Dwight Look College of ENGINEERING
TEXAS A&M UNIVERSITY

Team 30: Ember Bot
Bi-Weekly Update 3

Jonathan Chen, Kevin Rivera,
Nancy Ramirez Castillo, Yuwen Zheng
Sponsor: Kevin Nowka
TA: Roman Venegas

Project Summary

Problem Statement:

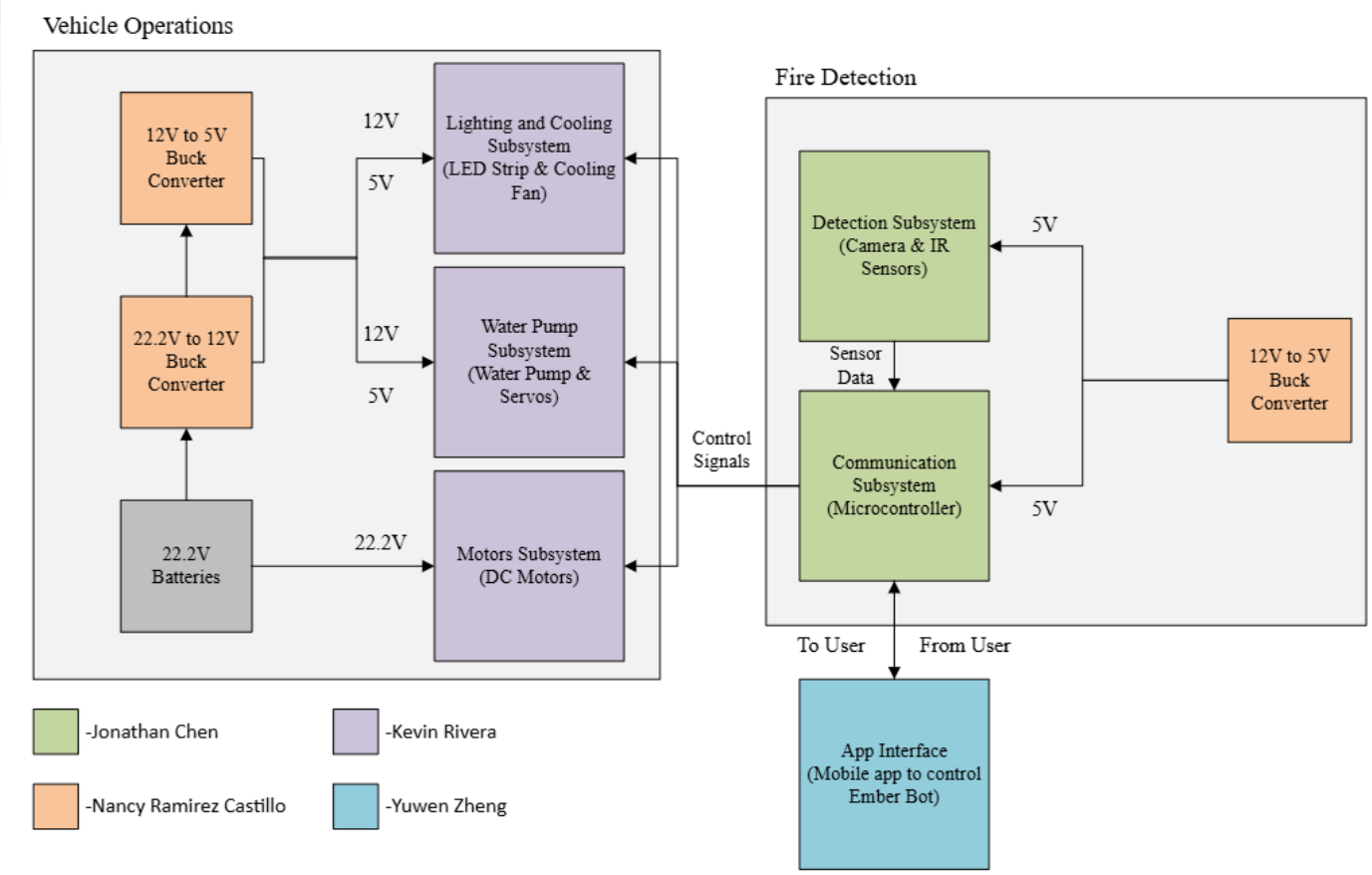
Traditional firefighting methods place firefighters in direct danger, exposing them to extreme heat, toxic smoke, and potential structural collapse, conditions that significantly threaten their safety.

Project Summary

Solution Proposal:

Ember Bot introduces a remotely operated robotic vehicle that allows firefighters to combat fires from a safe distance.

