

Fall Semester 2015

Line following robot

Group 2

2. Semester IT-Technology

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Title:

Line following robot

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Projectgroup:

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Introduction

A line following robot is basically a robot designed for the consumer to follow a line or path that is predetermined. This line or path may be as simple as a strip of tape or a black line and if developed further can follow e.g magnetic markers, embedded lines and laser guided markers. In order to detect the various lines or paths, miscellaneous sensors or sensing schemes can be used.

These schemes may range from simple low cost schemes to advanced and more expensive vision systems. In the industry the many different types of robots are already implemented in semi to fully automatic systems.

The project was handed to the group april 12'th and will be handed in at UCN Sofiendalsvej, june 7'th at 12.00.

The objective of this project is to design and implement an automotive robot capable of autonomous maneuvering, specifically a line-following robot employing light detecting sensors.

The challenges at hand is to design a system for the board, to utilize the ADC capabilities of the chip and to implement a PID controller. Furthermore test the products performance on a test track to optimize by trial and error and to implement software with multiple light detecting sensors.

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3D print	3-Dimensional printing
ADC	Analog-digital conversion
GUI	Graphical User Interface
IDE	Integrated Development Environment
MCU	Microcontroller Unit
PID	Proportional-integral-derivative
PWM	Pulse-width modulation
THT	Through-hole-technology

Requirements specification

1

The following section will describe the specific requirements that have been decided to fulfil to the general requirements as shown in the project description.

- Project must include light sensors
- Implement motor control
- Should make use of the Pic32 MCU
- Software will be written in MPLABX
- Autonomous operation
- The product must make use of feedback concept e.g. a PID algorithm
- A function & performance test is to be conducted

Hardware section 2

In the following section, the hardware parts and functions will be introduced and described. The following part consists of sensor selection, ADC, chipKIT Uno32 board & motor-shield.

2.1 Hardware diagram

The micro-controller is connected to the motor-shield and the motor-shield is then powering both motor 1 and motor 2. The sensor-array is sending the collected data to the micro-controller every 25 ms, the micro-controller then sends it further to the bluetooth unit. The bluetooth unit then writes the data to the terminal.

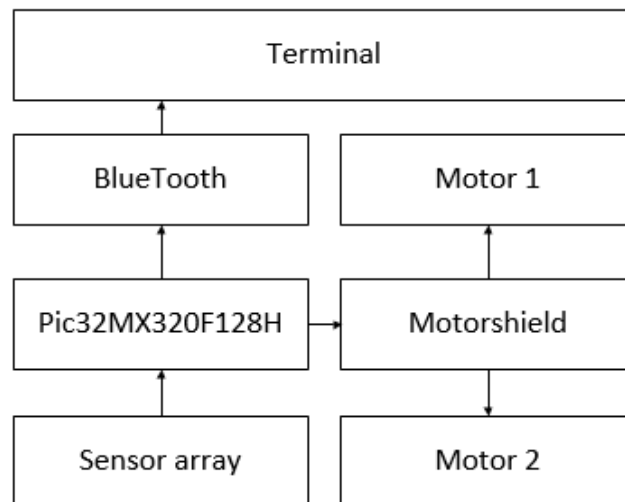


Figure 2.1: Block diagram showing the hardware.

2.2 Selection of sensor

The table shows a comparison of the two sensors that were taken into consideration for the project, that is to show the price difference and the utility from sensor to

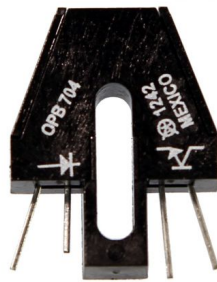
Name	QRE1113 Board	OPB704
Max sensor distance	3mm	3.8mm
Forward current	50mA	40mA
Mounting	On print	In casing
Price	19.43DKK	42.55DKK

Table 2.1: Table showing the sensors in consideration

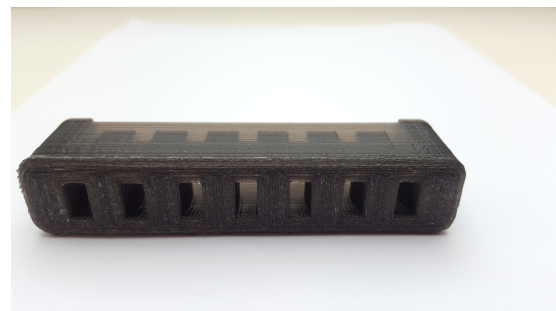
sensor. (*fig 2.1*)

2.2.1 The OPB704

The OPB704 sensor ended up being selected for the robot over the popular QRE1113 sensor board. It has a higher sensor max distance (3.8mm¹ compared to the QRE1113s 3mm) and it has the same functionality. It comes with a special casing, for which a special mounting unit was 3D-printed to accommodate an array of 7. This makes the mounting very solid and tightly fitted unto the robot, which ideally makes the sensor array more stable in case of an uneven test course.



(a) The sensor OPB 704



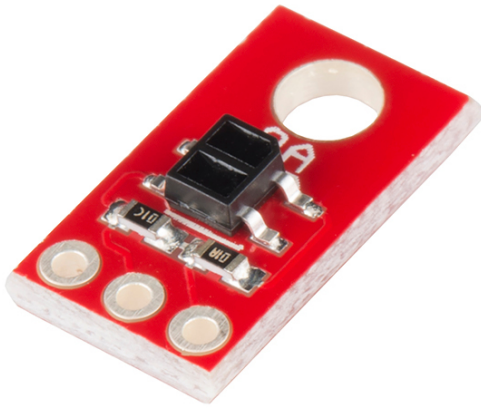
(b) 3D printed sensor array module

2.2.2 The QRE1113 board(Analog)

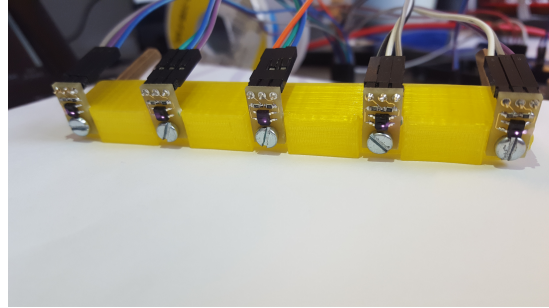
Another possible sensor selection would be the QRE1113² board sensor. This sensor comes complete with mounting and the necessary printing and wiring. This makes working with the sensor fairly straight forward. Although this sensor is commonly used for line following robots, when it was compared to the OPB704, it quickly became apparent that the difference in max sensor distance could become a liability, and with this in mind, the OPB704 sensor was selected.

