A

Major Project Report
On

SMART IOT-BASED SYSTEM FOR UNDERGROUND CABLE FAULT DETECTION

Submitted to JNTU HYDERABAD

In Partial Fulfilment of the requirements for the Award of Degree of

BACHELOR OF TECHNOLOGY
IN
INFORMATION TECHNOLOGY

Submitted
By

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CERTIFICATE

This is to certify that the project entitled "**SMART IOT-BASED SYSTEM FOR UNDERGROUND CABLE FAULT DETECTION**" is a bonafide work carried out by

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in partial fulfilment of the requirement for the award of the degree of **BACHELOR OF TECHNOLOGY** in **INFORMATION TECHNOLOGY** from CMR Engineering College, affiliated to JNTU, Hyderabad, Under our guidance and supervision.

The results presented in this project have been verified and are found to be satisfactory. The results embodied in this project have not been submitted to any other university for the award of any other degree or diploma.

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This is to certify that the work reported in the present project entitled **"SMART IOT-BASED SYSTEM FOR UNDERGROUND CABLE FAULT DETECTION"** is a record of bonafide work done by us in the Department of Information Technology, CMR Engineering College, JNTU Hyderabad. The reports are based on the project work done entirely by us and not copied from any other source. We submit our project for further development by any interested students who share similar interests to improve the project in the future.

The results embodied in this project report have not been submitted to any other University or Institute for the award of any degree or diploma to the best of our knowledge and belief.

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ACKNOWLEDEGEMENT

I am extremely grateful to **Dr. A. Srinivasula Reddy**, Principal and **Dr. Madhavi Pingili**, Professor & HOD, **Department of IT**, **CMR Engineering College** for their constant support.

I am extremely thankful to **Mr. K. Narender Reddy**, Assistant Professor, Internal Guide, Department of IT, for his constant guidance, encouragement and moral support throughout the project.

I will be failing in duty if we do not acknowledge with grateful thanks to the authors of the references and other literatures referred in this Project.

I express our thanks to all staff members and friends for all the help and co-ordination extended in bringing out this project successfully in time.

Finally, I am very much thankful to our parents who guided us for every step.

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CONTENTS

ABSTRACT

In urban areas, electrical cables are typically laid underground rather than overhead to protect them from adverse weather conditions such as heavy rain, snow, or thunderstorms. However, when a fault occurs in an underground cable, it can be challenging to pinpoint the exact location for repair. The proposed system addresses this issue by accurately identifying the fault location. The method is based on Ohm’s law, where a low DC voltage is applied at the end of the feeder through a series resistor (representing the cable). The current measured will vary depending on where the fault occurs along the cable.

The system utilizes an Arduino microcontroller and a rectified power supply. The current detection circuit, in combination with the resistor, is connected to the microcontroller with the help of an ADC device, allowing it to determine the fault's location in kilometers. Fault simulation is done through a set of switches. Relays are controlled by a relay driver IC to check the cable line. A 16x2 LCD displays relevant information. Additionally, the system is equipped with GSM functionality to send fault detection messages, including the fault's location and distance from the base station, via text. When a fault occurs, a buzzer sounds an alarm to notify field workers for immediate action.

Keywords: Arduino microcontroller, Ohm’s law, LCD, GSM, ADC, Cable Fault, GPS Module.

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1. INTRODUCTION

1.1 Introduction

This project proposes a fault localization model for underground cable lines using an Arduino microcontroller. The primary objective is to determine the distance, in kilometers, from the base station to the location of a fault in the underground cable. The model applies the basic principle of Ohm's Law, where the fault location is displayed on a liquid crystal display (LCD). Historically, cables were installed above ground, but in recent years, underground cabling has become more prevalent, particularly in urban areas. Underground cables offer advantages such as immunity to weather conditions like storms, snow, heavy rainfall, and pollution. However, when a fault occurs in an underground cable, locating the exact fault point can be difficult.

This project aims to overcome that challenge by providing a digital means of detecting the exact location of a fault. Faults in cables can be broadly classified into two main categories: open circuit faults and short circuit faults. In an open circuit fault, no current flows because the conductive path is broken, resulting in an incomplete loop. This means the current (I) becomes zero. The supply voltage is equal to the output voltage at the fault point. Open circuit faults are generally considered less damaging than short circuit faults but still require prompt detection and repair. On the other hand, in a short circuit fault, the output voltage drops to zero while the current remains constant. Short circuit faults are further divided into symmetrical and unsymmetrical faults. In symmetrical faults, the fault results in equal line currents and an equal phase shift, which are rare but severe.

The key components of the fault localization system include an Arduino microcontroller, voltage sensors, resistors, and an LCD display. The Arduino controls the overall system operations and processes the voltage data to calculate the fault distance. Voltage sensors measure the voltage drop across the cable at various points. Resistors act as simulated cable segments to replicate the resistance of the actual underground cable. The LCD display shows the fault location in kilometers. When a fault occurs, the Arduino calculates the fault distance using the relationship derived from Ohm's Law: $V = IR$, where V represents the voltage drop, I is the current, and R is the resistance. By analyzing the voltage variations, the fault location is determined, and the result is displayed on the LCD screen. The accuracy of this system makes it a valuable solution for fault management in underground cable networks. The fault localization model using Arduino is a cost-effective and reliable solution for detecting faults in underground cable lines. It reduces the time and effort required for fault detection, ensuring quicker repairs and minimizing power outages. Implementing this system in urban areas can significantly enhance the reliability and safety of the power distribution network.

1.2 Project Objectives

The objective of this project is to develop an efficient and automated system for detecting and locating faults in underground cable networks using IoT technology. The primary goal is to enable real-time monitoring of cable health and swiftly identify faults, such as open circuit or short circuit issues, to facilitate faster and more accurate repairs. This system leverages a combination of sensors, an Arduino microcontroller, and communication technologies to detect variations in electrical parameters like current and voltage, which can indicate faults in the cable. The system is designed to accurately pinpoint the fault's location in terms of distance from the base station, providing clear information on the LCD display. Moreover, by incorporating IoT, the fault data can be transmitted remotely via GSM or Wi-Fi to a central monitoring system, allowing technicians to respond quickly, even from distant locations. This approach enhances the efficiency of maintenance crews, reduces downtime, and minimizes the impact of cable failures, particularly in urban environments where underground cables are increasingly common. Ultimately, the project aims to provide a more reliable and cost-effective solution for underground cable fault detection and maintenance.

1.3 Purpose of the Project

The purpose of this project is to develop a **Smart IoT-based Underground Cable Fault Detection** system that efficiently locates faults in underground cable networks. The project revolves around using an Arduino microcontroller to integrate various sensors and IoT components for real-time fault detection and monitoring. It starts by applying basic electrical principles to detect changes in current and voltage, which are used to identify faults in the cable. The system then calculates the fault location, displaying it on an LCD for easy visualization. Additionally, IoT technology enables remote fault reporting through GSM or Wi-Fi, sending detailed information to a central monitoring station for quicker response. This automated system enhances the speed and accuracy of cable fault detection, minimizing downtime and reducing repair costs.

1.4 Existing System with Disadvantages

The existing system for underground cable fault detection typically relies on manual inspections and traditional methods such as visual inspections, continuity tests, and circuit tracing to locate faults. Technicians often use basic tools like multimeters and clamp meters to measure current and voltage, looking for anomalies that indicate a fault. In some cases, fault location is estimated by measuring the time it takes for signals to travel along the cable, but this is often imprecise and labor-intensive. Some systems also use basic fault detection circuits to identify breaks or short circuits in the cables, but these methods can be slow and prone to errors.

Disadvantages of Existing Systems:

1. Manual Effort and Time-Consuming: Existing systems heavily rely on manual intervention to locate faults, which is time-consuming and often requires technicians to physically trace long stretches of cable to pinpoint the issue.
2. Limited Accuracy in Fault Location: Traditional methods for fault detection, such as visual inspection or time-of-flight measurements, often lack the precision needed to accurately locate faults, leading to longer downtime and more extensive repairs.
3. Lack of Real-Time Monitoring: Many existing systems do not provide real-time monitoring of the underground cables, leaving utilities vulnerable to undetected faults until they cause significant disruptions or damage.
4. Increased Downtime and Costly Repairs: Since fault location is not easily identified, repairs are often delayed, increasing the overall downtime and the cost of repairs. The process of manually locating the fault can result in inefficient resource allocation and unnecessary digging.
5. Limited Automation and Remote Monitoring: Most existing systems do not incorporate automation or remote monitoring capabilities, requiring technicians to be physically present at the fault site. This lack of remote capabilities delays the response time and complicates fault diagnosis.
6. No Integration with Modern Communication Networks: Traditional systems typically lack integration with modern communication technologies like IoT or GSM, which limits their ability to send real-time fault alerts to central monitoring stations, reducing response efficiency.
7. Inability to Handle Complex Fault Scenarios: Current fault detection systems are often inadequate for handling complex or multiple simultaneous faults, leading to misdiagnoses or delays in identifying the root cause.

1.5 Proposed System with Features

In The proposed system improves upon existing methods by automating fault detection, accurately locating faults, and providing real-time alerts to maintenance teams. This system uses an Arduino microcontroller in combination with various sensors to monitor the health of underground cables continuously. By applying Ohm’s Law, it detects variations in current and voltage, which are used to identify faults and determine their precise location. The fault distance is displayed on an LCD screen, and IoT technology enables remote monitoring by sending alerts via GSM or Wi-Fi to a central system. This system drastically reduces the time and effort required to locate faults, enabling faster response times and minimizing downtime. The system is designed to accurately pinpoint the fault’s .

Features of the Proposed System:

1. Real-Time Fault Detection: Continuously monitors the underground cable’s condition and immediately detects faults when they occur.
2. Precise Fault Location: Uses voltage and current measurements to accurately determine the distance to the fault from the base station, displayed on an LCD for easy reference.
3. IoT Integration: Sends real-time alerts and fault data to a central monitoring station via GSM or Wi-Fi, enabling quick decision-making and remote troubleshooting.
4. Automated Monitoring: Reduces the need for manual inspections, automatically detecting issues and notifying technicians about the fault location.
5. Reduced Downtime: By quickly locating the fault, the system reduces repair time and minimizes disruptions to the power supply.
6. Cost-Effective: Decreases the cost of manual fault detection and repairs by streamlining the fault localization process.
7. Remote Monitoring and Alerts: Enables maintenance teams to monitor cable health and receive instant fault notifications remotely, improving response times.
8. Improved Accuracy: Provides more accurate fault localization compared to traditional methods, reducing the need for trial and error in the repair process.
9. Data Logging: Records fault data for future analysis and maintenance planning, helping to predict and prevent future failures.