System Overview



Project Timeline

Subsystem Designs and Testing (completed 9/11)	Integration of motor subsystem and MCU (completed 9/17)	Integration of Wi-Fi and iPhone App (to complete by 9/28)	Individual Subsystem Power Test (to complete by 10/15)	Frame Placement Integration (to complete by 11/2)	Integration Validation (to complete by 11/26)	Demo and Report (to complete by 12/5)

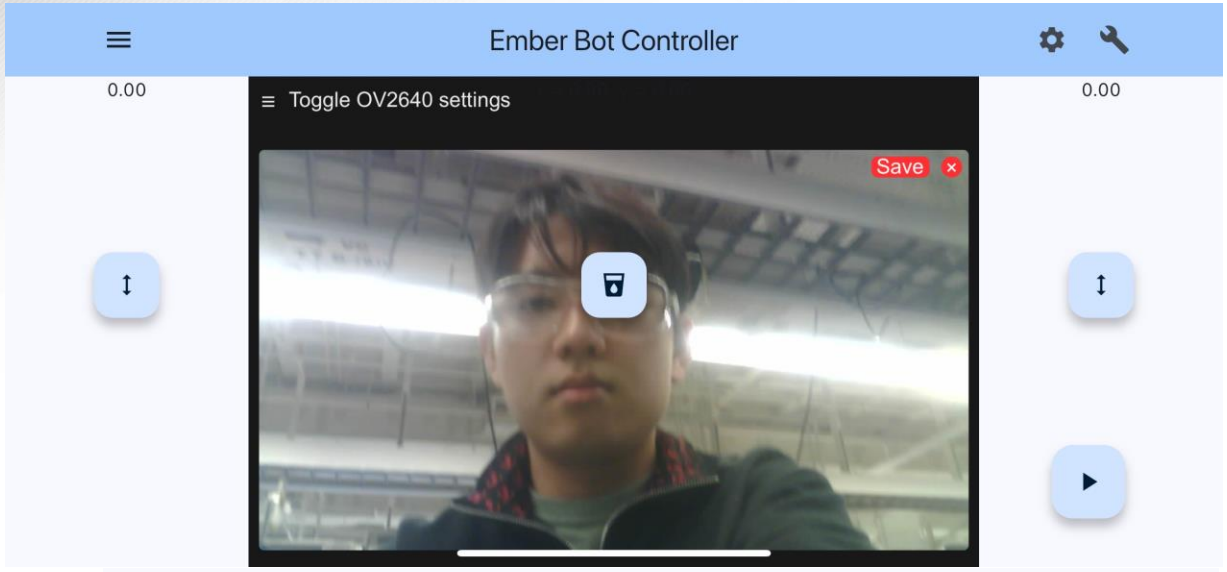
Microcontroller Subsystem

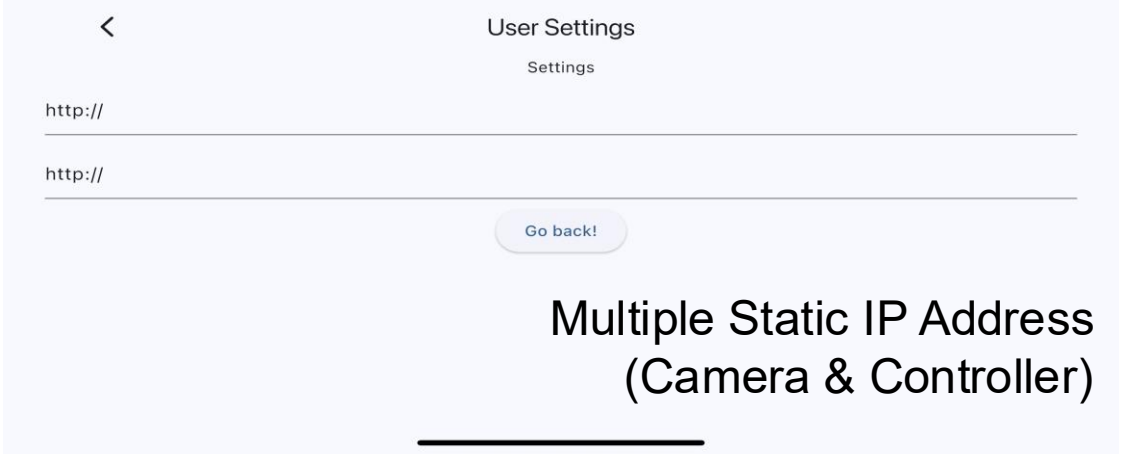
Jonathan Chen

Accomplishments since last update 22 hrs of effort	Ongoing progress/problems and plans until the next presentation
• Implemented Separate Web Server to deliver Real-time Coordinate Values • Configured multiple IP addresses for parallel data handling	• Starting Physical Testing calibration with Motors and Nozzle Systems • Ongoing Integration with Power PCBs and Testing – Completed by Next Review • Building HTML page to display values for users • On-Going Implementation with Direct Camera Functionality • Tested New Frame for Sensor – Validation Failed