¹<http://www.farnell.com/datasheets/1884910.pdf>

²<http://cdn.sparkfun.com/datasheets/Sensors/Proximity/QRE1113.pdf>



(a) QRE1113 Sensor with own mount



(b) 3D printed sensor array module with the QRE1113

2.3 Analog-to-digital converter (ADC)

The purpose of the ADC is to convert the analog data from the sensors to digital data that can be managed by a computer - this allows data received from the blue-tooth transmitter on the product to be processed into readable data more easily, which is great for showing how the sensors are reacting. The sensors themselves cannot discern what they actually need to read, the sensors just read anything they can see and send that signal.

Analog signals can have a significant amount of noise - since any received noise is interpreted as part of the signal, a digital signal is not only more easy to work with, it will also provide more precise data. This will make for more accurate readings on the tachometer on the robot, which allows even more finely tuned monitoring of the robot and its working processes.

ADC diagram

This products usage of ADC

The usage of the ADC in the system, is to measure the returning voltage from the OPB704 sensor. Both the OPB704 and the QRE1113 sensors are reflective phototransistors. A reflective phototransistor consists of a infrared LED and a phototransistor. The phototransistors output voltage is controlled by the amount of light from the LED that is being reflected of the given surface the sensor is looking at, back to the phototransistor.

2.4 The ChipKit Uno32 board

Our main computing core is at the ChipKit Uno32 board. The board was selected both because of previous experiences, and because it met the set requirements perfectly - most importantly it has twelve analog inputs to handle our array of seven

