Line Following Robot

Frank Bruno James Ihrig

University of Central Florida University of Central Florida  
4000 Central Florida Blvd 4000 Central Florida Blvd

Orlando, Florida, 32816 Orlando, Florida, 32816

fbruno13@knights.ucf.edu JEIhrig@gmail.com

Abstract

The abstract will talk about the project as a whole in no more than 150 words.

# Introduction (.5 to 1 page) F

This is the introduction section. It should talk about our project in general and the goals, motivation, and real life applications of this project.

# Related Work (1 – 2 pages) F

This is the related work section. It should talk about the work being done that relates to this project, such as, other designs for line following robots, learning techniques, and controller methods.

# Method (2-4 total pages)

This section should talk about what we are using to make this project.

Hardware (1 page) F

This section discusses the hardware used to make the line following robot. The focus of this section is on the design decisions made while constructing the robot such as what parts were used in creation of the robot including sensors, microcontroller (MCU), Wireless Command and Reporting, and Motors. It will also cover some of the hardware limitations and the cost of the robot.

PID controller (1 page) J

This section should talk about the PID controller and how it works. It should include Explanation of the controller and terms include pseudo-code and the control system loop. Explain how we are calculating error and how the manual tuning process works for us. As well as, the values of P, I, and D we used for our default values that yielded good results.

Learning PID values (0.5 – 1 page) J

This section should talk about the learning technique used to find PID values.

# Evaluation (2 total pages)

Performance based on speed being 75% and the total accuracy being 25%. So, the speed will take priority over the error, but still allow for more accurate values to overcome the speed.

Comparison between Controllers (1 page) F

A PID controller to a P, PI, and PD controller will be tested with similar values. This will show the benefit to having each of the terms and how they affect the performance.

|  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- |
| Run | P | I | D | Error | Time |
| 1 | 20 | 0 | 0 |  |  |
| 2 | 20 | 0 | 10 |  |  |
| 3 | 20 | 0 | 15 |  |  |
| 4 | 20 | 0.05 | 0 |  |  |
| 5 | 20 | 0.05 | 10 |  |  |
| 6 | 20 | 0.05 | 15 |  |  |
| 7 | 20 | 0.1 | 0 |  |  |
| 8 | 20 | 0.1 | 10 |  |  |
| 9 | 20 | 0.1 | 15 |  |  |
| 10 | 25 | 0 | 0 |  |  |
| 11 | 25 | 0 | 10 |  |  |
| 12 | 25 | 0 | 15 |  |  |
| 13 | 25 | 0.05 | 0 |  |  |
| 14 | 25 | 0.05 | 10 |  |  |
| 15 | 25 | 0.05 | 15 |  |  |
| 16 | 25 | 0.1 | 0 |  |  |
| 17 | 25 | 0.1 | 10 |  |  |
| 18 | 25 | 0.1 | 15 |  |  |
| 19 | 30 | 0 | 0 |  |  |
| 20 | 30 | 0 | 10 |  |  |
| 21 | 30 | 0 | 15 |  |  |
| 22 | 30 | 0.05 | 0 |  |  |
| 23 | 30 | 0.05 | 10 |  |  |
| 24 | 30 | 0.05 | 15 |  |  |
| 25 | 30 | 0.1 | 0 |  |  |
| 26 | 30 | 0.1 | 10 |  |  |
| 27 | 30 | 0.1 | 15 |  |  |

Comparison of PID Values (1 page) J

The PID values found in the method section will be tested against the learned PID values. This will show the benefit of the learned PID values over the user set values.

# Conclusion (.5 – 1 page) F J

This section should be concluding remarks about the project talking about the strengths, weaknesses, and possible improvements.

# References

Pololu Baby Orangutan B Users Guide. Available from http://www.pololu.com/docs/pdf/0J14/baby\_orangutan\_b.pdf.

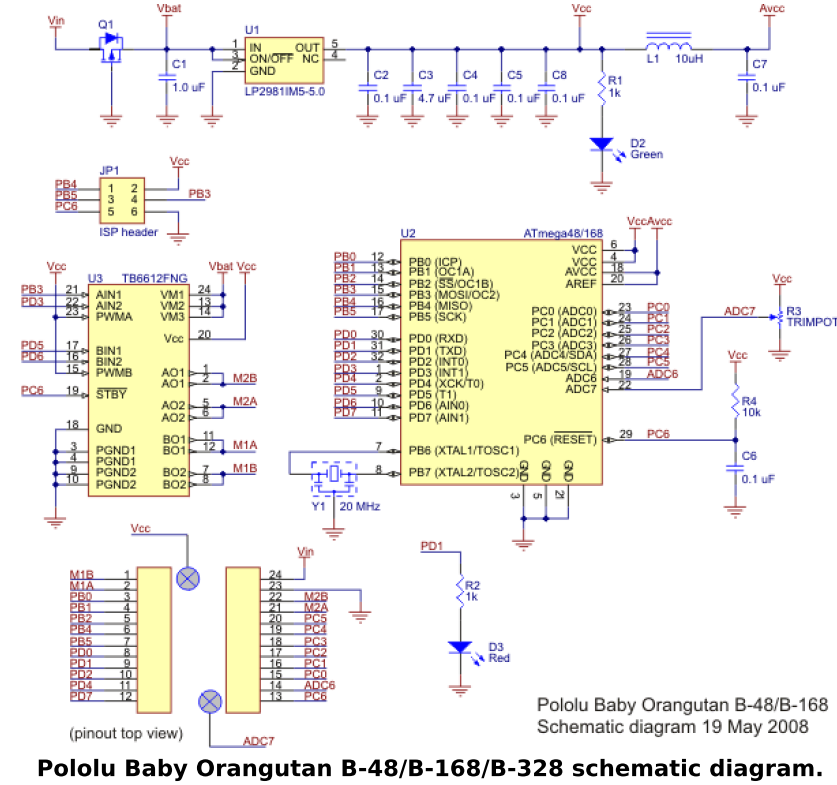


Figure - Pololu Baby Orangutan B-328 Schematic diagram (Pololu Baby Orangutan B Users Guide)