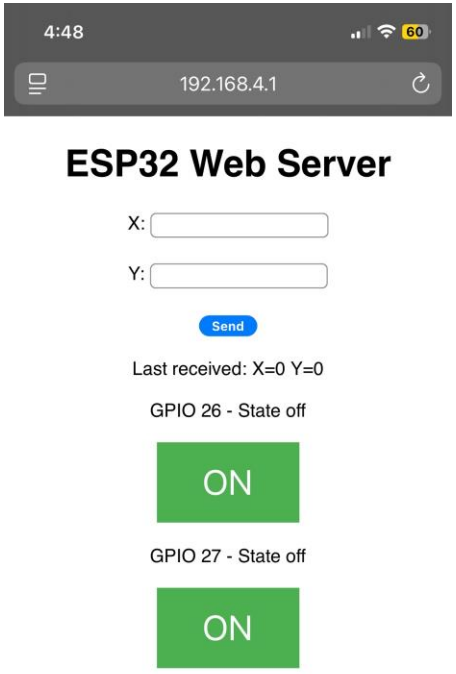
Microcontroller Subsystem

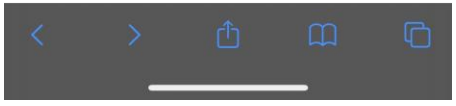
Jonathan Chen





Multiple Static IP Address
(Camera & Controller)





Microcontroller Subsystem

Jonathan Chen

```
Received JSON:
{"left_position":-5.666656494140625,"mid_x":0.0,"mid_y":0.0,"right_position":0.0}
Parsed coords: leftMotor=-6, rightMotor = 0, NozzleX=0, NozzleY=0
Received JSON:
{"left_position":-52.0,"mid_x":0.0,"mid_y":0.0,"right_position":0.0}
Parsed coords: leftMotor=-52, rightMotor = 0, NozzleX=0, NozzleY=0
Received JSON:
{"left_position":-46.33332824707031,"mid_x":0.0,"mid_y":0.0,"right_position":0.0}
Parsed coords: leftMotor=-46, rightMotor = 0, NozzleX=0, NozzleY=0
Current coords: leftMotor=-46, rightMotor = 0, NozzleX=0, NozzleY=0
No input received for 1 second. Resetting all values to 0.
Current coords: leftMotor=0, rightMotor = 0, NozzleX=0, NozzleY=0
```

Vehicle Operations & Water Pump Subsystem

Kevin Rivera

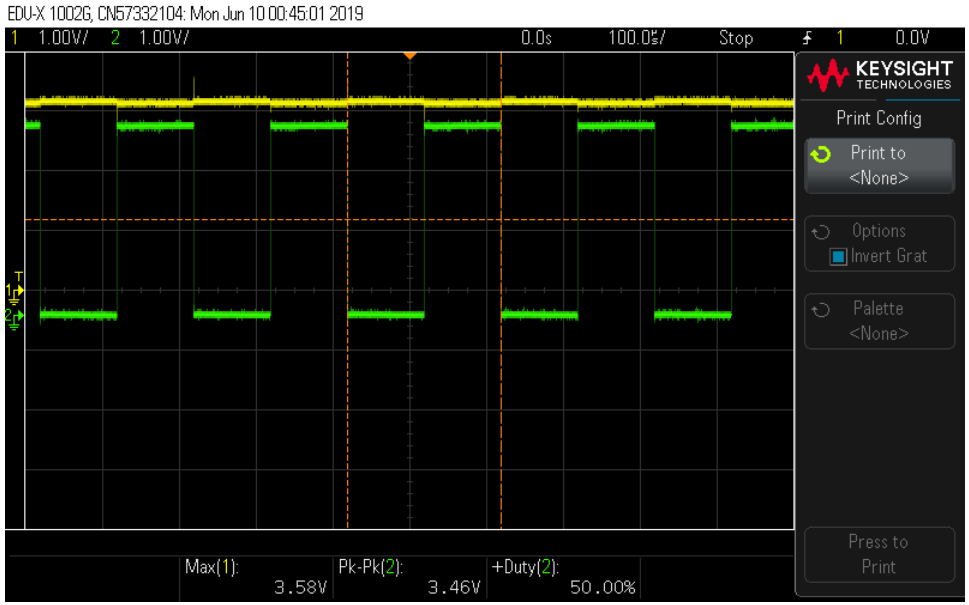
Accomplishments since last update 15 hrs of effort	Ongoing progress/problems and plans until the next presentation
• Prepared motors and water nozzle control for app integration	• Final adjustments to frame for housing PCBs/sensors • Integrate motors and water pump with PCB

Vehicle Operations & Water Pump Subsystem

Kevin Rivera

Input of –128 and 0

```
Output   Serial Monitor X
Message (Enter to send message to 'ESP32 Dev Module' on 'COM3')
Please enter two motor speeds separated by a space.
Values can only be in the range of -255 to 255.
Format: <rightMotor> <leftMotor>
Your right motor speed: 128
Your left motor speed: 0
Please enter new speeds:
```