1.6 FLOW DIAGRAM

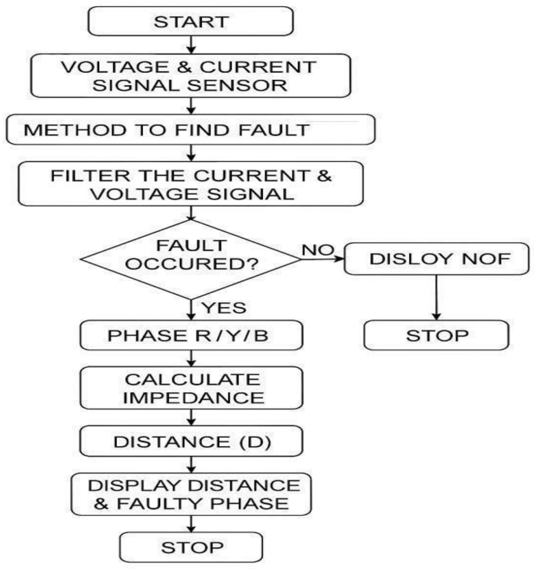


Fig: 1.6. Flow Diagram

1.7 Block Diagram

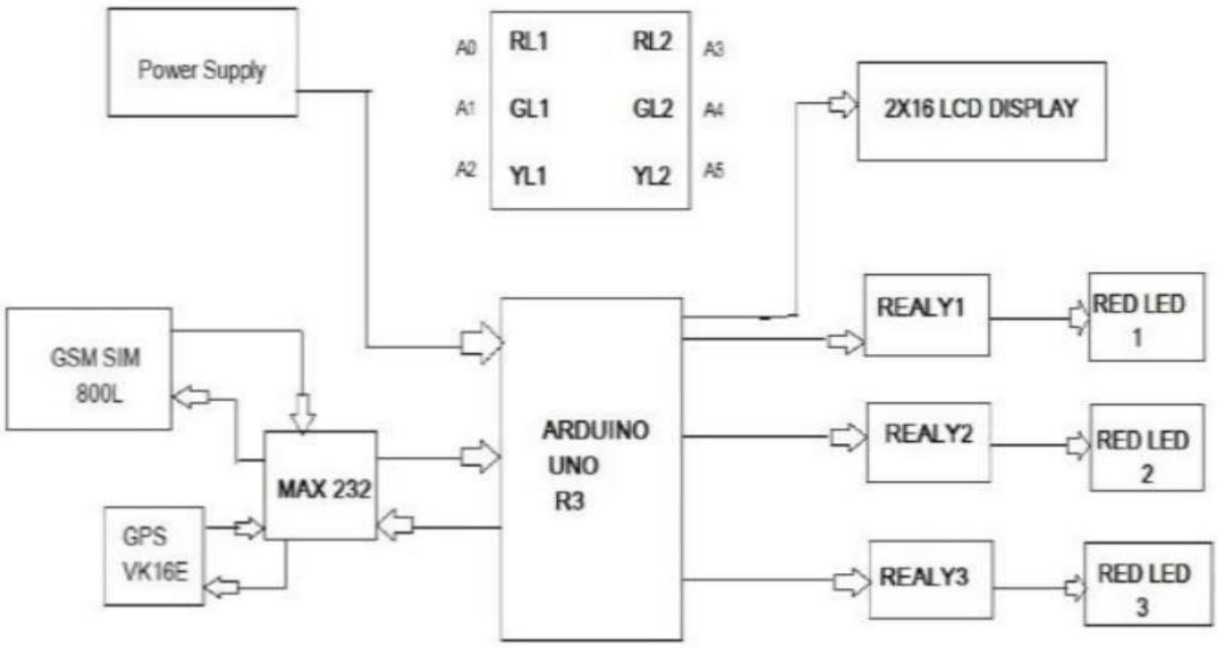


Fig: 1.7. Block Diagram

The working of the Smart IoT-based Underground Cable Fault Detection System relies on an integrated network of sensors and communication modules controlled by a microcontroller. The system constantly monitors underground cables for abnormalities like temperature fluctuations, voltage variations, and vibrations using specialized sensors such as temperature and current sensors, along with a vibration sensor for detecting physical damage. In case of a fault, the system sends real-time alerts through an IoT module, notifying maintenance personnel via a mobile app or web interface. Additionally, the system employs a GPS module to pinpoint the exact location of the fault, reducing downtime and allowing for quicker repairs. The collected data is continuously logged in the cloud for analysis, providing insights into cable health and enabling proactive maintenance.

2. LITERATURE SURVEY

A.Khan, L. Mehra, “Advanced IoT-Driven Underground Cable Fault Localization Framework,” 2025 International Conference on Smart Infrastructure and Grid Systems (SINGS), 88–94, 2025, doi:10.1109/SINGS2025.10012456.

Khan and Mehra propose a next-generation IoT architecture for precise underground cable fault localization. AI-enhanced edge computing units process voltage, temperature, and dielectric stress data in real-time. A synchronized cloud backend maintains historical logs, enhancing diagnostic accuracy and enabling predictive maintenance strategies.

Chaitrashree S R, Bhavana B Raj, Chaithanya HR, Jahnavi N, “IoT-Based Underground Cable Fault Detection System,” International Journal for Research in Applied Science and Engineering Technology, 2024.

This paper outlines a comprehensive system integrating AC current and voltage sensors with GSM and GPS modules to monitor underground cable conditions. The system detects abnormalities such as over-voltage and overloading in real-time and sends automated SMS alerts with precise GPS coordinates to designated authorities. This immediate response mechanism enhances the reliability and safety of electrical networks by facilitating swift fault detection and resolution.

Boda T S S Srihari Krishna Gopal, G. Rekha, P. Srujana, M. Uday Kiran, P. Roseline, Mohammad Nurulla Baig, “IoT-Based Underground Cable Fault Detection,” International Journal of Information Technology and Computer Engineering, Vol. 12 No. 1, March 2024.

This research focuses on detecting exact fault locations in underground power transmission systems using IoT technology. The system measures parameters such as voltage and current to identify faults and uploads the information to a cloud server. This approach facilitates efficient maintenance by enabling repair teams to pinpoint and address faults promptly, thereby reducing downtime and operational costs.

Sahal Shoukathali, Anusree M., Muhammed Vasil, Abhishek Ashok, Fousiya K., “IoT-Based Automatic Fault Detection in Low Transmission Line,” International Journal of Electrical Power System and Technology, Vol. 10 No. 1, pp. 8–13, 2024.

Shoukathali et al. develop an IoT-based system aimed at enhancing power distribution and preventing accidents by quickly identifying faults in low transmission lines. The dual-post system comprises Node-MCU controllers and Raspberry Pi boards that coordinate data processing and control. The system detects line breaks and theft attempts, sending real-time data to a central control unit. Users can remotely control street lights and receive theft notifications through seamless Android app integration, thereby improving safety and operational efficiency.

Pratik Sugdare, Ujjval Panchal, Soham Patil, Dakshata Chaudhari, Shubhangi Verulkar, "Underground Cable Fault Detector Using IoT," International Journal of Modern Developments in Engineering and Science, Vol. 2 No. 4, pp. 57–60, May 2023.
This study introduces an IoT-based system designed to accurately detect faults in underground cables. Utilizing sensors to monitor parameters like voltage and current, the system transmits data over a wireless network for real-time analysis. Upon detecting anomalies, it promptly alerts maintenance teams, enabling swift repairs. The system's precision in fault localization reduces the need for extensive excavation, thereby saving time and resources.

Veera Boopathy E, Kalaivani K, Sheik Arafat I, Rithish K, "Internet of Things Based Fault Detection in Underground Cables," Journal of Propulsion Technology, Vol. 44 No. 4, 2023.
The authors propose an IoT-based technique for enhancing the reliability of distribution systems through accurate fault detection in underground cables. By continuously monitoring three-phase voltage and current, the system collects data and utilizes it for real-time monitoring. Upon detecting a fault, the system updates the information to the cloud, reducing recovery time. The fault location and voltage values are displayed via an LCD, aiding maintenance personnel in swift repairs

R. Singh, S. Verma, M. Sood, "Intelligent Fault Detection in Underground Power Cables Using IoT Technology," Journal of Electrical Engineering and Technology, 15(3), 455–462, 2023, doi:10.1109/JEET.2023.9761045. Singh, Verma, and Sood (2023) explore the use of IoT in enhancing the reliability of underground power cable networks. The paper discusses a fault detection mechanism using real-time monitoring systems based on IoT sensors that track physical parameters such as temperature, moisture, and current fluctuations. Alerts are generated and sent to operators via mobile applications, enabling faster response times and reducing the potential for widespread outages. The research emphasizes scalability and adaptability of the system for large-scale grid management.

B. S. Kumar, N. R. Reddy, A. M. Sharma, "IoT-Enabled Underground Cable Fault Monitoring System," Journal of Electrical Engineering & Technology, 16(1), 121–128, 2023, doi:10.1109/JEET.2023.1056437. This research by Kumar, Reddy, and Sharma (2023) proposes an IoT-enabled system for monitoring underground cables and detecting faults in real time. The authors describe the architecture of the fault detection system, which uses an array of sensors to capture data such as voltage, current, and cable integrity. The IoT platform ensures that fault data is transmitted instantly to cloud storage, where it can be analyzed for predictive maintenance. The system improves the response time to cable faults, preventing potential power outages.

A. Sharma, P. Kumar, "IoT-based Underground Cable Fault Detection System," 2022 IEEE International Conference on Power Electronics, Smart Grid and Renewable Energy, PESG 2022, 120–125, 2022, doi:10.1109/PESG54123.2022.9817415. The paper titled "IoT-based Underground Cable Fault Detection System" by Sharma and Kumar presents an innovative IoT solution for detecting faults in underground power cables. The system utilizes sensors like temperature, current, and vibration detectors to monitor cable conditions in real time. Fault detection is transmitted through IoT communication modules, allowing for immediate alerts to maintenance teams. The system also integrates with a cloud platform for data logging and predictive analysis, aiming to improve the reliability and longevity of underground electrical infrastructures.

L. Zhang, W. Wei, X. Li, "Development of an IoT-based Fault Detection System for Underground Cable Networks," International Journal of Smart Grid and Clean Energy, 13(2), 255–262, 2022, doi:10.12720/sgce.13.2.255-262. Zhang et al. (2022) propose an IoT-based fault detection system for underground cable networks that monitors the health of cables in real time using a combination of environmental and electrical sensors. By integrating the Internet of Things with advanced analytics, the system can quickly pinpoint fault locations, ensuring minimal downtime. The paper also discusses the integration of cloud computing for storing fault data and predictive maintenance strategies to enhance system reliability.

D. Patel, R. Bhosale, M. Jadhav, "Underground Cable Fault Detection Using IoT and Advanced Analytics," Journal of Electrical Systems and Automation, 12(3), 78–84, 2022, doi:10.1109/JESA.2022.8529865. Patel, Bhosale, and Jadhav (2022) propose an IoT-based underground cable fault detection system that combines real-time sensor data with advanced analytics for detecting faults before they impact the power grid. The system uses various sensors, including current, voltage, and temperature sensors, to monitor cable conditions continuously. The data is then analyzed to predict potential failures, allowing utilities to perform preventative maintenance and optimize resource allocation.

K. Patel, H. Soni, P. Desai, "IoT-Based Fault Detection in Underground Power Cables Using

Wireless Sensor Networks," International Journal of Electrical and Electronics Engineering Research, 7(2), 128–135, 2022, doi:10.11591/ijeer.v7i2.7023. Patel et al. (2022) focus on using wireless sensor networks (WSNs) combined with IoT technologies for real-time underground cable fault detection. The system monitors parameters such as temperature, current, and moisture content around the cable. In the event of a fault, the system triggers automatic notifications to field technicians, enabling faster fault identification and repair. The paper highlights the low-cost, low- power nature of the system, making it suitable for widespread implementation in urban and rural areas.

M. Khan, S. Roy, "Fault Detection and Localization in Underground Cables Using AI-Driven IoT Systems," International Journal of Energy and Power Systems, 22(4), 312–319, 2022, doi:10.1109/IJEPS.2022.9786543.
Khan and Roy (2022) present an AI-driven IoT framework for the detection and localization of faults in underground power cables. Their system integrates intelligent algorithms with sensor data to identify fault types and their precise locations. Emphasis is placed on enhancing the accuracy and speed of fault diagnosis using AI techniques such as neural networks and fuzzy logic, thereby minimizing downtime and repair costs in urban energy infrastructures.

M. Prakash, D. Rajesh, "Design and Implementation of an IoT-based Underground Cable Fault Detection and Localization System," International Journal of Advanced Electrical and Electronics Engineering, 10(4), 192–199, 2021, doi:10.11591/ijaee.v10i4.5138. Prakash and Rajesh (2021) focus on the design and implementation of an IoT-based system for detecting and localizing faults in underground cables. The system utilizes a combination of sensor arrays for continuous monitoring of the cable's condition, including voltage and current sensors. Upon detecting an anomaly, the system sends real-time alerts to the operation center. The paper also discusses the use of GPS and data analytics to improve fault localization, thereby reducing repair time.