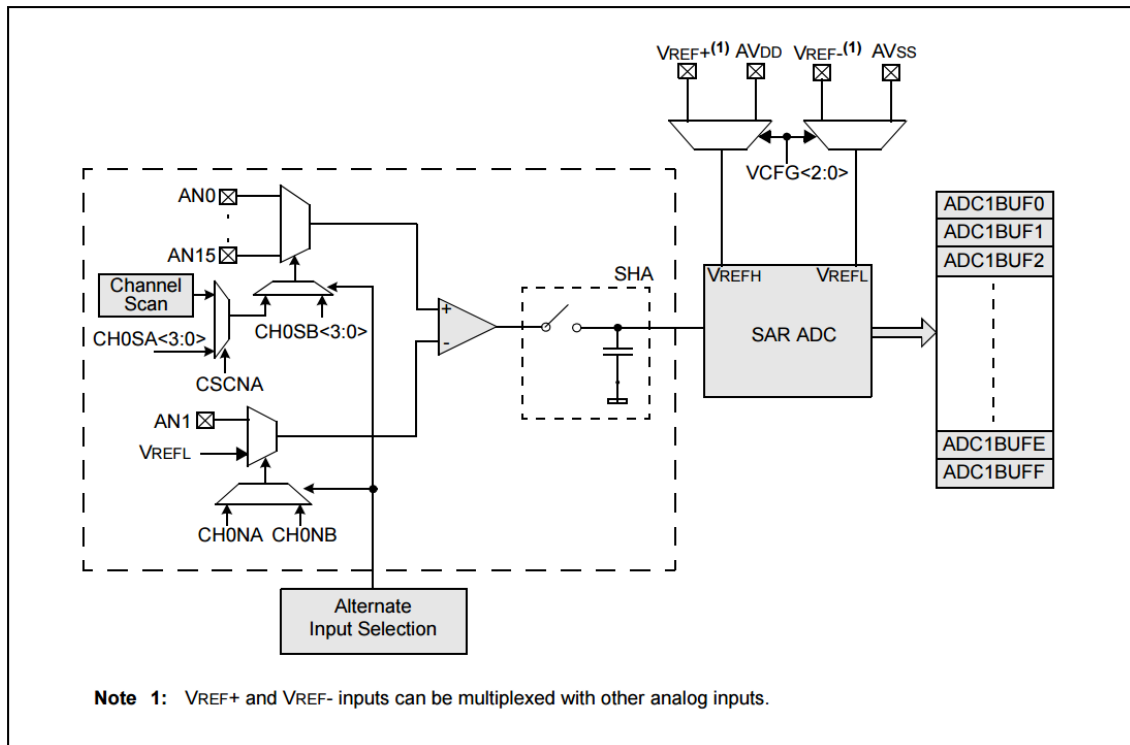


Figure 2.4: PIC32 ADC functional block diagram

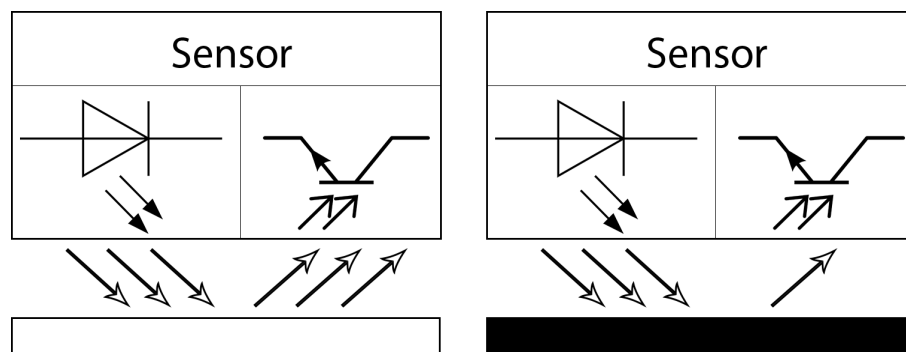


Figure 2.5: The difference in reflection on light and dark surfaces

sensors. This board utilizes the PIC32MX320F128 microcontroller, which features a 32-bit processing core running at 80Mhz with 128K of flash program memory and 16K SRAM data memory³. This board allowed the most important aspects of the project to become reality; namely a GUI showing both the ADC readings as well as visualizing the sensor inputs, plenty of analog inputs to allow for the sensor array, and BlueTooth transmission of data from the robot unto a computer.

The board is compatible for use with MPLAB IDE and the PICKit3 debugger.

³<http://www.microchip.com/wwwproducts/en/PIC32MX320F128H>

2.5 The motor shield - PKA03

The motor shield was chosen because it is compatible with the Uno32 board, and fits perfectly within the scope of the project. It controls both motors and receives power from the 7.2 V lithium-ion battery pack mounted on the chassis itself. The motor shield is instrumental in providing motor controls to the product. To do this, it utilizes a specific electric circuit, called an H bridge.

2.5.1 The H bridge

An H bridge is a circuit that allows a voltage to be applied across a load in either direction. The purpose of this in the case of this project is to enable controls of the two motors in a way so that they can function individually, and both drive forwards and backwards.

At first, there were experiments with custom prints and a purpose-built h bridge on the first iteration of the motor shield. However after testing, it proved faulty and was changed to accommodate time constraints.

2.6 The blue-tooth transmitter - BlueSMIRF Silver

The robot utilizes the BlueSMIRF Silver blue-tooth transmitter made by Sparkfun. Its function is to send data from the ADC and pulse width modulator (see the software section) to a C# GUI run on a computer. This way, it is possible to monitor both the inputs the robot is receiving, as well as the logic behind the steering. It allows for any stream between 2400 to 115200 bps⁴.

⁴<https://www.sparkfun.com/products/12577>

Software section 3

3.0.1 Software diagram

TBD Softwarediagram

3.1 Description of the software structure and functionality

The following section will introduce the software segment, based on the required specifications. The design will shown in the form of a flowchart. The section consists of the PID controller & the Pulse width modulator. TBD Softwarebeskrivelse og underafsnit

3.2 Analog to digital conversion (software)

```
1 extern int analogRead(char CH) {
2     AD1PCFG = ~CH; // PORTB = Digital; RB2 = analog
3     AD1CON1 = 0x0000; //AMP bit = 0 ends sampling and starts
        converting
4     AD1CSSL = 0; //Input scan select, not used
5     AD1CON3 = 0x0001; //Manual Sample, TAD = internal 6 TPB
6     AD1CON2 = 0; //No scanning, interrupt at completion of each
        sample, one 16-word buffer
7     AD1CON1SET = 0x8000; //Turn on the ADC
8     AD1CHSbits.CH0SA = CH;
9     AD1CON1SET = 0x0002; //Start sampling
10    DelayUs(2); //Wait 2 microseconds
11    AD1CON1CLR = 0x0002; // Start converting
12    while (!(AD1CON1 & 0x0001)); //Waits for conversion
13    return ADC1BUF0; //Returns content of the buffer
14 }
```

The software code is showing how the ADC is converting analog to digital for the product. TBD beskriv koden med registre

3.3 Description of the PID controller

A PID controller continuously calculates an error value as the difference to a reference point and a measured process variable.

PID is an abbreviation for a proportional-integral-derivative controller, it is a control loop feedback mechanism. The controllers job is to minimize the error value for the given devices running time. In the case of this project the reference point is the line to follow and the PID will allow the MCU to adjust the power to the engines,

to steer accordingly to said reference point.

$$F(t) = K_p e(t) + K_i \int_0^t e(\tau) d\tau + K_d \frac{de(t)}{dt}$$

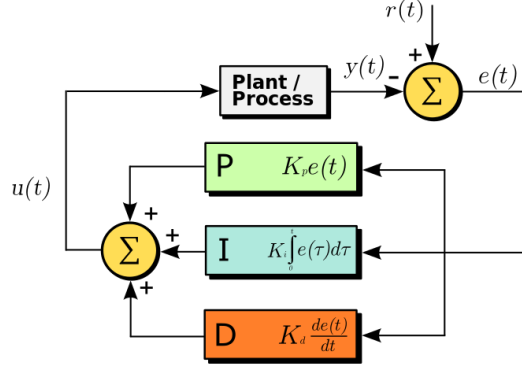


Figure 3.1: Block diagram, showing the idea of PID controller.

Credits: www.wikipedia.org/wiki/PID_controller

3.3.1 Proportional control(P)

The proportional part creates an output value that is proportionally related to the current error value, this value can be tuned by multiplying the error by a constant K_p . A high proportional gain results in a large change in the output for a given change in the error.

$$P_{\text{out}} = K_p e(t)$$

If the proportional gain is too high, the system can become unstable. Contrarily, a small gain will result in the device adjusting too slowly, which decreases overall efficiency and in the case of this project, it will end up being detrimental to the steering accuracy.

3.3.2 Steady-state error

When looking at figure 3.2 the reference point is the blue line and the feedback line is the green, the two lines merge up and the steady-state is achieved. When the lines don't merge and the feedback line is slightly above or under the reference point there is a steady-state error. This steady-state error can be minimized by adjusting the proportional and integral term.

3.3.3 Integral control(I)

The integral controller is contributing proportionally to both the magnitude of the error and the duration of the error.