Due to negative speed, direction pin set to high to go in reverse

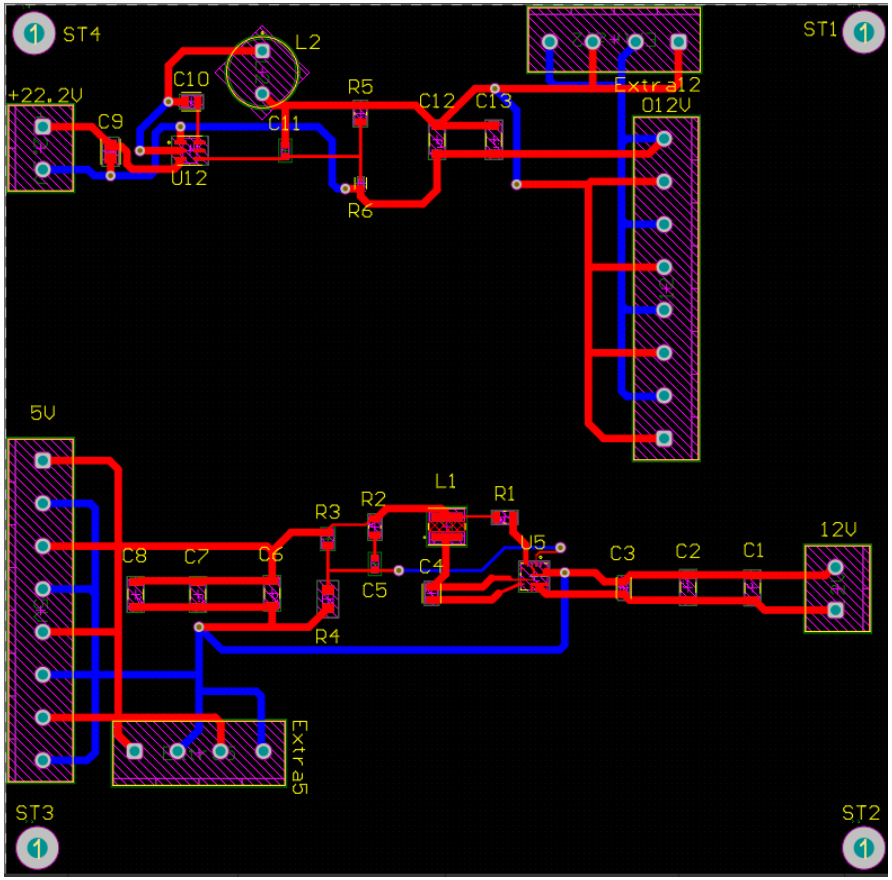
Power & Recharging

Nancy Ramirez Castillo

Accomplishments since last update 9 hrs of effort	Ongoing progress/problems and plans until the next presentation
- Ordered new 5V Buck Converter PCB, will be delivered EOW	- 5V Buck: Solder, E-Load test, and mounted onto frame - Perf board mounted for camera, servo motors, and LED light - Battery Percentage Implementation - Failed to do E-Load test on 12V Buck Converter