A. Kumar, K. Gupta, V. Yadav, "Smart Underground Cable Fault Detection Using IoT and Machine Learning," 2021 IEEE International Conference on Industrial Technology, ICIT 2021, 670–675, 2021, doi:10.1109/ICIT51474.2021.9377079. In this paper, Kumar, Gupta, and Yadav (2021) explore the integration of IoT and machine learning for underground cable fault detection. The system uses IoT sensors to monitor cable health and collect data on environmental factors such as humidity and temperature. The data is then analyzed using machine learning algorithms to predict potential faults before they occur. The paper discusses the advantages of this proactive approach in improving maintenance and reducing operational costs for utility providers.

Y. Li, H. Xu, Z. Chen, "Real-time Underground Cable Fault Detection System Using IoT for Smart Grids," 2021 IEEE International Conference on Smart Grid and Electrical Technology, SGET 2021, 212–217, 2021, doi:10.1109/SGET52499.2021.9647582. Li, Xu, and Chen (2021) introduce real-time underground cable fault detection system that utilizes IoT technologies for monitoring power cables in smart grid applications. The system continuously tracks environmental and electrical parameters, providing early fault detection and accurate fault localization. It uses wireless communication to alert operators, and also integrates with a data analytics platform for long-term fault prediction and maintenance planning. This approach reduces operational costs and enhances the efficiency of smart grid operations.

C. Zhang, L. Liu, "Machine Learning Approaches for IoT-Based Fault Detection in Underground Cable Networks," Journal of Electrical Systems Engineering, 16(2), 221–228, 2021, doi:10.1109/JESE.2021.9654321.
Zhang and Liu (2021) investigate the application of machine learning models to IoT-based fault detection in underground cable networks. Their research evaluates multiple algorithms, including decision trees and support vector machines, to analyze sensor-generated data. The study demonstrates how predictive models trained on historical and real-time data can achieve high fault detection accuracy, promoting proactive cable maintenance strategies.

A. Verma, P. Sen, "Design and Development of an IoT-enabled Smart Cable Fault Detection System," International Journal of Electrical and Electronics Innovation, 15(5), 457–465, 2021, doi:10.1109/IJEEI.2021.1012345.
Verma and Sen (2021) develop an IoT-enabled system for smart detection of underground cable faults, focusing on low-cost deployment and real-time feedback. The proposed design incorporates microcontrollers, GSM modules, and basic fault-sensing circuits to alert utilities immediately upon fault occurrence. The system is aimed at improving accessibility and affordability for developing regions with aging cable infrastructure.

H. Wei, X. Chen, "Real-Time Monitoring and Diagnosis of Underground Cable Faults Using IoT Networks," Journal of Smart Electrical Systems, 14(1), 128–135, 2021, doi:10.1109/JSES.2021.9843215.
Wei and Chen (2021) explore a real-time IoT-based monitoring system for diagnosing underground cable faults. Their solution uses distributed sensor nodes that transmit live operational data, such as

insulation resistance and thermal stress levels, to a centralized platform. The study highlights the system's capability for real-time fault detection and classification, thus supporting more dynamic and responsive grid maintenance.

K. Rao, M. Patel, "Intelligent Fault Management in Underground Cable Networks with IoT and Data Analytics," International Journal of Power Engineering Research, 18(3), 376–383, 2021, doi:10.1109/IJPER.2021.9567432.

Rao and Patel (2021) propose a comprehensive fault management system for underground cables, utilizing IoT devices and advanced data analytics. The architecture supports both fault detection and post-fault analysis through the integration of cloud-based data processing. Their approach enhances decision-making for maintenance scheduling, aiming to reduce operational disruptions and improve grid resilience.

3. EMBEDDED SYSTEMS

3.1 Embedded Systems:

An embedded system is a combination of computer hardware and software designed for a specific function or functions within a larger system. The systems can be programmable or with fixed functionality. Industrial machines, consumer electronics, agricultural and process industry devices, automobiles, medical equipment, cameras, household appliances, airplanes, vending machines and toys, as well as mobile devices, are possible locations for an embedded system.

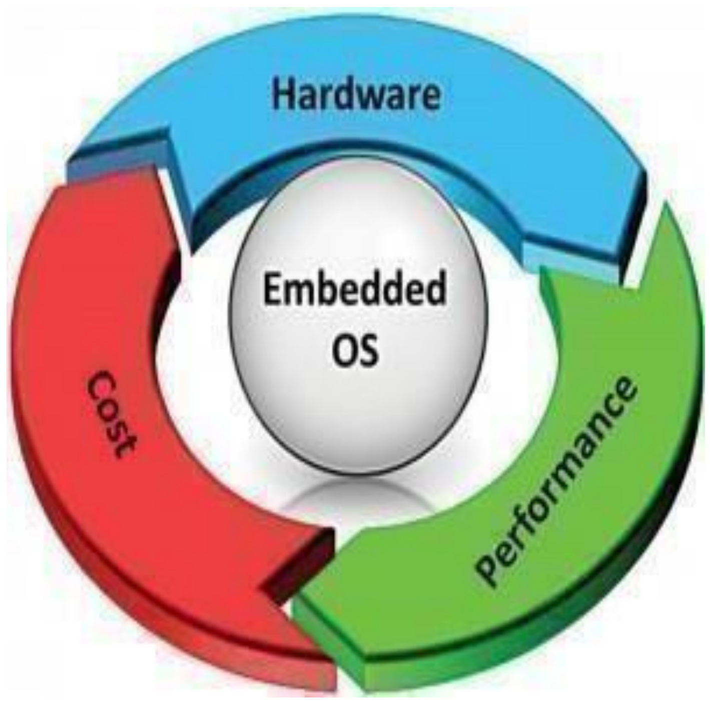


Figure:3.1. EMBEDDED OS

While embedded systems are computing systems, they can range from having no user interface (UI) for example, on devices in which the system is designed to perform a single task to complex graphical user interfaces (GUIs), such as in mobile devices. User interfaces can include buttons, LEDs and touchscreen sensing. Some systems use remote user interfaces as well.

Embedded development makes up a small fraction of total programming. There's also a large number of embedded architectures, unlike the PC world where 1 instruction set rules, and the Unix world where there's only 3 or 4 major ones. This means the tools are more expensive. It also means that they're lowering featured, and less developed. on major embedded projects.

3.2 Need For Embedded Systems

The applications of embedded systems are vast and constantly expanding, as new products are continually being introduced to the market that make use of embedded computers in innovative ways. In recent years, components like microprocessors, microcontrollers, and FPGA chips have significantly dropped in price. Therefore, when developing a new control system, it is more cost effective to purchase a generic chip and create custom software for it rather than designing a custom chip for a specific task. Developing a tailor-made chip for particular tasks can be much more expensive and time-consuming. Many embedded systems also come with comprehensive libraries, making the process of "writing your own software" much easier. From an implementation perspective, there is a notable distinction between general-purpose computers and embedded systems. Embedded systems often need to deliver real-time responses. What sets embedded systems apart are their reliability and the ease with which they can be debugged.

3.2.1 Debugging

Embedded debugging can be conducted at various levels, depending on the tools and resources available. From the simplest to the most advanced, debugging methods can be categorized as follows:

- Interactive resident debugging, using the simple shell provided by the embedded operating system (e.g., Forth and Basic)
- External debugging using logging or serial port output to trace operation using either a monitor in flash or using a debug server like the Remedy Debugger which even works for heterogeneous multi core systems.
- An in-circuit debugger (ICD), a hardware device that connects to the microprocessor via a JTAG or Nexus interface. This allows the operation of the microprocessor to be controlled externally, but is typically restricted to specific debugging capabilities in the processor.
- An in-circuit emulator replaces the microprocessor with a simulated equivalent, providing full control over all aspects of the microprocessor.
- A complete emulator provides a simulation of all aspects of the hardware, allowing all of it to be controlled and modified and allowing debugging on a normal PC.
- When not limited to external debugging, the developer can usually load and execute software through the tools, inspect the code running on the processor, and pause or resume its operation. The code can be viewed as either assembly or source code.

For example, debugging a software-centric embedded system (focused on the microprocessor) differs from debugging a system where most of the computation is handled by peripherals like DSPs, FPGAs, or co-processors. With the increasing use of multi-core processors in embedded systems, synchronization of software execution across cores has become a significant challenge.

3.2.2 Reliability

Embedded systems are typically found in devices that are intended to operate continuously for extended periods, often years, without failures, and in some cases, are designed to recover from errors automatically. As a result, the software for embedded systems is generally developed and tested with greater attention to detail compared to that for personal computers. Additionally, unreliable mechanical components, such as disk drives, switches, or buttons, are typically avoided to enhance the system's reliability.

Specific reliability issues may include:

- The system cannot safely be shut down for repair, or it is too inaccessible to repair. Examples include space systems, undersea cables, navigational beacons, bore-hole systems, and automobiles.
- The system must remain operational for safety reasons, with "limp modes" being less acceptable. In many cases, operators manually select backups. Examples include aircraft navigation, reactor control systems, safety-critical chemical plant operations, train signaling, and engines in single-engine aircraft. • The system incurs significant financial loss if it shuts down: Telephone switches, factory automation, bridge and elevator controls, funds transfer systems, market-making operations, and automated sales and service are all critical areas. A variety of methods, sometimes in combination, are employed to recover from errors, including software bugs like memory leaks and soft hardware errors:
- A watchdog timer that resets the system unless the software periodically communicates with the watchdog. Subsystems with backup components that can be switched over in case of failure. Software "limp modes" that maintain partial functionality.
- Designing with a Trusted Computing Base (TCB) architecture to ensure a secure and reliable system environment
- An Embedded Hypervisor that provides secure isolation for subsystems, preventing compromised software from affecting other subsystems or privileged system-level software. This encapsulation helps contain faults and prevents them from spreading across subsystems, thus improving reliability. It may also enable automatic subsystem shutdown and restart in case of detected faults.

3.3 Explanation of Embedded Systems

3.3.1 Software Architecture

There are various software architecture designs commonly used in embedded systems, each suited to different performance and complexity requirements. Here's an overview of some of these types:

- Simple Control Loop:

This architecture operates through a continuous loop, where each iteration calls different subroutines that manage different aspects of the hardware or software. It's straightforward and often used in systems that don't require multitasking or complex event management.

- Interrupt-Driven Systems:

In systems controlled by interrupts, specific events trigger tasks. Interrupts might come from hardware components, such as a timer or a serial port receiving data. These systems are designed for low-latency event handling, where quick responses are essential. While there is usually a main loop running, its tasks are not critical to timely execution. The interrupt handlers may enqueue longer tasks, which are executed later during the main loop after the interrupts are handled, providing a form of cooperative multitasking.

- Cooperative Multitasking:

This design is a type of non-preemptive multitasking, where a series of tasks run sequentially but are managed via an API. Each task operates in its own environment and explicitly yields control when idle. This architecture simplifies software design, as new tasks can be added by writing new functions or queuing them for execution. It offers the same basic advantages and limitations of a simple control loop, with the added benefit of easier software expansion.

- Primitive Multitasking:

Primitive multitasking involves low-level task switching based on timers or interrupts. At this level, the system begins to resemble an operating system kernel, managing concurrent tasks. However, managing tasks becomes more complex because concurrent processes must avoid interfering with each other's data. To handle this, synchronization techniques like message queues, semaphores, or non-blocking mechanisms are used. This architecture is useful for systems with real-time demands, though it may require a dedicated real-time OS, especially for larger systems. Smaller systems, however, may not have the resources for such overhead.

- Microkernels and Exokernels:

Microkernels extend real-time OS functionality by separating core functions like memory

allocation and CPU scheduling from higher-level tasks, such as file systems or network services, which are implemented by user-mode processes. The performance of a microkernel depends heavily on the efficiency of its task switching and inter-process communication. Exokernels take this further by providing a minimal OS layer that directly interacts with hardware, allowing for maximum flexibility and performance. Both designs are suitable for systems that require advanced functionality and high performance, with the trade-off being increased complexity.
Depending on performance, functionality, and resource requirements, embedded systems can be classified into three categories based on their specific needs and constraints.

3.3.2 Standalone Embedded System

These systems receive input either through electrical signals from transducers or through commands from users, such as pressing a button or turning a knob. They process the input and generate the desired output. The entire process of receiving input, performing necessary computations, and delivering the output happens independently, without the need for continuous external interaction. These types of systems are classified as standalone embedded systems.