The integral in a PID controller is the sum of the instantaneous error over time and gives the accumulated offset that should have been corrected previously.

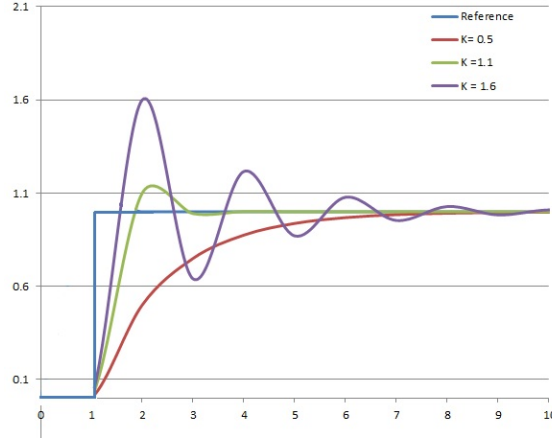


Figure 3.3: K_p with 3 values. (K_i , K_d held constant)

Credits: www.wikipedia.org/wiki/PID_controller#Proportional_term

The controller output equals the accumulated error multiplied by the integral gain(K_i)

$$I_{\text{out}} = K_i \int_0^t e(\tau) d\tau$$

The integral part accelerates the movement of the process towards the reference point. Since the integral term correlates to accumulated errors from the past, it can cause the present value to overshoot the reference value.

3.3.4 Derivative control(D)

The derivative of the process error is calculated by determining the slope of the error over time and multiplying this rate of change by the derivative gain K_d . The magnitude of the contribution of the derivative term to the overall control action is termed the derivative gain, K_d .

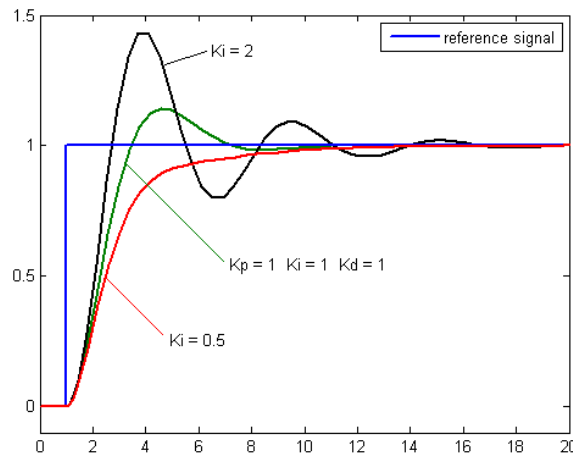


Figure 3.5: K_i shown with 3 values.

Credits: www.wikipedia.org/wiki/PID_controller#Integral_term

The derivative term is given by:

$$D_{\text{out}} = K_d \frac{de(t)}{dt}$$

The derivative action predicts system behaviour and utilizes this to improve the settling time and stability of the system. An ideal derivative is not causal, so that implementations of PID controllers include an additional low pass filtering for the derivative term, to limit the high frequency gain and noise.

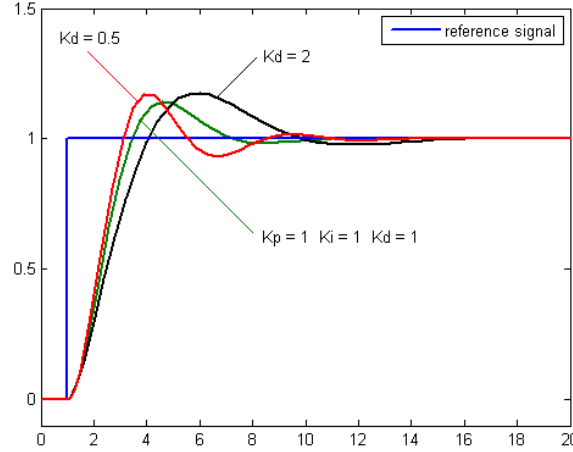


Figure 3.7: K_d shown with 3 values.

Credits: www.wikipedia.org/wiki/PID_controller#Derivative_term

3.3.5 Loop tuning

Tuning the loop is the term used to describe the adjustments of the PID's control parameters (proportional band/gain, integral gain/reset, derivative gain/rate) to the optimal values for the given control scheme.

Stability is the first requirement; however systems can differ greatly, and different applications may have different requirements and these may even conflict with each other. For example, high speed and high accuracy often cancel each other out, because high speed may cause overshooting, while high accuracy is slow.

The ideal realistic behaviour is both as fast as possible, while also having minimum overshoot and oscillation.

Even though the process seems simple, with only three variables, it can be challenging to achieve, because it must satisfy the criteria despite being within the limitations of PID control. While adjusting the PID can seem conceptually intuitive, and while most PIDs may perform acceptably with default controls, they may very well also have an unsatisfactory performance.

This can generally be fixed through optimisation and tuning, either through computer simulations or manual testing. In this case, there was used manual tuning of the numbers.

3.3.6 Stability

If the parameters of the PID controller are set incorrectly the process input can become unstable. This means the controllers output becomes divergent, which can be limited by saturation and mechanical breaking.

3.3.7 Manual tuning

When a system must be online at all times a method for tuning is to first set K_i and K_d values to zero. Increase K_p until the loop output oscillates, setting K_p at approximately half the value for a "quarter amplitude decay" type response.

Then increase K_i until any set off is corrected in sufficient time for the process. Adding too much K_i will however cause an instability. Finally, increase K_d , if required at all, until the loop is acceptably quick to reach its reference after a load disturbance.

A fast PID loop tuning process usually overshoots slightly to reach the reference point faster.

But in the case of systems that can't accept overshoot, an over-damped closed-loop system is best suited, which requires K_p setting significantly less than half that of the K_p setting that was causing the oscillation.