Power & Recharging

Nancy Ramirez Castillo

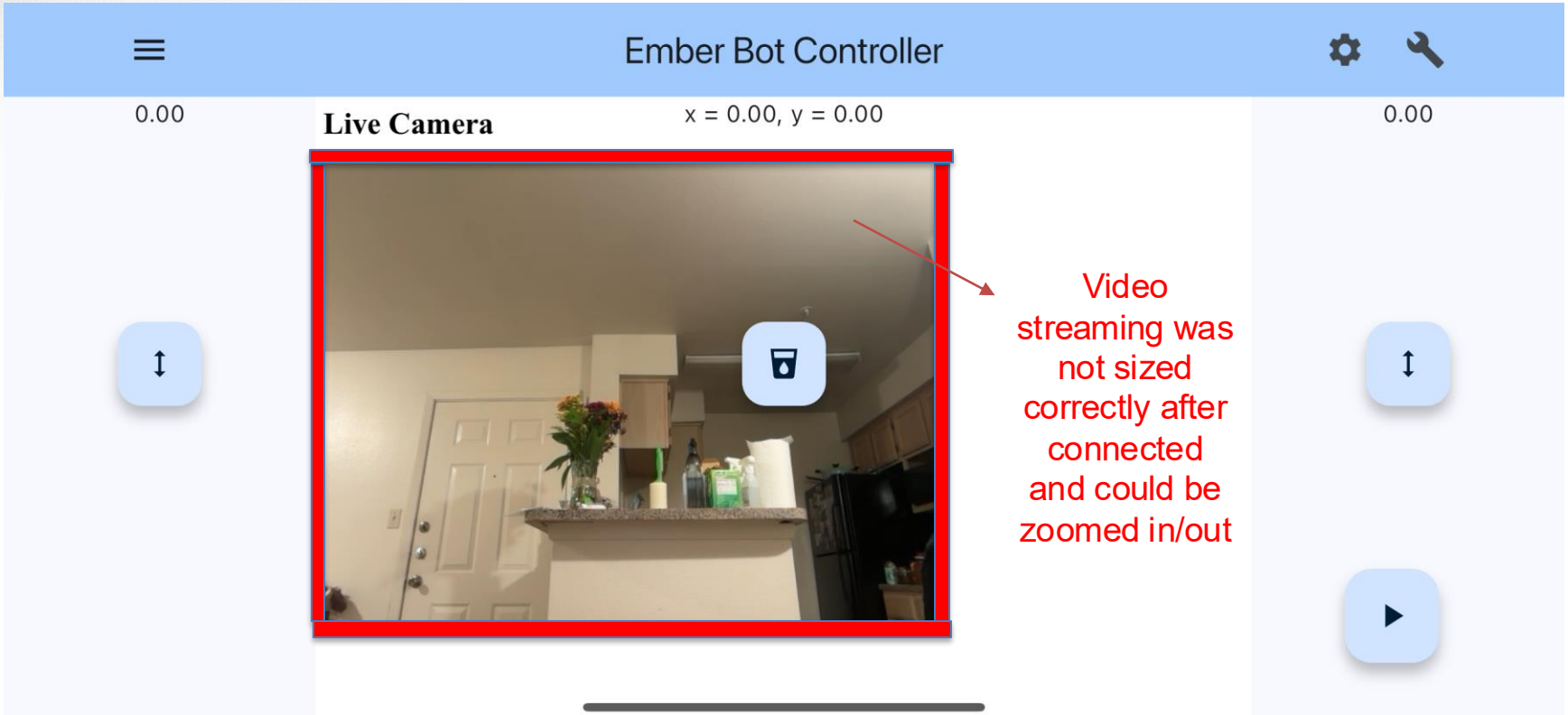


Mobile App Subsystem

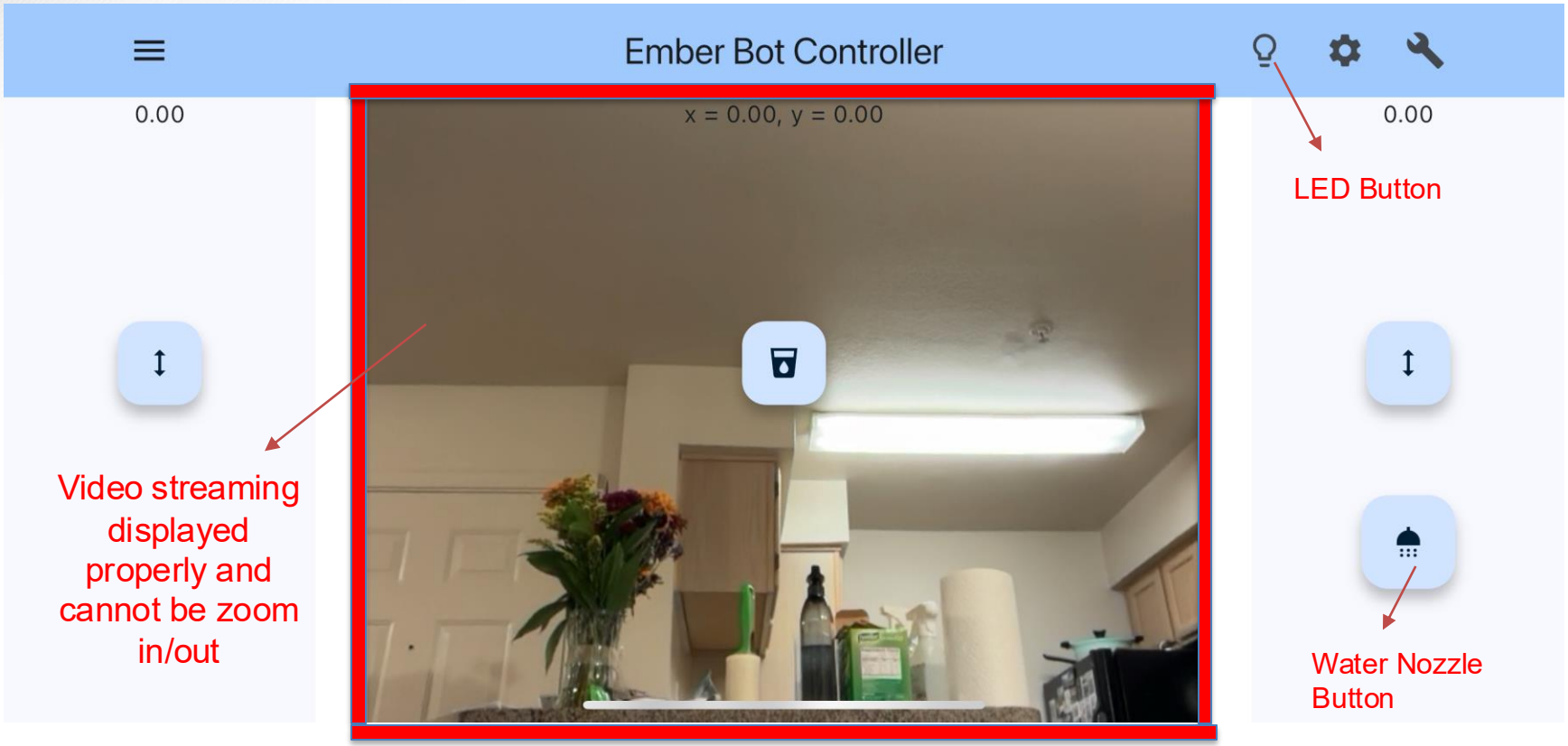
Yuwen Zheng

Accomplishments since last update 14 hrs of effort	Ongoing progress/problems and plans until the next presentation
- Changed IP address from hardcoded to two user input entries for testing purposes - Tested user coordinates integration with microcontroller