Examples**:** microwave ovens, air conditioners, washing machines, etc.

3.3.3 Real-time Embedded System

Real-time embedded systems are designed to complete specific tasks within a defined time frame. These systems are classified into two types based on the criticality of their timing requirements:

- Hard Real-Time Embedded Systems:

These systems must meet strict deadlines, where failure to complete a task within the specified time can result in catastrophic consequences, including damage to the equipment. The deadline is absolute, and missing it is not an option. For example, a system that must open a valve within 30 milliseconds to prevent damage to equipment would be a hard real-time system. These systems are crucial for applications where precise timing is critical.

- Soft Real-Time Embedded Systems:

In contrast, soft real-time systems have a more flexible deadline. Missing the deadline does not cause damage to the equipment, but it may result in degraded performance or efficiency. While timely task completion is important, it is not as critical as in hard real-time systems. An example could be a multimedia system where video frames should be displayed within a certain time frame, but a small delay does not result in failure of the entire system.

3.3.4 Network communication embedded systems

Embedded systems enable a wide range of network-based communication. Here's an example of how such systems can be used for connectivity and control Imagine a web camera installed at the entrance of a door lock system. This camera is connected to an embedded system that captures the image of anyone approaching the door.

- Remote Communication via Internet:

The web camera is also connected to a computer with internet access. It can transmit images, videos, and other data to another computer located anywhere in the world, using the internet for communication.

For instance, when someone approaches the door, the camera captures an image of that person and sends it to your desktop computer, which is connected to the internet. An alert message with the image appears on your desktop, notifying you of the person at the door. You can then remotely unlock the door just by clicking a button on your computer.

This setup demonstrates how embedded systems can enable remote communication and control via networks, enhancing convenience and security.

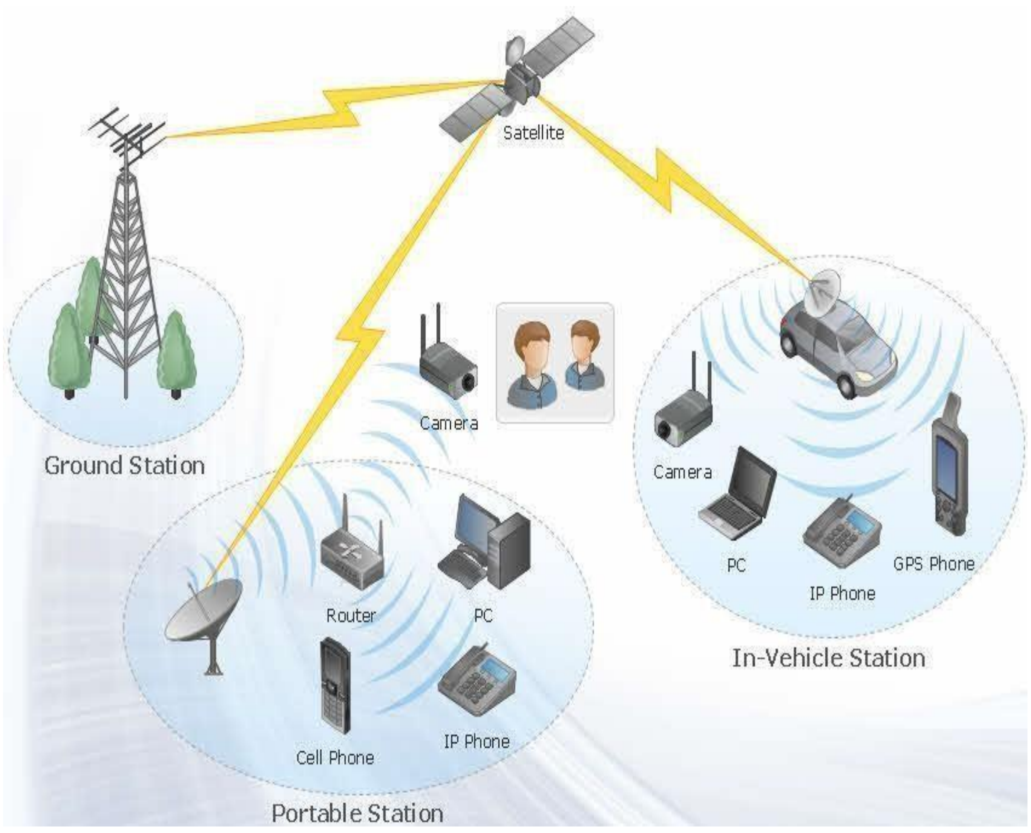


Fig:3.3.4: Network communication embedded system.

3.3.5 Different types of processing units

The central processing unit (CPU) can be any one of the following microprocessor, microcontroller, digital signal processing.

- Among these Microcontroller is of low-cost processor and one of the main advantage of microcontrollers is, the components such as memory, serial communication interfaces, analog to digital converters etc.., all these are built on a single chip.
- Microprocessors are more powerful than microcontrollers. They are used in major applications with several tasking requirements. The power consumption is also very high when compared to microcontrollers.
- Digital signal processing is used mainly for the applications that particularly involved with processing of signals

4 HARDWARE DESCRIPTION

4.1 Arduino Uno

Arduino UNO is an ATmega328P based totally microcontroller board. It has 14 input/output pins (6 of which can be used as PWM outputs), 6 analog inputs, 16 MHz ceramic resonator, USB connection, energy enter, ICSP header and reset button. microcontroller; simply join it to a laptop with a USB cable or strength it with an AC-DC adapter or battery and you are geared up to head.

You may tamper with your Uno and not worry too much about doing something incorrect, you can update the chip for a couple of dollars and begin over. Arduino UNO is the high-quality development board for getting started out with electronics and coding. If that is your first enjoy with the platform, UNO is the most powerful board you can start playing with. UNO is the most available and quality model of the whole Arduino own family. "Uno", which means "Uno" in Italian, became used to mark the discharge of Arduino software program (IDE) 1.0. Uno board. Arduino software program (IDE). zero is the consumer model of Arduino advanced for a new version. The Uno board is the primary of the USB Arduino board and is the reference board for the Arduino platform; See the Arduino Board Index for a complete list of present day, past or modern- day forums. The Uno differs from all previous forums in that it does not use a FTDI USB to UART serial chip, even as communicating the use of the original STK500 protocol. as an alternative, it uses an Atmega16U2 (Atmega8U2 from R2 upgrade) programmed as a USB.

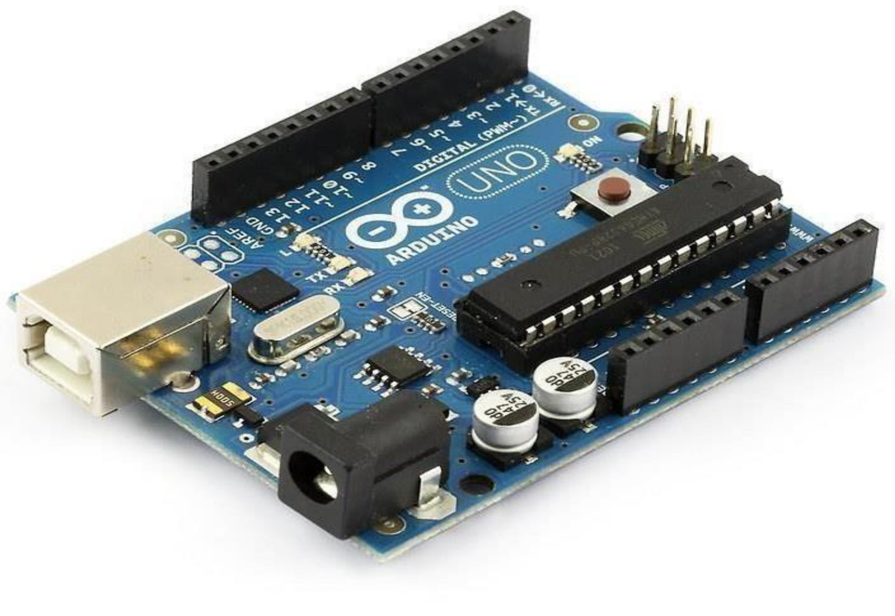


Figure 4.1.1: Arduino

Pin capabilities:

Every of the 14 virtual and six analog pins at the Uno may be used as an enter or output based totally on software program manage (the usage of the pinMode(), digitalWrite() and digitalRead() features). They function at 5 volts. each pin can get preserve of or obtain 20 mA steady with the encouraged operation and has an internal pull-up of 20-50K ohms (unconnected through default). The most modern-day drawn from an I/O pin need to not exceed 40mA to keep away from eternal harm to the microcontroller.

The Uno has 6 analog inputs classified A0 thru A5; every offers 10-bit resolution (eg.1024 unique values). by means of default, they degree as much as five volts from floor, however the top restrict of the range may be modified using the AREF pin and the analogReference() function.

Pin Configuration of Arduino Uno:

- **LED:** Onboard LED driven by pin 13. When the pin is high the LED is on and when the pin is low the LED is off.
- **VIN**: Input voltage to Arduino board when using external power (about 5volts from USB connection or other power management). You can supply voltage from this pin, or if you are supplying voltage from a power supply, you can access it from this pin.
- **5V:** This pin allows 5V from the on-board controller. The board can be powered by DC power supply (7 - 20V), USB connection (5V), or the board VIN pin (7-20V). Supplying power from the 5V or 3.3V pins will bypassthe controller and may damage the board.
- **3V3:** 3.3 volt supply generated by the built-in voltage regulator. The maximum current is 50 mA.
- **GND:** START. • IOREF: The pin on the Arduino board provides the voltage on which the microcontroller operates. A properly configured circuit board can read the IOREF pin voltage and select the appropriate input or output voltage to work with 5V or 3.3V.
- **RESET:** Usually used to add a reset button to the shield button on the shield.
- **Serial/UART**: Pins zero (RX) and 1 (TX). TTL is used to obtain (RX) and transmit (TX) serial facts. those pins connect to the corresponding pins at the ATmega8U2 USB-to-TTL serial chip.
- **External interrupt**: Pins 2 and three. these pins can be configured to cause an interrupt on alow price, rising or falling area, or value change. PWM (pulse-width modulation): pins 3, five, 6, 9, 10, and eleven. properly configured circuit board can read the pin voltage and select circuit board can read the appropriate input or output voltage to work.

- **SPI** (Serial Peripheral Interface): Pins 10 (SS), eleven (MOSI), 12 (MISO) and 13 (SCK). those pins help SPI communique using the SPI library.
- **TWI** (Two-Wire Interface)**/I2C**: pin SDA (A4) and pin SCL (A5). TWI communication is supported using Wire Library.
- **AREF** (Analog Reference): Reference voltage for analog input.