Table 3.1: Manual tuning

Parameter	Rise time	Overshoot	Settling time	Steady-state error	Stability
K_p	Decrease	Increase	Small change	Decrease	Degrade
K_i	Decrease	Increase	Increase	Eliminate	Degrade
K_d	Minor change	Decrease	Decrease	No effect in theory	Improves if K_d is small

Table 3.1 explained

Table 3.1 gives an informative overview of what the different parameters does when tuned manually¹.

- To minimize the rise time, decrease K_p
- To eliminate the steady-state error, increase K_i
- To reduce the overshoot and settling time, decrease K_d

3.3.8 PID Implementation

TBD har ændret sensorAvg til sensorMean, gør dette i koden også

¹<http://saba.kntu.ac.ir/eecd/pcl/download/PIDtutorial.pdf>

```

1 void PID(int sensorMean, int sensorSum)
2 {
3     if(sensorSum > 0) //At least one sensor sees black
4     {
5         sensorPos = sensorMean/sensorSum; //Position of the line on
           the sensorarray
6         sensorProp = sensorPos - 3; //Proportional part
7         sensorInt = sensorInt + sensorProp; //Integral part
8         if(sensorInt > 100) //Reduce adjustment time by limiting Int
9             sensorInt = 100;
10        if(sensorInt < -100)
11            sensorInt = -100;
12        sensorDer = sensorProp - sensorLastProp; //Derivative part

```

The PID function has two parameters, sensorMean and sensorSum. These are used to calculate where the line is in relation to the sensors. In the beginning, a check is made to make sure the line actually is on the array somewhere, since the program would stall by trying to divide by sensorSum being 0. If at least one sensor detects the line, the position is calculated by dividing the mean value of the active sensors by the amount of sensors active. Since sensorMean is calculated using weighs on each sensor, this will give the average position. The function then calculates the different parts of the PID controller, firstly the proportional part. This is done by simply subtracting the weighted value of the middle sensor from the position calculated earlier. Next up is the integral part, which is calculated by adding the previous value of the integral to the proportional value. Right after, the integral is limited since the robot will be working fast on a small line. Derivative is the last part calculated, which is done by subtracting the previous value of the proportional part from the current value.

```

1     sensorError = (sensorProp*kp)+(sensorInt*ki)+(sensorDer*kd);
           //PID calculation
2     sensorLastProp = sensorProp; //Saves proportional for next
           derivative
3     if(sensorError < -(initialPwm)) //Sets an upper cap for
           adjustment
4         sensorError = -(initialPwm);
5     if(sensorError > (initialPwm))
6         sensorError = (initialPwm);

```

This part of the code handles the total PID value as well as limiting this value. First of all, it multiplies the previous PID values by their constants and adding these numbers together and then saves the proportional value to be handled by the derivative part next time. At the end, sensorError is limited to the maximum speed of the motors, to make future calculations easier.

```

1     if(sensorError<0)
2     {
3         adjustedPWM[0] = initialPwm-sensorError; //Increase left
           motor, sensorError is negative here
4         adjustedPWM[1] = initialPwm+sensorError; //Decrease right
           motor
5         dir = 1; //turn right

```

```

6     }
7     else if(sensorError>0)
8     {
9         adjustedPWM[0] = initialPwm-sensorError;
10        adjustedPWM[1] = initialPwm+sensorError;
11        dir = 0; //turn left
12    }
13    else
14    {
15        adjustedPWM[0] = initialPwm;
16        adjustedPWM[1] = initialPwm;
17        dir = 2;
18    }
19 }
20 }

```

The final part of the PID function handles the duty cycle sent to the motors. If sensorError is less than 0, the robot needs to turn right, increasing engine power on the left while decreasing engine power on the right. If sensorError is positive, do the opposite. If sensorError is exactly 0, the duty cycle will remain what it was last iteration, which is a very rare case.

3.4 Description of the Pulse width modulator - PWM

A pulse width modulation technique used to encode a message into a pulsing signal. Its primary use is to control the power supply of electronic devices - the case of this project; this means the motors. The average voltage and amplitude output to the motors is altered by rapidly switching between an 'on' and 'off' state. This way, the average output is easily altered by changing the proportions between the on and off state. The longer the switch is set to on compared to off, the higher the average supply will be. Pulse-width modulation utilizes a rectangular pulse where the width of the pulse is modulated to get the variation in the average value of the waveform. Given the pulse waveform $f(t)$ over the period T , low value y_{\min} and high value y_{high} and duty cycle D , the average waveform is given by:

$$\bar{y} = \frac{1}{T} \int_0^T f(t) dt$$

This expression can be simplified where $y_{\min} = 0$ as $\bar{y} = D \cdot y_{\max}$. From this it can be observed that the average value of the signal (\bar{y}) has a direct correlation with the duty cycle D .²

$$\bar{y} = \frac{1}{T} \left(\int_0^{DT} y_{\max} dt + \int_{DT}^T y_{\min} dt \right)$$

²https://en.wikipedia.org/wiki/Pulse-width_modulation#Principle

$$\begin{aligned}
&= \frac{1}{T} (D \cdot T \cdot y_{\max} + T(1 - D)y_{\min}) \\
&= D \cdot y_{\max} + (1 - D) y_{\min}
\end{aligned}$$

3.4.1 Duty cycles

The duty cycle describes the proportion of 'on' compared to any given period of runtime for the device. The duty cycle is described as a percentage, where 100% means that it's turned on the entire time, where 10% would be a tenth of the time.

$$D = \frac{T}{P} \cdot 100\%$$

- Where **D** is the duty cycle.
- **T** is the time the signal is active.
- **P** is the total period of the signal.