subsystem - Video Display size in Mobile App is fixed - Added LED Button & Nozzle Button	- Test the communication of all buttons between the mobile app and ESP32 in the server - Use oscilloscope to test pin voltages of the ESP32 when the Mobile App is sending different signals - Test the coordinates and video streaming functionality simultaneously with ESP32

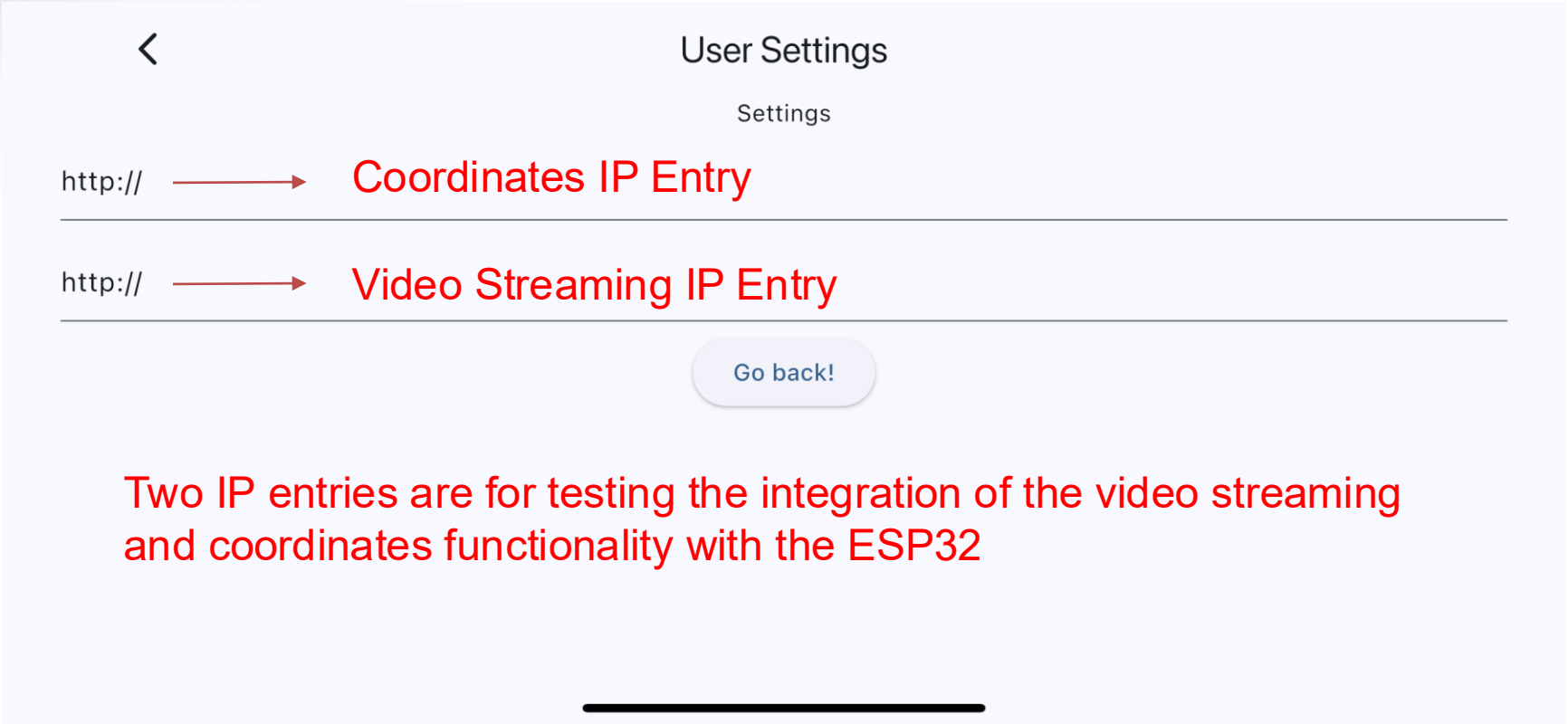
App Interface(Before)



