(numberString);

lcd\_setCursor(10, 2);

lcd\_print(" cm");

previous\_distance = distance;

\_delay\_ms(30);

}

}

}

}

**Working process**

**pipe**

ultrasonic sensor

50 cm can

45cm

* Using an ultrasonic sensor, we measure the distance between the can from the sensor. If the distance is between 50cm and 45cm we can determine that customer entered a valid can. But to ensure that it is a can, we also must consider weight sensor output and proximity sensor output.

Ultrasonic Sensor Data Sheet -: <https://datasheetspdf.com/pdf/1380136/ETC/HC-SR04/1>

**LCD DISPLAY**



**Lcd 16\*2 display**

This display includes 2 lines, and each line can display 16 characters. Each character displays in 5\*7-pixel matrix. Most of the 16x2 LCDs use a Hitachi HD44780 or a compatible controller.

Using this display, we can get many benefits.it is inexpensive, simply programmable and there are no limitations for displaying custom characters. Hence, we use lcd 16\*2 display for our hardware project.

**Features**

Operating voltage : 4.7V-5.3V

The utilization of current : 1mA (with no backlight)

Working modes : 4bit mode & 8bit mode

Display characters : 32 characters

There are green & blue blacklight displays in the market

**Pin configuration of 16\*2 display**

Timeline

Description automatically generated

**physically location**

Graphical user interface

Description automatically generated with medium confidence

Lcd display

**Schematic diagram of lcd display**

Diagram, schematic

Description automatically generated

**PCB design**

Diagram

Description automatically generated

**Code for lcd display**

#define F\_CPU 16000000UL

#include <avr/io.h> // Include AVR std. library file

#include <util/delay.h>

#define lcd\_port PORTD // connected lcd on to the port D

#define lcd\_data\_dir DDRD // difinding the direction of the pins- input/out

#define rs PD0

#define en PD1

void lcd\_command( unsigned char );

void initialize (void)

{

lcd\_data\_dir = 0xFF;

\_delay\_ms(15);

lcd\_command(0x02); // 4-bit initialization of lcd

lcd\_command(0x28); // 2 line,5\*7 matrix in 4-bit mode

lcd\_command(0x0c); //display on cursor off

lcd\_command(0x06); //increment cursor

lcd\_command(0x01); // clear display screen

\_delay\_ms(2);

}

void lcd\_command( unsigned char cmnd )

{

// send higher 4 bit of data

lcd\_port = (lcd\_port & 0x0F) | (cmnd & 0xF0);

lcd\_port &= ~ (1<<rs);

lcd\_port |= (1<<en);

\_delay\_us(1);

lcd\_port &= ~ (1<<en);

\_delay\_us(200);

// lower 4 bit of data

lcd\_port = (lcd\_port & 0x0F) | (cmnd << 4);

lcd\_port |= (1<<en);

\_delay\_us(1);

lcd\_port &= ~ (1<<en);

\_delay\_ms(2);

}

void lcd\_clear()

{

lcd\_command (0x01);

\_delay\_ms(2);

lcd\_command (0x80); // cursor at home

}

void lcd\_print (char \*str)

{

int i;

for(i=0; str[i]!=0; i++)

{

lcd\_port = (lcd\_port & 0x0F) | (str[i] & 0xF0);

lcd\_port |= (1<<rs);

lcd\_port|= (1<<en);

\_delay\_us(1);

lcd\_port &= ~ (1<<en);

\_delay\_us(200);

lcd\_port = (lcd\_port & 0x0F) | (str[i] << 4);

lcd\_port |= (1<<en);

\_delay\_us(1);

lcd\_port &= ~ (1<<en);

\_delay\_ms(2);

}

}

void lcd\_setCursor(unsigned char x, unsigned char y){

unsigned char adr[] = {0x80, 0xC0};

lcd\_command(adr[y-1] + x-1);

\_delay\_us(100);

}

int main()

{

initialize();

lcd\_setCursor(2, 1);

lcd\_print("hello customer");

lcd\_setCursor(2,2 );

lcd\_print("Enter your can");

}

**Working process**

Using lcd display we are giving necessary outputs to the customer according to the measurements of the sensors.

Lcd display data sheet - <https://www.vishay.com/docs/37299/37299.pdf>