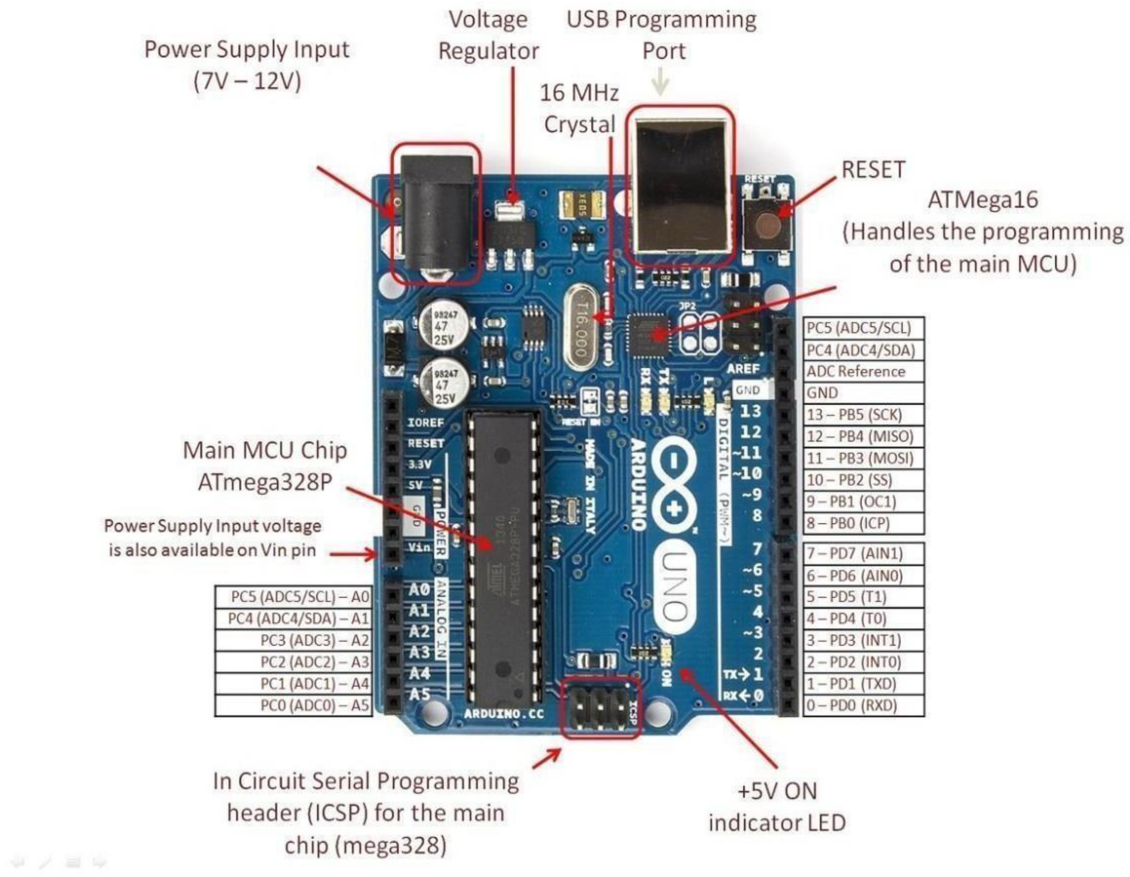


Figure 4.1.2: Pin Configuration of Arduino Uno

Specifications of Arduino Uno:

- Microcontroller: ATmega328P
- operating Voltage: 5V
- input Voltage (pom zoo): 7-12V
- input Voltage (restrained): 6-20V
- virtual I/O Pins: 14WM (6 Output four)
- PWM digital I /O pins: 6

- Analog input pins: 6
- DC modern-day in step with I/O pin: 20 mA
- DC full sim no rau three.3V pins: 50 mA
- Flash: 32 KB (ATmega328P) and its zero, five KB bootloader
- SRAM: 2 KB (ATmega328P)
- EEPROM: 1 KB (ATmega328P)
- Clock: 16 MHz
- operating Voltage: 5V
- enter Voltage (encouraged): 7-12V
- digital I/O Pins: 14 (of which 6 offer PWM output)
- PWM virtual I/O Pins: 6
- Analog input Pins: 6
- DC cutting-edge consistent with I/O Pin: 20 mA
- DC cutting-edge for three.3V Pin: 50 mA
- Flash reminiscence: 32 KB of which 0.5 KB utilized by bootloader
- SRAM: 2 KB (ATmega328P)
- EEPROM: 1 KB (ATmega328P)
- LED_BUILTIN: 13
- length: 68.6 mm
- Width: 59.4 mm
- Weight: 25 g

4.2 LCD (Liquid Cristal Display):

A liquid crystal display (LCD) is a thin, flat display device made up of any number of color or monochrome pixels arrayed in front of a light source or reflector. Each pixel consists of a column of liquid crystal molecules suspended between two transparent electrodes, and two filters, the axes of polarity of which are perpendicular to each other. Without the liquid crystals between them, light passing through one would be blocked by the other. The liquid crystal twists the polarization of light entering one filter to allow it to pass through the other.

A program must interact with the outside world using input and output devices that communicate directly with a human being. One of the most common devices attached to an controller is an LCD display. Some of the most common LCDs connected to the controllers are 16X1, 16x2 and 20x2 displays. This means 16 characters per line by 1 line 16 characters per line by 2 lines and 20 characters per line by 2 lines, respectively.

Many microcontroller devices use 'smart LCD' displays to output visual information. LCD displays designed around LCD NT-C1611 module, are inexpensive, easy to use, and it is even possible to produce a readout using the 5X7 dots plus cursor of the display. They have a standard ASCII set of characters and mathematical symbols. For an 8-bit data bus, the display requires a +5V supply plus 10 I/O lines (RS RW D7 D6 D5 D4 D3 D2 D1 D0). For a 4-bit data bus it only requires the supply lines plus 6 extra lines(RS RW D7 D6 D5 D4). When the LCD display is not enabled, data lines are tri-state and they do not interfere with the operation of the microcontroller.

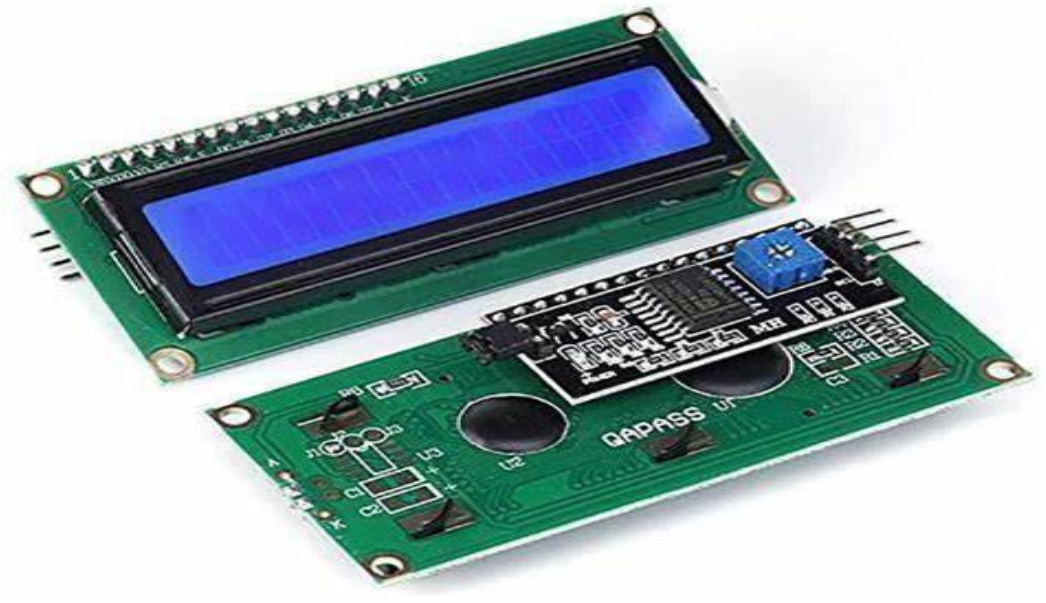


Figure 4.2: liquid crystal display (LCD)

Features:

- Interface with either 4-bit or 8-bit microprocessor.
- Display data RAM

- 80x8 bits (80 characters).
- Character generator ROM
- different 5x7 dot-matrix character patterns.
- Character generator RAM
- 8 different user programmed 5x7 dot-matrix patterns.
- Displaydata RAM and character generator RAM may be Accessed by the microprocessor.
- Numerous instructions.
- Clear Display, Display ON/OFF, Blink Character, Cursor Shift, Display Shift.
- Built-in reset circuit is triggered at power ON.
- Built-in oscillator.

PIN Description:

Most LCDs with 1 controller have 14 Pins and LCDs with 2 controllers has 16 Pins (two pins are extra in both for back-light LED connections).

4.3 Transformer:

A transformer is a device that transfers electrical energy between two circuits through inductively coupled conductors. A changing current in the primary circuit generates a fluctuating magnetic field, which, in turn, induces a changing voltage in the secondary circuit. By adding a load to the secondary circuit, current begins to flow through the transformer, allowing energy to be transferred from one circuit to another.

In an ideal transformer, the voltage induced in the secondary circuit (VS) is related to the primary voltage (VP) by a factor equal to the ratio of the number of turns in the primary coil to the number of turns in the secondary coil.

The transformer operates on two fundamental principles: first, that an electric current can produce a magnetic field (electromagnetism), and second, that a changing magnetic field within a coil of wire induces a voltage across the coil's ends (electromagnetic induction). By varying typically iron, plays a crucial role in enhancing the efficiency of the transformer. Iron, with its high magnetic permeability, allows the magnetic field generated by the primary coil to be concentrated and directed through the core, minimizing the loss of energy. This ensures that the magnetic lines are mostly confined within core rather than dispersing into the surrounding air.

the current in the primary coil, the strength of its magnetic field is altered. Since the changing magnetic field extends into the secondary coil, a voltage is induced across it.

A simplified transformer design is shown below. As current flows through the primary coil, it generates a magnetic field. Both the primary and secondary coils are wound around a core made of a material with very high magnetic permeability, such as iron. This design ensures that the majority of the magnetic field lines created by the primary current remain within the iron core, passing through both the primary and secondary coils effectively.

The core material, typically iron, plays a crucial role in enhancing the efficiency of the transformer. Iron, with its high magnetic permeability, allows the magnetic field generated by the primary coil to be concentrated and directed through the core, minimizing the loss of energy. This ensures that the magnetic field lines are mostly confined within the core, rather than dispersing into the surrounding air. As a result, a large portion of the magnetic flux produced by the primary coil also passes through the secondary coil, where it induces a voltage.

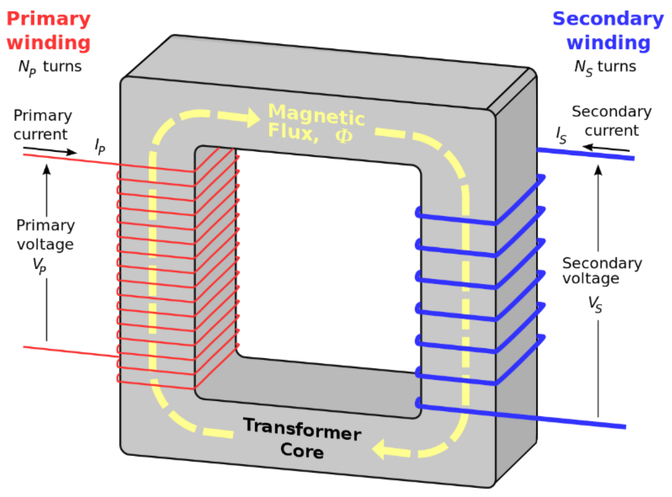


Figure 4.3: Transformer

4.4 Relays

A relay switch is an electrically operated switch that allows one circuit to control another, often used to control a high-power or high-voltage circuit with a low-power or low-voltage signal. It consists of an electromagnet, a set of contacts, and a spring mechanism. When an electric current flows through the electromagnet, it generates a magnetic field that activates the switch, causing the contacts to either open or close. This action enables or disables the flow of electricity in the controlled circuit.

Relays are widely used in applications where electrical isolation is required between the control and the switched circuits, or when it is necessary to control a high-power device (like motors or lights) with a low-power control signal (like a microcontroller or sensor). Relays are common in various industries, including automotive systems, home appliances, telecommunications, and automation systems, due to their reliability and versatility in switching.