App Interface(After)



IP Address Entries

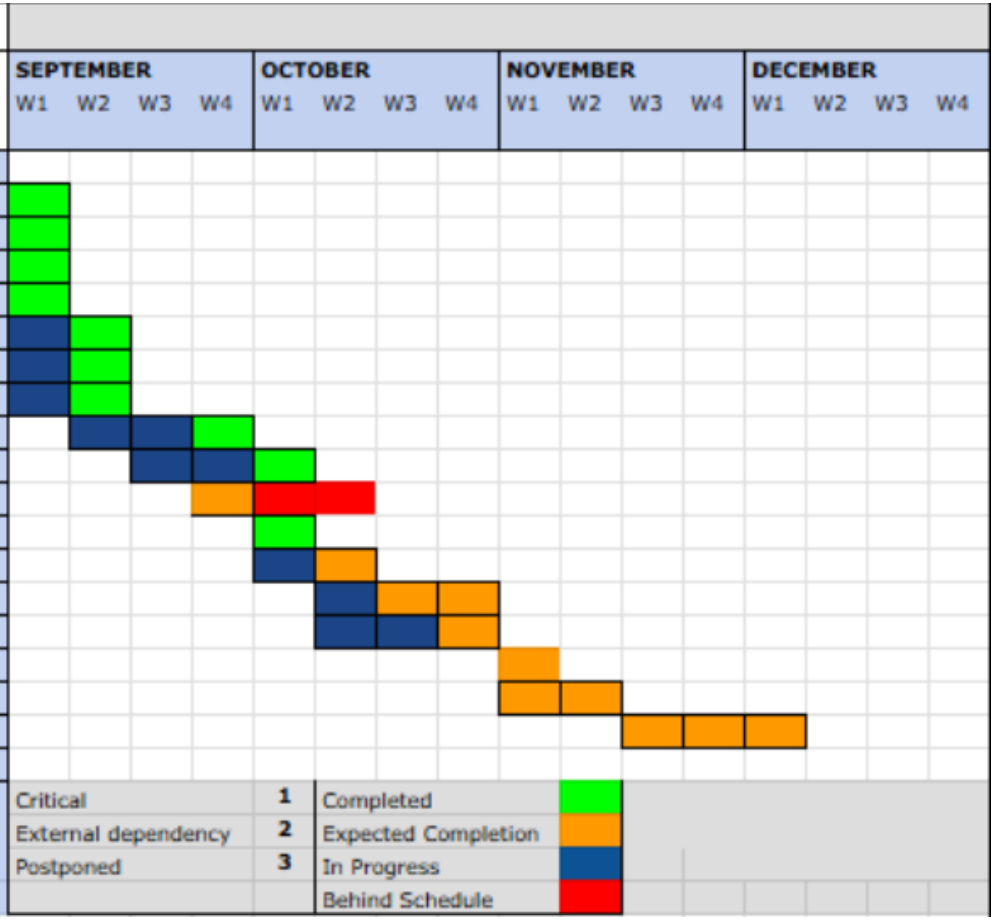


Two IP entries are for testing the integration of the video streaming and coordinates functionality with the ESP32

Execution Plan

Ember Bot Project Schedule

Deliverable/Task	Owner	Duration
Engineering Milestones		
Add IP Address Page	Jonathan	1 Week
Implement Video Streaming code	Yuwen	1 Week
Real Flame Testing	Jonathan	1 Week
Buck Converters Re-design	Nancy	1 Week
Integrate Video Streaming with ESP32	Jonathan	2 Weeks
Frame Re-design	Kevin	2 Weeks
Nozzle Calibration	Kevin	2 Weeks
ESP32 PCB Design	Nancy	2 Weeks
Motor Control via App	Kevin	2 Weeks
Order PCBs	Nancy	2 Weeks
Implement LED Button	Yuwen	1 Week
Fine Tune Buttons of UI	Yuwen	2 Weeks
Frame Installation with Water Tank Filled	Kevin	1 Week
Bind Mobile App with ESP32	Jonathan	2 Weeks
Implement App User Guide	Yuwen	1 Week
Test Mobile App on Different Devices	Yuwen	2 Weeks
Final Integration and Testing	All	3 Weeks
Annotations:		