TBD Vores duty cycle

3.5 The GUI

The project utilizes a GUI written in C# , it shows a graphical representation of the sensor load, as well as which motor is running in accordance to the PID. The GUI has controls to set the COM-port as well as the baud rate, and a button prompt to connect and disconnect the robots blue-tooth transmission. It also features a terminal in the bottom, showing all the data sent from the ADC to the robot.

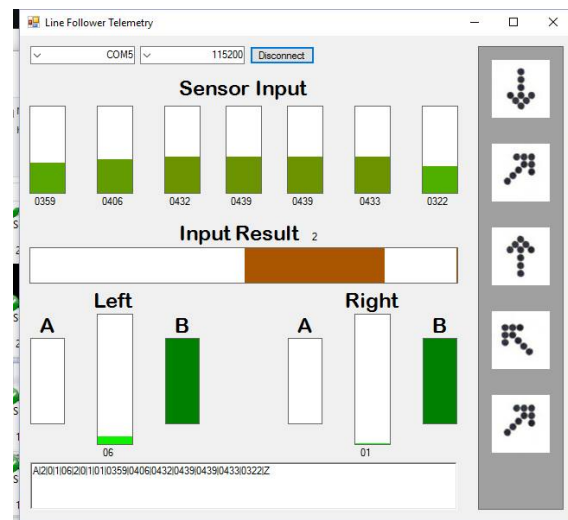


Figure 3.9: Screenshot of the C# GUI used to monitor the input readings.

To make sure the product as a whole is working according to plan, testing must be done. First the components must be tested, this is done individually for each component to make sure there are no errors or fails when the product is built. The purpose of integration testing is to detect any inconsistencies between the software units that are integrated together. Testing is also done to watch the behavior of the product and tweak it.

4.1 Unit Testing

The individual parts of the system will be tested in the following section

4.1.1 Sensor

The following test is to make sure that the selected sensors work as intended for the project.

Equipment

- Hameg HM8040-2 Triple Power Supply
- Fluke 45 Multimeter

Setup

Sensor is powered through the robot. Output from sensor is measured with multi-meter.

Results

White Surface: Average voltage measured: 230 mV

Black Surface: Average voltage measured: 2,6 V

This shows that the sensor clearly measures a difference between light and dark surfaces, making it ideal for this application.

4.1.2 DC Motors

The following test is to make sure that the DC motors work as intended.

Equipment

- Hameg HM8040-2 Triple Power Supply
- Fluke 45 Multimeter

Setup

The motor is powered through the power supply. Amount of drawn current is measured with multimeter.

Results

Both motors have been measured at 6 V and show a steady current draw of 0,11 A when running freely.

4.1.3 H-Bridge

The following test is to make sure the H-bridge works as intended.

Equipment

- Hameg HM8040-2 Triple Power Supply
- Fluke 45 Multimeter
- Agilent MSO-X 3024A Oscilloscope.

Setup

H-Bridge is powered by the power supply. PWM and duty cycle is controlled by the function generator in the Oscilloscope. Output is measured with the multimeter. H-bridge motor direction is controlled manually.

Results

Direction: 0

- **Duty Cycle 20%:** 1,76 V measured.
- **Duty Cycle 50%:** 2,74 V measured.
- **Duty Cycle 80%:** 3,58 V measured.

Direction: 1

- **Duty Cycle 20%:** -1,57 V measured.
- **Duty Cycle 50%:** -2,55 V measured.
- **Duty Cycle 80%:** -3,50 V measured.

The results show that the H-Bridge unit is capable of controlling the voltage output in both directions, with the output voltage level controlled by the PWM signal applied to the unit.

4.1.4 PWM

This test is to measure the PWM capability of the PIC32MX320F128H as well to see if the software implementation is capable of controlling the PWM module of the MCU.

Equipment

- Agilent MSO-X 3024A Oscilloscope.
- chipKIT Uno32 with PICkit 3 programmer.

Setup

The Uno32 board is programmed to run the PWM at different frequencies and duty cycles. Output is measured with the Oscilloscope.

Results

The test shows that the PWM module and developed software is working as intended.