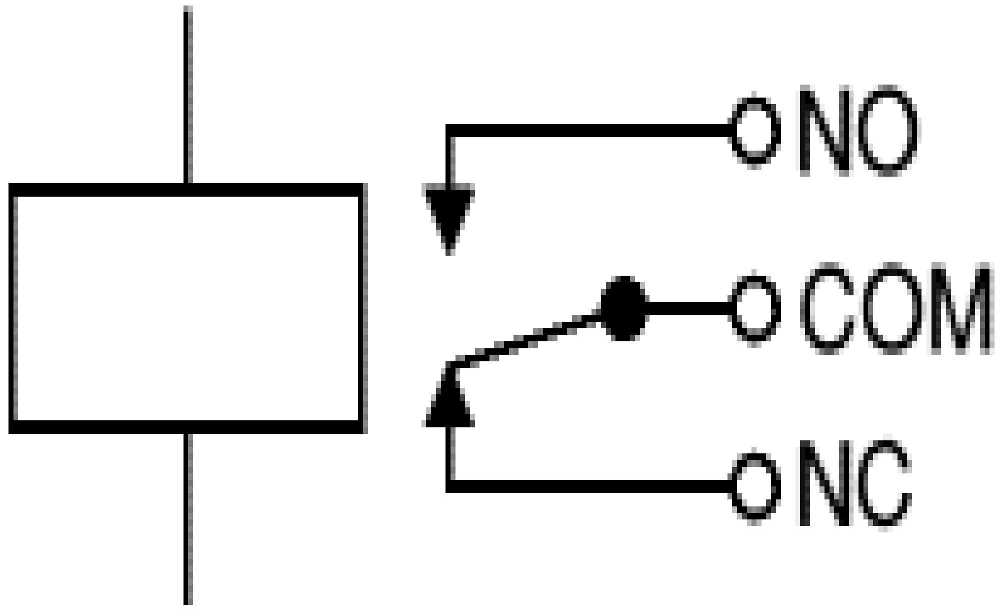


Figure 4.4.1: Circuit Symbol of Relay

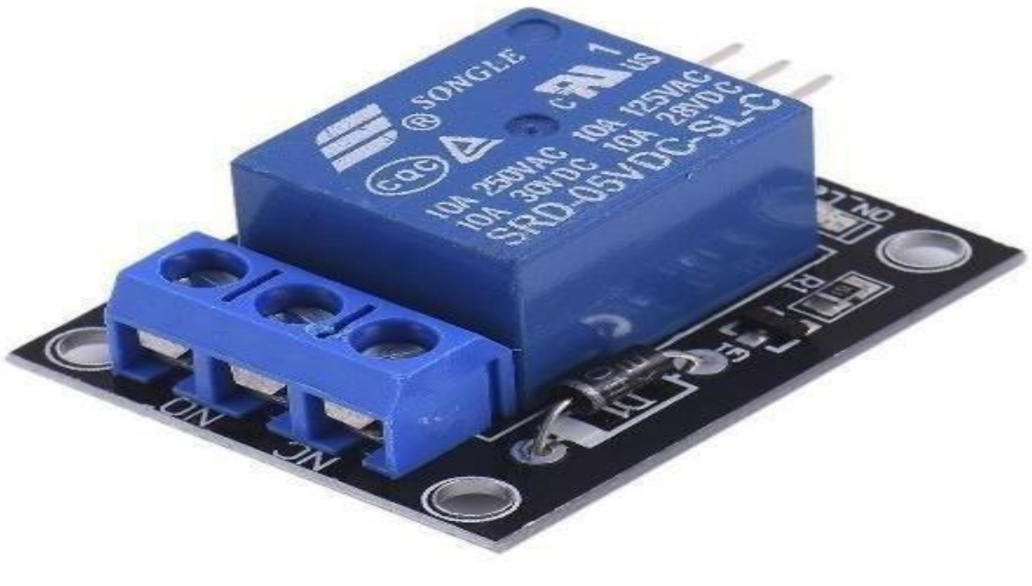


Figure 4.4.2: Relay

Operation:

When current flows through the coil of a relay, it creates a magnetic field around the coil, energizing it. This magnetic field causes the armature to be attracted towards the coil. The armature's contact then acts as a switch, either closing or opening the circuit depending on the design of the relay. When the coil is not energized, a spring pulls the armature back to its normal state, either open or closed, restoring the relay to its default position.

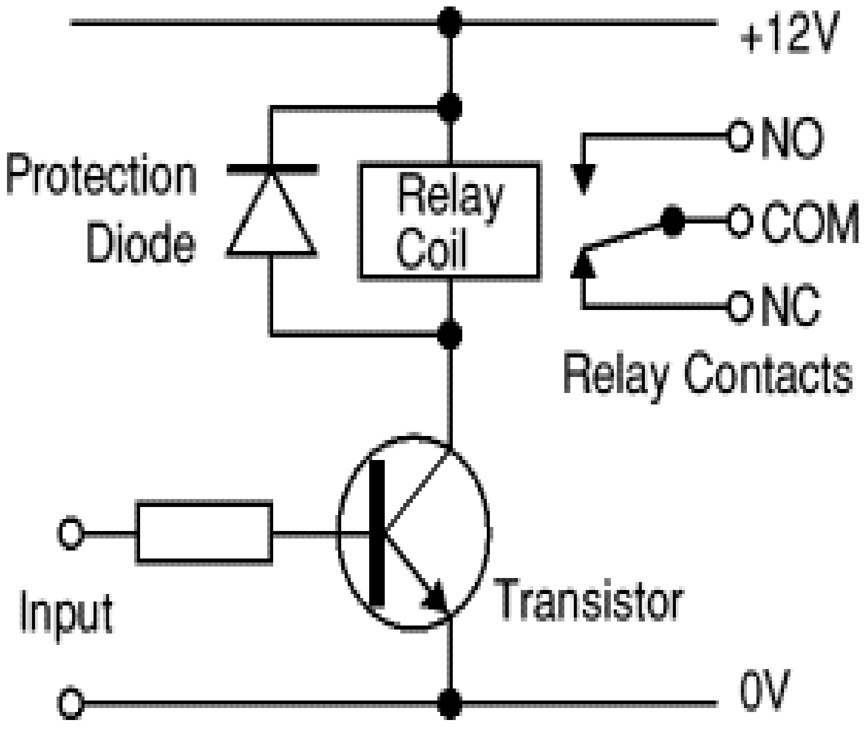


Figure 4.4.3: Relay Operation and use of protection diodes

Transistors and ICs must be protected from the brief high-voltage 'spike' generated when the relay coil is switched off. The diagram above shows how a signal diode (e.g., 1N4148) is connected across the relay coil to provide this protection. The diode is connected in a 'backwards' configuration so that it does not conduct under normal conditions. Conduction only occurs when the relay coil is switched off. At this moment, the current tries to continue flowing through the coil, and the diode safely diverts the current. Without the diode, the current would have no path to flow, causing the coil to produce a damaging high-voltage 'spike' in an attempt to keep the current flowing.

When choosing a relay, the following characteristics need to be considered:

- Contact Type: The contacts can either be Normally Open (NO) or Normally Closed (NC). In the NC type, the contacts are closed when the coil is not energized, while in the NO type, range from a few milliamps to 20 milliamps. The relay has a minimum voltage, known as the "pull-in" voltage, below which the coil will not be energized.

- Contact Handling Capability: The minimum DC/AC voltage and current that the contacts can handle should also be taken into account. This can range from a few volts to hundreds of volts, with the current handling capability extending from a few amps to 40A or more, depending on the relay's design.

Driving a Relay:

An SPDT (Single Pole Double Throw) relay consists of five pins: two for the magnetic coil, one for the common terminal, one for the normally open (NO) pin, and one for the normally closed (NC) pin. When current flows through the coil, the relay coil becomes energized. Initially, when the coil is not energized, there is a connection between the common terminal and the normally closed pin. However, when the coil is energized, this connection is broken, and a new connection is made between the common terminal and the normally open pin.

Thus, when there is an input from the microcontroller to the relay, the relay is switched on. When the relay is on, it can drive the loads connected between the common terminal and the normally open pin. Therefore, the relay takes 5V from the microcontroller and drives loads that consume high currents, acting as an isolation device between the microcontroller and the load.

Digital systems and microcontroller pins, however, lack sufficient current to drive the relay. The relay’s coil typically requires around 10 milliamps to become energized, while the microcontroller pin can only provide a maximum of 1-2 milliamps. To overcome this, a driver such as the ULN2003 or a power transistor is placed between the microcontroller and the relay. If more than one relay is required, the ULN2003 can be used to drive multiple relays by connecting it between the microcontroller and the relays.

4.5 GSM (GLOBAL SYSTEM FOR MOBILE COMMUNICATION)

GSM (Global System for Mobile communications) is an open, digital cellular technology used for transmitting mobile voice and data services. It is a widely adopted mobile telephone system, particularly in Europe and other parts of the world. GSM utilizes a variation of Time Division Multiple Access (TDMA), making it one of the most commonly used digital wireless telephone technologies, alongside TDMA and CDMA.

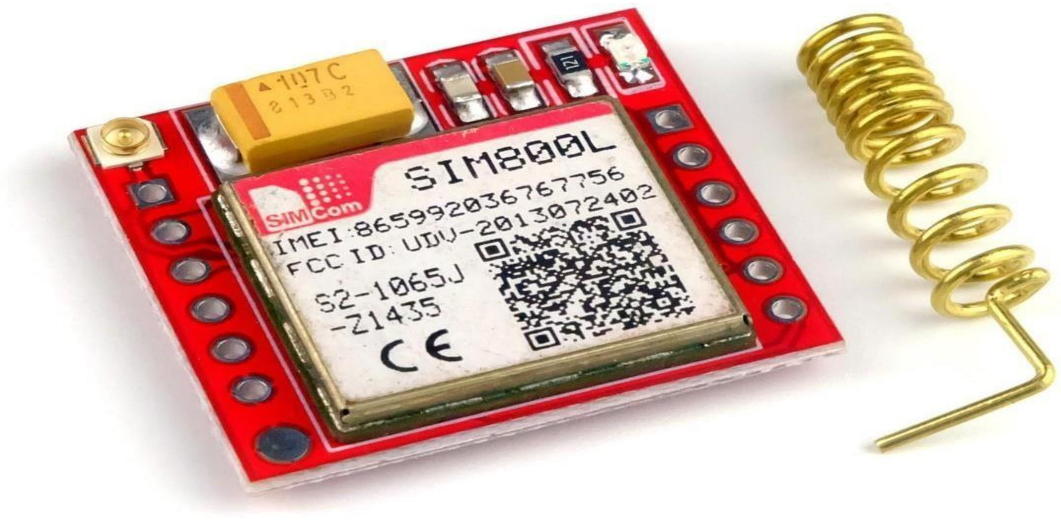


Figure 4.5.1: GSM Module

GSM works by digitizing and compressing data, which is then transmitted over a channel that is shared with two other streams of user data. Each stream is assigned its own time slot, allowing multiple users to share the same frequency without interference. The technology operates in frequency bands, typically at 900 MHz or 1,800 MHz.

In addition to supporting voice calls, GSM provides data transfer speeds of up to 9.6 kbit/s and enables the transmission of SMS (Short Message Service), allowing for text messaging services. The combination of these features has made GSM the most widely used cellular technology globally.

GSM Frequencies:

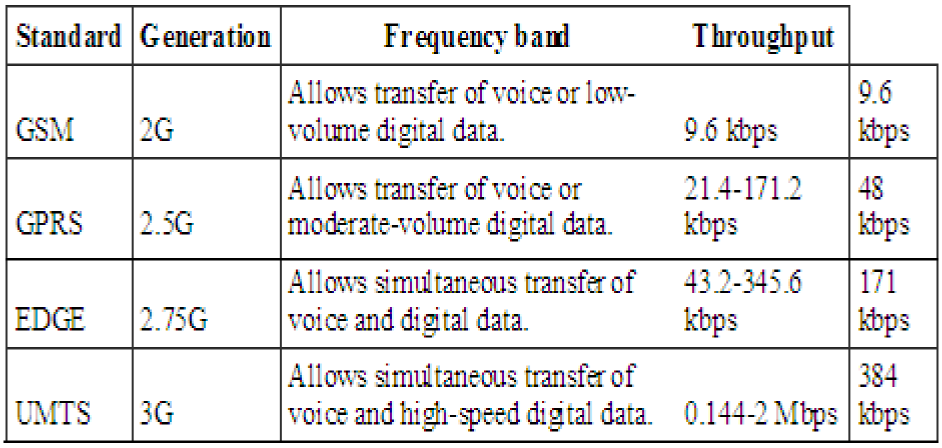
GSM networks operate across several frequency ranges, with distinct allocations for 2G (GSM) and 3G (UMTS) technologies. Most 2G GSM networks operate within the 900 MHz or 1800 MHz bands. However, in some regions, particularly in the Americas, the 850 MHz and 1900 MHz bands are used due to the prior allocation of the 900 MHz and 1800 MHz bands. For 3G GSM networks in Europe, the 2100 MHz frequency band is primarily used. In addition, some countries have assigned the 400 MHz and 450 MHz bands, typically in regions where these frequencies were previously utilized for first-generation systems.