Validation Plan

Test Name	Success Criteria	Methodology	Status
Real Flame Testing	Able to detect Lighter Flame 5 to 10 Feet at Distance	Use the IR sensor on a at a small controlled flame source (lighter) and record baseline data before lighting the flame. Conduct multiple trials at each distance and logging analog sensor output	Failed
Optimizing WiFi Connection	Connect via Wi-Fi Access Point 50-100 Feet Away	Attempt connecting to the ESP-32 Wi-Fi access point at varying distances and with/without obstacles inbetween.	Tested
Frame Installation	Frame does not dislodge from 10 minutes of use	Once installed, the robot will be moved via the motors and the frame must stay in place without dislodging for 10 minutes	Untested
Water Holding	Water Tank Does Not Leak	With the designed and printed water tank, it will be filled with water away from all electronics and be observed for any areas of leaks	Untested
Thermal Management	Thermal Management	Testing will be done in ambient room temperature (77 F) and recorded with an infrared temperature gun. Place all electronics in the frame and have them run at nominal operating states with the fan on. Temperature of each board will be tracked and recorded every 30 seconds for a total of 5 minutes.	Untested
Movement Speed With Weight	Ember Bot is able to move at 4mph with the estimated full weight of system	The equivalent of the total weight of all electronics/components will be placed on the robot. Verify that the motors are capable of moving the weighted robot at our desired speed by recording the total displacement in 10 seconds.	Untested
Water Nozzle Aim Calibration	Water Nozzle points to +-10 degrees of user input	Sketching a x-y plane at the recommended distance of 6ft and measuring the accuracy of this distance.	Untested
Video Streaming	Mobile app can receive and display video signals from ESP32	The mobile app will able to display video streaming from the camera on Ember Bot	Tested
Video Distance & Frame Test	Video Stream doesn't lose frames or quality as distance increase	Test the independent mobile integration with the camera at varying distances, aiming for 5 feet intervals until 50 feet or the distance of entire room	Tested
LED Button	Mobile app can turn LED On/Off	The LED on Ember Bot should turn on/off when user press the LED button in the app	Tested
Coordinate System	Motors and Nozzle are able to recieve coordinates given by mobile app	Using user inputs on the mobile app, ensure that the motors and nozzle operate as expected, and test under edge cases (High speeds and sudden changes of input)	Tested
App User Guide	App user page can be viewed on the mobile app	Let other group members walk through the user guide to check if it provides a clear instructions to users	Untested
Mobile App on Different Devices	The mobile app can be loaded on to at least 3 other devices	Load mobile app on other group member's devices to test if the app can function as expected on different devices	Untested
Power Boards Testing	Able to supply power under max load	Using different combinations of loads, two buck converters should keep a consistent output for all components needed	Untested
Battery Endurance Testing	Ember Bot can operate for an hour under continuous use and indicate when battery is low	Starting with full batteries, Ember Bot will run all different components for an hour and then will log how much battery power was used.	Untested
Motor and nozzle user test	Control the motors and nozzle movements with no more than a 2 second delay via the mobile app	After connection between the ESP32 and our mobile app is made, have a user send inputs from the app to control the motors and servo motors. Track how long it takes for these actions to take place.	Untested
Electonics Isolation	There is no risk of water damaging the PCB, motors, and other electronics in the bottom layer of the robot	Connect the pieces of the frame and pour 1 gallon of water over it for a short time and once done check below the frame to see if water leaked	Tested
Servo Movements	Servos can successfuly move and point to a certain point	Attatch a laser on the end of the servo configuration to point to a x-y grid. Input x and y coordinates and verify that the laser is pointing to the correct point	Tested
Water Nozzle Movement	Water pump system successfully attatched to the servo system	Connect the servos with the water nozzle and verify that the range fits with the coordinate system verified in the servos movement test	Tested
Vehicle Movement	Both motors can be controlled independetly via the motor driver	Input control signals can control each motor independetly to go forward, backwards, turn left, turn right, and turn 180 degrees.	Tested
12V Buck Simulation	Steady state waveform and outputing a max of 12.6V	Using LTSpice/Altium to select components and verify power rail. Using a higher voltage to compensate for real world applications which will decrease the output voltage	Tested
5V Buck Simulation	Steady state waveform and outputing a max of 5.5V	Using LTSpice/Altium to select components and verify power rail. Using a higher voltage to compensate for real world applications which will decrease the output voltage	Tested
E-Load Testing	Maintains a steady 12V ± 5% and 5V ± 5% output under varying load conditions up to 2A.	Using an E-load in constant current mode and vary the load from 0A to 2A, monitor the output voltage and ripple using an oscilloscope to ensure stable operation at full load.	Untested

Dwight Look College of ENGINEERING
TEXAS A&M UNIVERSITY

Questions?

Thank You!
Ember Bot

Jonathan Chen, Kevin Rivera, Nancy Ramirez Castillo, Yuwen Zheng

Sponsor: Kevin Nowka

TA: Roman Venegas