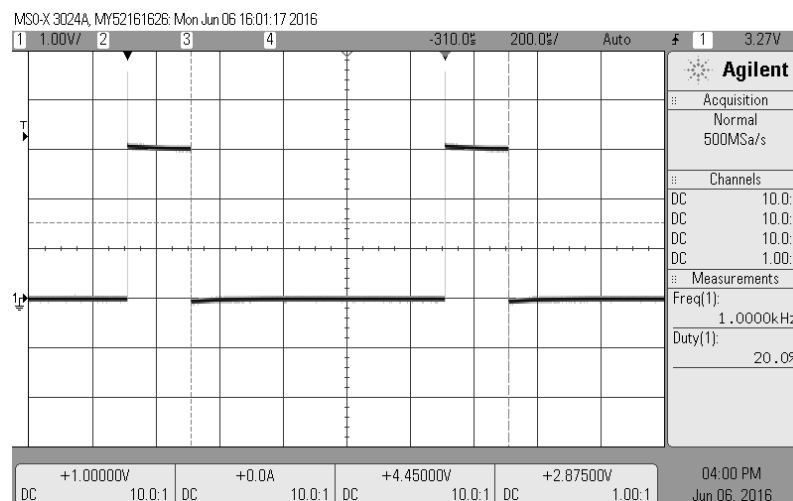


Figure 4.1: Output with 1000 Hz frequency and 20% Duty Cycle

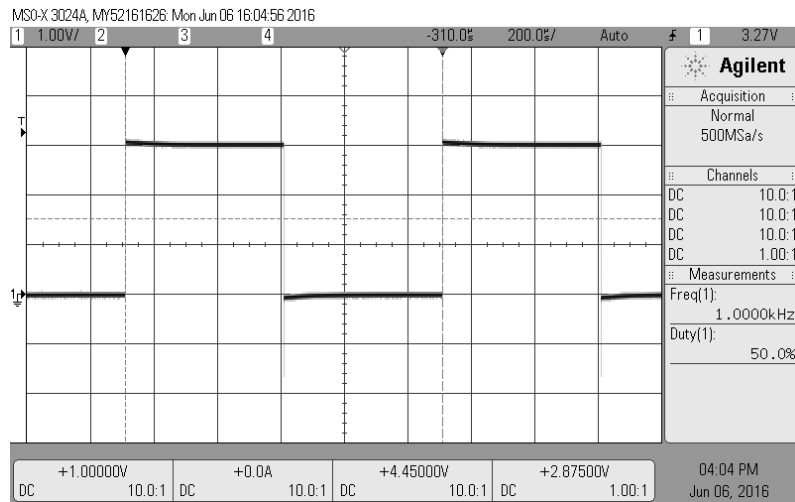


Figure 4.2: Output with 1000 Hz frequency and 50% Duty Cycle

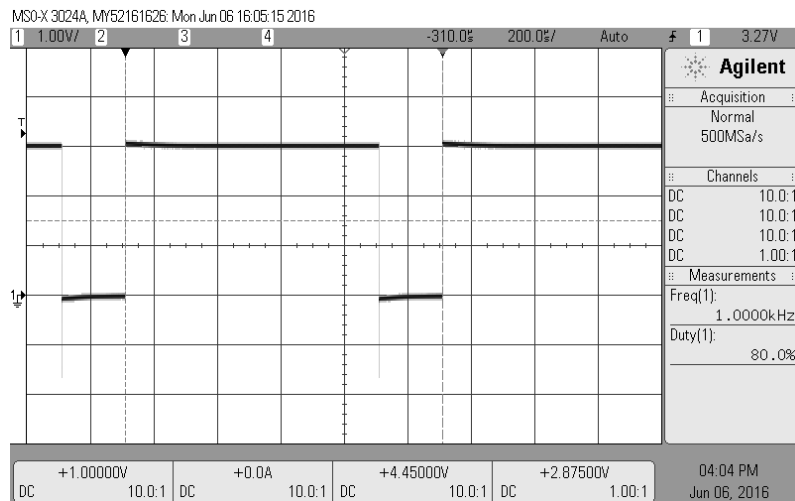


Figure 4.3: Output with 1000 Hz frequency and 80% Duty Cycle

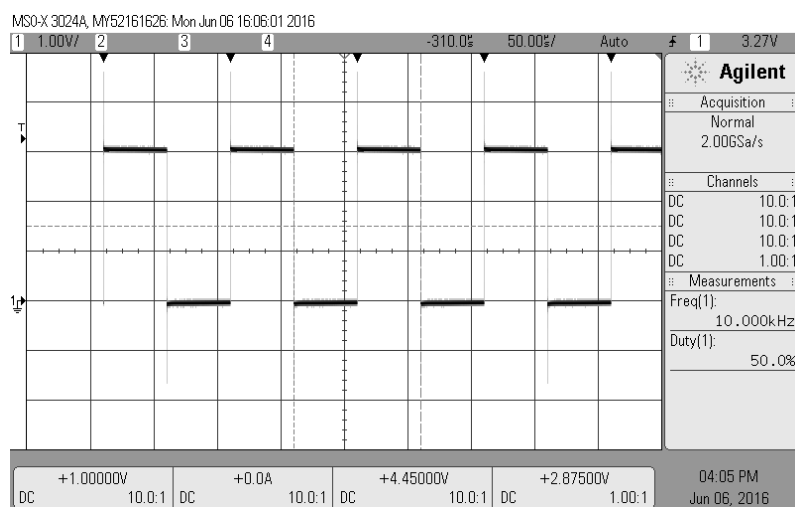


Figure 4.4: Output with 10000 Hz frequency and 50% Duty Cycle

4.1.5 ADC

This test is to show that the ADC module and the developed software for the module is working as intended.

Equipment

- Hameg HM8040-2 Triple Power Supply.
- chipKIT Uno32 with PICkit 3 programmer in debug mode.

Setup

The Uno32 is powered from the PICkit 3 programmer in debug mode to read the contents of a variabel containing the output of the ADC module. The input voltage on the ADC is supplied by the power supply.

Results

- **PS:** 0,499V - **Measured:** 163 (0,526V) - **Error:** 5,3%
- **PS:** 1,000V - **Measured:** 331 (1,068V) - **Error:** 6,7%
- **PS:** 2,006V - **Measured:** 665 (2,145V) - **Error:** 6,4%
- **PS:** 3,299V - **Measured:** 1023 (3,300V) - **Error:** 0,03%

This shows that the ADC and the developed software works within the required area for the application.

4.2 Integration Testing

TBD testing af interfacet og evt samarbejde mellem enkelte dele

4.2.1 PWM motor control

The following test is to show that the DC motors can be controlled by the H-bridge unit.

Equipment

- Hameg HM8040-2 Triple Power Supply.
- chipKIT Uno32 with PICkit 3 programmer.

Setup

The H-bridge module is powered from the power supply. The control signals is controlled by the Uno32 board.

Results

- **PWM: 20%:** Motors are not turning. Audible whine.
- **PWM: 30%:** Motors are not turning. Higher audible whine.
- **PWM: 37%:** Motors are turning slowly with assisted start.
- **PWM: 40%:** Motors are turning slowly.
- **PWM: 100%:** Motors are turning maximum speed.

This shows that we the current setup of Motors and H-bridge unit, the variable control span is between an duty cycle of 37% and 100%.