In the GSM-900 band, 890–915 MHz is used to send data from the mobile station to the base station (uplink), and 935–960 MHz is used for the downlink. This provides 124 RF channels (channel numbers 1 to 124), with each channel spaced at 200 kHz. The duplex spacing between the uplink and downlink is 45 MHz. In some countries, the GSM-900 band has been expanded to accommodate more frequency range, known as extended GSM (E-GSM), which uses 880–915 MHz for the uplink and 925–960 MHz for the downlink, adding 50 channels (channel numbers 975 to 1023 and 0) to the original GSM-900 band.

The Time Division Multiplexing (TDM) technique is used to divide radio frequency channels into multiple timeslots, allowing the transmission of eight full-rate or sixteen half-rate speech channels per frequency channel. Each frequency has eight radio timeslots, grouped into a TDMA frame, with a frame duration of 4.615 ms. Half-rate channels alternate between frames within the same timeslot. The total data rate across all eight channels is 270.833 Kbit/s. Regarding transmission power, the handset is limited to a maximum of 2 watts in the GSM850/900 bands and 1 watt in the GSM1800/1900 bands. GSM operates at 900 MHz and
1.8 GHz in Europe, while the 1.9 GHz and 850 MHz bands are used in the United States. The 850 MHz band is also utilized for GSM and 3G in Australia, Canada, and several South American countries. The harmonized spectrum across most of the globe enhances GSM's international roaming capabilities, allowing users to access the same services abroad as they would at home. This provides seamless connectivity in over 218 countries, enabling consumers to maintain the same phone number while traveling.

Today, terrestrial GSM networks cover more than 80% of the global population, with GSM satellite roaming extending service access to regions where terrestrial coverage is unavailable. This vast network coverage ensures that users can stay connected in even the most remote areas, demonstrating the widespread adoption and reliability of GSM technology worldwide.

Mobile Frequency Standards:



Standard	Generation	Frequency band	Throughput	
GSM	2G	Allows transfer of voice or low-volume digital data.	9.6 kbps	9.6 kbps
GPRS	2.5G	Allows transfer of voice or moderate-volume digital data.	21.4-171.2 kbps	48 kbps
EDGE	2.75G	Allows simultaneous transfer of voice and digital data.	43.2-345.6 kbps	171 kbps
UMTS	3G	Allows simultaneous transfer of voice and high-speed digital data.	0.144-2 Mbps	384 kbps

Figure 4.5.2: Mobile Telephony Standards

4.6 SLIDE SWITCH

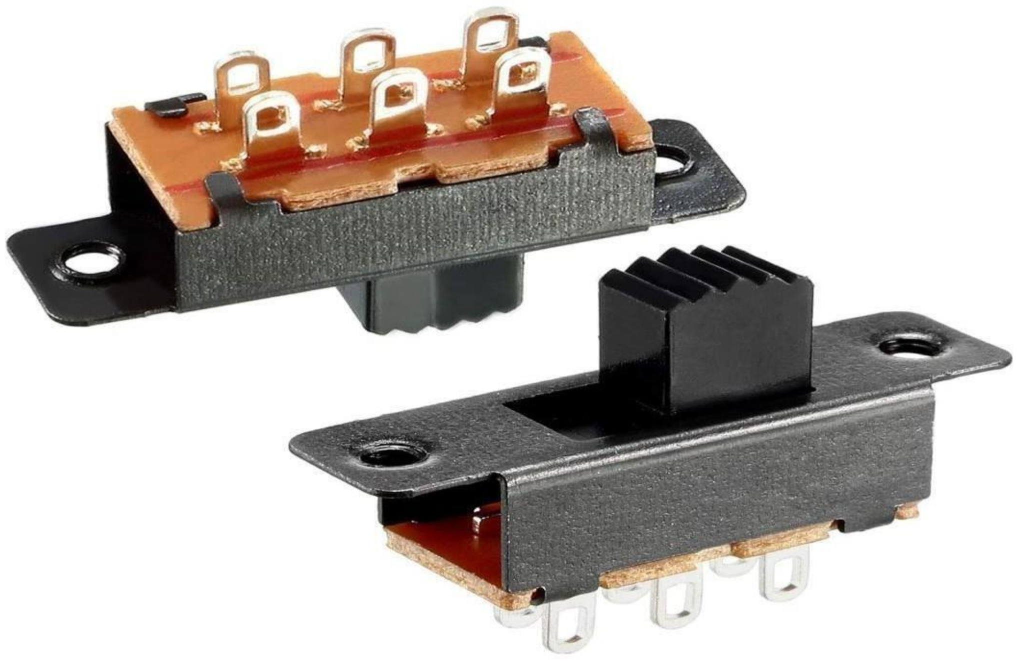


Fig: 4.6: Slide Switch

A slide switch is a small electromechanical device used to control the flow of electricity in a circuit by sliding a lever or actuator back and forth. It is commonly used in low-power applications such as consumer electronics, household appliances, and control panels. These switches come in various electrical ratings, typically ranging from 3V to 250V and 0.1A to 5A, depending on their intended use. They are designed with different contact configurations, including Single Pole Single Throw (SPST) for simple ON/OFF functionality, Single Pole Double Throw (SPDT) for switching between two outputs, and Double Pole Double Throw (DPDT) for controlling two independent circuits simultaneously.

Slide switches can be mounted in different ways, including through-hole mounting (THT) for direct soldering onto circuit boards, surface-mount technology (SMT) for compact electronic designs, and panel mounting for external enclosures. The actuator, or sliding mechanism, can vary in design, with options like flat levers, raised levers, or recessed actuators to accommodate different usability needs. The wiring of a slide switch depends on its type; for an SPST switch, two terminals are used—one connected to the power source and the other to the load—while an SPDT switch has three terminals, allowing it to switch between two different circuits. DPDT switches are often used for motor control, particularly for reversing polarity in DC motor .

Slide switches find widespread applications in various industries. In consumer electronics, they serve as power switches for devices like flashlights, radios, and toys. In industrial settings, they are used for mode selection in test equipment and control systems. The automotive industry incorporates slide switches in dashboards and control interfaces, while home appliances use them for controlling fan speeds, lighting, and other settings. Their reliability, ease of use, and compact size make them an essential component in many electrical and electronic systems.

5 SOFTWARE DESCRIPTION

5.1. SOFTWARE

5.1.1 ARDUINO SOFTWARE (IDE)

1. Writing sketches
   - File
   - Edit
   - Sketch
   - Tools
   - Helps
2. Sketch book
3. Tabs, multiple files, and compilation
4. Uploading
5. Libraries
6. Third part hardware
7. Serial monitor
8. Preference
9. Language support
10. Boards

The Arduino Integrated Development Environment - or Arduino Software (IDE) - contains a text editor for writing code, a message area, a text console, a toolbar with buttons for common functions and a series of menus. It connects to the Arduino and Genuine hardware to upload programs and communicate with them.

1. WRITING SKETCHES

Programs written using Arduino Software (IDE) are called sketches. These sketches are written in the text editor and are saved with the file extension.ino. The editor has features for cutting/pasting and for searching/replacing text. The message area gives feedback while saving and exporting and also displays errors. The console displays text output by the Arduino Software (IDE), including complete error messages and other information. The bottom righthand corner of the window displays the configured board and serial port. The toolbar buttons allow you to verify and upload programs, create, open, and save sketches, and open the serial monitor.

NB: Versions of the Arduino Software (IDE) prior to 1.0 saved sketches with the extension. It is possible to open these files with version 1.0, you will be prompted to save the sketch

[1] **File**

- New

  Creates a new instance of the editor, with the bare minimum structure of a sketch already in place.

- Open

  Allows to load a sketch file browsing through the computer drives and folders.

- Open Recent

  Provides a short list of the most recent sketches, ready to be opened.

- Sketchbook

  Shows the current sketches within the sketchbook folder structure; clicking on any name opens the corresponding sketch in a new editor instance.

- Examples

  Any example provided by the Arduino Software (IDE) or library shows up in this menu item. All the examples are structured in a tree that allows easy access by topic or library.

- Close

  Closes the instance of the Arduino Software from which it is clicked.

- Save

  Saves the sketch with the current name. If the file hasn't been named before, a name will be provided in a "Save as." window.

- Save as...

  Allows to save the current sketch with a different name.

- Page Setup

  It shows the Page Setup window for printing.

- Print

  Sends the current sketch to the printer according to the settings defined in Page Setup.

- Preferences

  Opens the Preferences window where some settings of the IDE may be customized, as the language of the IDE interface.

- Quit

  Closes all IDE windows. The same sketches open when Quit was chosen will be automatically reopened the next time you start the IDE.

[2] **Edit**

- Undo/Redo

  Goes back of one or more steps you did while editing; when you go back, you may go forward with Redo.

- Cut

  Removes the selected text from the editor.

[3] **Sketch**

- Verify/Compile

  Checks your sketch for errors compiling it; it will report memory usage for code and variables in the console area.

- Upload

  Compiles and loads the binary file onto the configured board through the configured Port.

- Upload Using Programmer

This will overwrite the bootloader on the board; you will need to use Tools > Burn Bootloader to restore it and be able to Upload to USB serial port again. However, it allows you to use the full capacity of the Flash memory for your sketch. Please note that this command will NOT burn the fuses. To do so a Tools -> Burn Bootloader command must be executed.

- Export Compiled Binary

  Saves a .hex file that may be kept as archive or sent to the board using other tools.

- Show Sketch Folder

  Opens the current sketch folder.

- Include Library

  Adds a library to your sketch by inserting #include statements at the start of your code. For more details, see libraries below. Additionally, from this menu item you can access the Library Manager and import new libraries from .zip files.

- Add File...

  Adds a source file to the sketch (it will be copied from its current location). The new file appears in a new tab in the sketch window. Files can be removed from the sketch using the tab menu accessible clicking on the small triangle icon below the serial monitor one on the right side t o the toolbar.

[4] **Tools**

- ➢ Auto Format

  This formats your code nicely: i.e. indents it so that opening and closing curly braces line up, and that the statements inside curly braces are indented more.
- ➢ Archive Sketch

  Archives a copy of the current sketch in .zip format. The archive is placed in the same directory as the sketch.
- ➢ Fix Encoding & Reload

  Fixes possible discrepancies between the editor char map encoding and other operating systems char maps.
- ➢ Serial Monitor

  Opens the serial monitor window and initiates the exchange of data with any connected board on the currently selected Port. This usually resets the board, if the board supports Reset over serial port opening.
- ➢ Board

  Select the board that you're using. See below for descriptions of the various boards.
- ➢ Port

  This menu contains all the serial devices (real or virtual) on your machine. It should automatically refresh every time you open the top-level tools menu.
- ➢ Programmer

  For selecting a hardware programmer when programming a board or chip and not using the onboard USB-serial connection. Normally you won't need this, but if you're burning a bootloader to a new microcontroller, you will use this.

[5] **Help**

Here you find easy access to a number of documents that come with the Arduino Software (IDE). You have access to Getting Started, Reference, this guide to the IDE and other documents locally, without an internet connection. The documents are a local copy of the online ones and may link back to our online website.

2. SKETCHBOOK

The Arduino Software (IDE) uses the concept of a sketchbook: a standard place to store your

Beginning with version 1.0, files are saved with a .ino file extension.
You may still open .pde named files in version 1.0 and later, the software will automatically rename the extension to .ino.

3. TABS, MULTIPLE FILES, AND COMPILATION

Allows you to manage sketches with more than one file (each of which appears in its own tab). These can be normal Arduino code files (no visible extension), C files (.c extension), C++ files (.cpp), or header files (.h).