4.2.2 Robot to Interface communication

Equipment

Setup

Results

4.3 System Testing

TBD testing af systemet som helhed Sensor - motor

4.4 Acceptance Testing

TBD testing af systemet som helhed. Acceptabel ydeevne? Kan den klare banen?
Evt. referer til video

Conclusion 5

TBD Konklusion

Appendices 6

6.1 Group collaboration agreement

6.1.1 Contact Information

Table 6.1: Contacts

Benjamin Nielsen	Tlf: 30427645	@: yipiyuk5@gmail.com
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Nikolaj Bilgrau	Tlf: 29802715	@: nikolajbilgrau@gmail.com

6.1.2 Workflow

- Every friday after 12:00 is expected work consisting of three hours.
- If you aren't able of attending for scheduled study day. - Notice must be given to the project team.

6.1.3 Deadline

- Hand in June 7th.

6.1.4 Milestones and goals

In may there is listed a workshop from the 17-23 May. This was postponed and used for project days instead.

April 2016

MONDAY	TUESDAY	WEDNESDAY	THURSDAY	FRIDAY	SATURDAY	SUNDAY
28	29	30	31	1	2	3
4	5	6	7	8	9	10
11	12	13	14	15	16	17
18	19	20 Project day - Tidsplan, rapportstruktur	21	22	23	24
25	26 Project day - Argumentation for komponenter	27	28 Project day -	29 Project day Shield	30 Finish	1
2	3	NOTES				

Figure 6.1: 4 Work days in April

May 2016

MONDAY	TUESDAY	WEDNESDAY	THURSDAY	FRIDAY	SATURDAY	SUNDAY
25	26	27	28	29	30	1
2	3	4	5	6 Project day(Halv helligdag) - Hardware done, software start	7	8
9	10	11	12	13 Project day - Start testing(motor)	14	15
16	17 WORKSHOP	18 WORKSHOP	19 WORKSHOP	20 WORKSHOP	21	22
23 WORKSHOP	24	25 Project day - Software done	26	27 Project day -	28	29
30 Project day	31 Project day - Testing done	NOTES				

Figure 6.2: 6 Work days in May

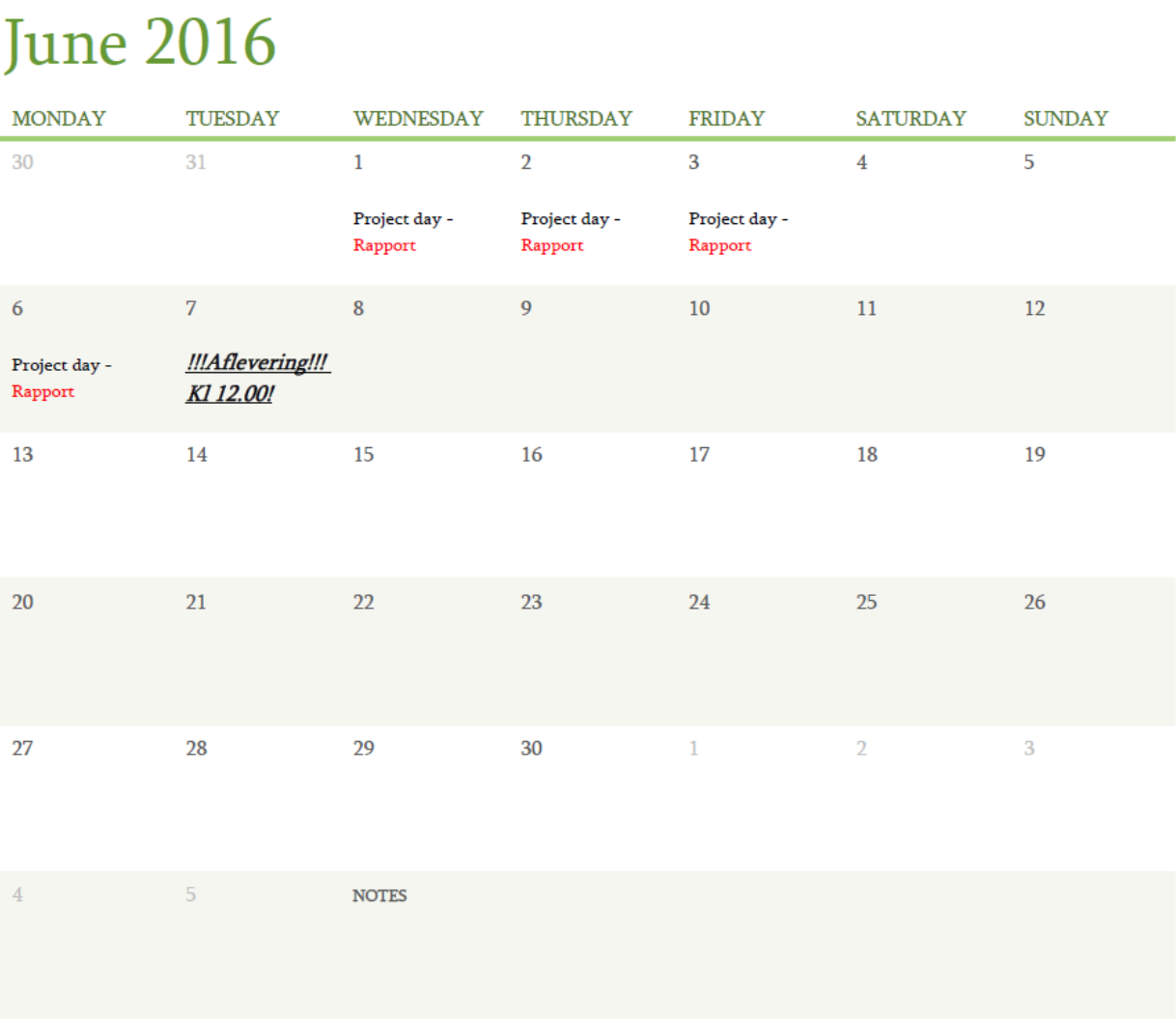


Figure 6.3: 4 Work days in June

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<http://blog.opticontrols.com/archives/1066>

PWM:

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