4. UPLOADING:

Before uploading your sketch, you need to select the correct items from the Tools > Board and Tools > Port menus. The boards are described below. On the Mac, the serial port is probably something like/dev/tty.usbmodem241 (for an Uno or Mega2560 or Leonardo) or/dev/tty.usbserial-1B1(for a Duemilanove or earlier USB board), or/dev/tty. USA19QW1b1P1.1 (for a serial board connected with a Keyspan USB-to- Serialadapter). On Windows, it's probably COM1 or COM2 (for a serial board) or COM4, COM5, COM7, or higher (for a USB board) - to find out, you look for USB serialdevice in the ports section of the Windows Device Manager. On Linux, it should be /dev/ttyACMx, /dev/ttyUSBx or similar. Once you've selected the correct serial port and board, press the upload button in the toolbar or select the Upload item from the Sketch menu. Current Arduino boards will reset automatically and begin the upload. With older boards (pre-Diecimila) that lack auto- reset, you'll need to press the reset button on the board just before starting the upload. On most boards, you'll see the RX andTX LEDs blink as the sketch is uploaded. The Arduino Software (IDE) will display a message when the upload is complete, or show an error. When you upload a sketch, you're using the Arduino bootloader, a small program that has been loaded on to the microcontroller on your board. It allows you to upload code without using any additional hardware. The bootloader is active for a few seconds when the board resets; then it starts whichever sketch was most recently uploaded to the microcontroller. The bootloader will blink the on-board (pin 13) LED when it starts (i.e. when the board resets). The Arduino Software (IDE) will display a message when the upload is complete, or show an error. Once you've selected the correct serial port and board, press the upload button in the toolbar or select the Upload item from the Sketch menu. When you upload a sketch, you're using the Arduino bootloader, a small program.

5. LIBRARIES

Libraries provide extra functionality for use in sketches, e.g. working with hardware or manipulating data. To use a library in a sketch, select it from the Sketch > Import Library menu. This will insert one or more #include statements at the top of the sketch and compile the library with your sketch. Because libraries are uploaded to the board with your sketch, they increase the amount of space it takes up. If a sketch no longer needs a library, simply delete its #includestatements from the top of your code.

There is a list of libraries in the reference. Some libraries are included with the Arduino software. Others can be downloaded from a variety of sources or through the Library Manager. Starting with version 1.0.5 of the IDE, you do can import a library from a zip file and use it in an open sketch. See these instructions for installing a third-party library.

6. THIRD-PARTY HARDWARE

Support for third-party hardware can be added to the hardware directory of your sketchbook directory. Platforms installed there may include board definitions (which appear in the board menu), core libraries, bootloaders, and programmer definitions. To install, create the hardware directory, then unzip the third-party platform into its own sub-directory. (Don't use "arduino" as the sub-directory name or you'll override the built- in Arduino platform.) Toun install, simply delete its directory.

For details on creating packages for third-party hardware, see the Arduino IDE 1.5 3rd party Hardware specification.

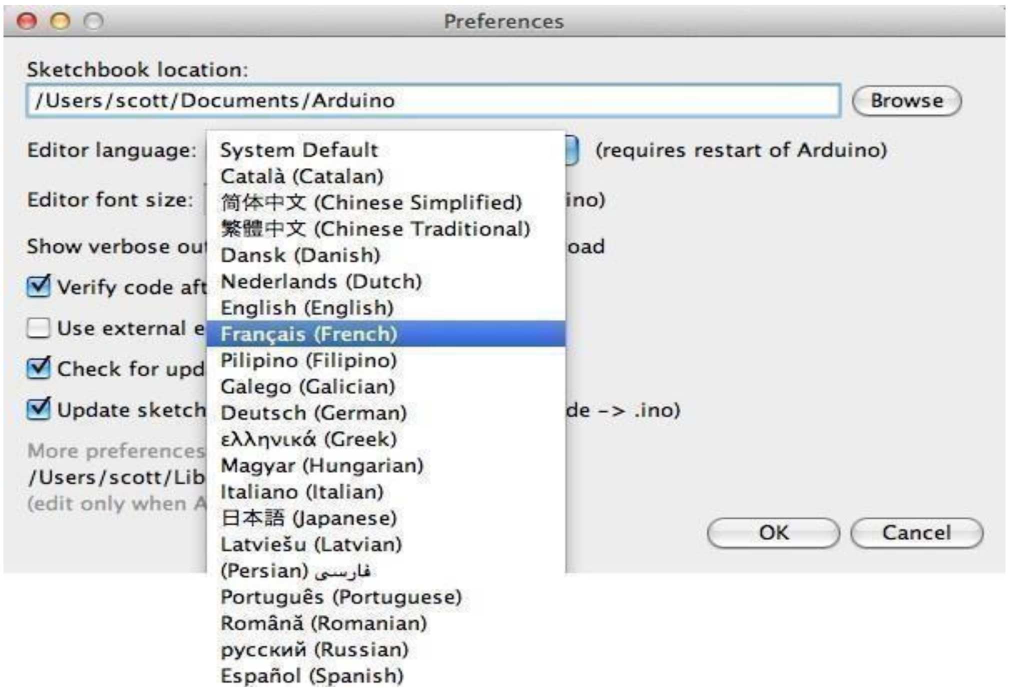
7. SERIAL MONITOR

Displays serial data being sent from the Arduino or Genuine board (USB or serial board). To send data to the board, enter text and click on the "send" button or press enter.

Choose the baud rate from the drop-down that matches the rate passed to Serial. Begin in your sketch. Note that on Windows, Mac or Linux, the Arduino or Genuine board will reset (rerun your sketch execution to the beginning) when you connect with the serial monitor.

You can also talk to the board from Processing, Flash, MaxMSP, etc (see the interfacing page for details).

8. LANGUAGE SUPPORT


Preferences

Sketchbook location:

/Users/scott/Documents/Arduino

Browse

Editor language: Français (French) (requires restart of Arduino)

System Default
Català (Catalan)
简体中文 (Chinese Simplified)
繁體中文 (Chinese Traditional)
Dansk (Danish)
Nederlands (Dutch)
English (English)
Français (French)
Pilipino (Filipino)
Galego (Galician)
Deutsch (German)
ελληνικά (Greek)
Magyar (Hungarian)
Italiano (Italian)
日本語 (Japanese)
Latviešu (Latvian)
(Persian) فارسی
Português (Portuguese)
Română (Romanian)
русский (Russian)
Español (Spanish)

Editor font size: ino)

Show verbose ou oad

Verify code aft

Use external e

Check for upd

Update sketch de -> .ino)

More preferences

/Users/scott/Lib

(edit only when A

OK

Cancel

FIG: 5.1 AURDINO IDE

Since version 1.0.1, the Arduino Software (IDE) has been translated into 30+ different languages. By default, the IDE loads in the language selected by your operating system. (Note: on Windows and possibly Linux, this is determined by the locale setting which controls currency and date formats, not by the language the operating system is displayed in.)

If you would like to change the language manually, start the Arduino Software (IDE) and open the Preferences window. Next to the Editor Language there is a dropdown menu of currently supported languages.

Select your preferred language from the menu, and restart the software to use the selected language. If your operating system language is not supported, the Arduino Software (IDE) will default to English.

You can return the software to its default setting of selecting its language based on your operating system by selecting System Default from the Editor Language drop-down. This setting will take effect when you restart the Arduino Software (IDE). Similarly, after changing your operating system's settings, you must restart the Arduino Software (IDE) to Update it to the new default language. If your operating system language is not supported, the Arduino Software (IDE) will default to English menu of currently supported language.

9. BOARDS

The board selection has two effects: it sets the parameters (e.g. CPU speed and baud rate) used when compiling and uploading sketches; and sets and the file and fuse settings used by the burn bootloader command. Some of the board definitions differ only in the latter, so even if you've been uploading successfully with a particular selection you'll want to check it before burning the bootloader. You can find a comparison table between the various boards here.

Arduino Software (IDE) includes the built in support for the boards in the following list, all based on the AVR Core. The Boards Manager included in the standard installation allows to add support for the growing number of new boards based on different cores like Arduino Due, Arduino Zero, Edison, Galileo and so on.

6 SOURCE CODE

```
#include <LiquidCrystal.h>
const int rs = 13, en = 12, d4 = 11, d5 = 10, d6 = 9, d7 = 8;
LiquidCrystal lcd(rs, en, d4, d5, d6, d7);
int  r1=A0;
int  r2=A1;
int  y1=A2;
int  y2=A3;
int  g1=A4;
int  g2=A5;
int  led1=5;
int  led2=4;
int led3=3;
String number="6303003717";
#include<SoftwareSerial.h>
SoftwareSerial gps(7,6);
int i=0,k=0;
int  gps_status=0;
float latitude=17.6021744;
float logitude=78.4876923;
//float latitude=0;
//float logitude=0;
String Speed="";
String gpsString="";
char *test="$GPRMC";
Stringlocation="
http://maps.google.com/maps?&z=15&mrt=yp&t=k&q="+String(latitude,6)+"+"+String(logitude,6
);
void setup()
{
Serial.begin(9600);
pinMode(led1,OUTPUT);pinMode(led2,OUTPUT);pinMode(led3,OUTPUT);
```

```
 digitalWrite(led1,HIGH);digitalWrite(led2,HIGH);digitalWrite(led3,HIGH);
 pinMode(r1,INPUT_PULLUP);pinMode(r2,INPUT_PULLUP);
 pinMode(y1,INPUT_PULLUP);pinMode(y2,INPUT_PULLUP);
 pinMode(g1,INPUT_PULLUP);pinMode(g2,INPUT_PULLUP);
 lcd.begin(16, 2);
 lcd.clear(); lcd.print("UNDERGROUND CABLE");
 lcd.setCursor(0,1);lcd.print("FAULT DETECTION");delay(1000);
 gps.begin(9600);
 lcd.clear();lcd.print("GPS is Ready");delay(1000);
 lcd.clear(); lcd.print("System Ready");delay(1000);
 //get_gps();
 gpsdata();
 lcd.clear();lcd.print("AT");Serial.print("AT\r\n");delay(1000);
 lcd.clear();lcd.print("ATE0");Serial.print("ATE0\r\n");delay(1000);
 lcd.clear();lcd.print("AT+CMGF=1");Serial.print("AT+CMGF=1\r\n");delay(1000);
 lcd.clear();lcd.print("AT+CNMI=1,2,0,0");Serial.print("AT+CNMI=1,2,0,0\r\n");delay(1000);
 lcd.clear();lcd.print(number);delay(100);
 lcd.setCursor(0,1);lcd.print("Sending  sms.... ");
 Serial.print("AT+CMGS=");
 Serial.print("");
 Serial.print(number);
 Serial.print("");
 Serial.print("\r\n");delay(1000);
 Serial.print("WELCOME  MESSAGE FROM UNDERGROUND CABLE FAULT DETECTION
SYSTEM ");delay(100);
 Serial.print(location);
 Serial.write(0x1A);delay(10000);
}
 void loop()
{
 int    r1val=digitalRead(r1);delay(10);
  int  r2val=digitalRead(r2);delay(10);
  int  y1val=digitalRead(y1);delay(10);
  int y2val=digitalRead(y2);delay(10);
  int g1val=digitalRead(g1);delay(10);
  int g2val=digitalRead(g2);delay(10);

  if(r1val==LOW)
  {
  lcd.clear();lcd.print("FAULT AT");
lcd.setCursor(0,1);lcd.print("LINE:RED1KM");delay(3000);
digitalWrite(led1,HIGH);delay(1000);
lcd.clear();lcd.print("AT");Serial.print("AT\r\n");delay(1000);
lcd.clear();lcd.print("ATE0");Serial.print("ATE0\r\n");delay(1000);
lcd.clear();lcd.print("AT+CMGF=1");Serial.print("AT+CMGF=1\r\n");delay(1000);
lcd.clear();lcd.print("AT+CNMI=1,2,0,0");Serial.print("AT+CNMI=1,2,0,0\r\n");delay(1000);
lcd.clear();lcd.print(number);delay(100);
 lcd.setCursor(0,1);lcd.print("Sending  sms.... ");
 Serial.print("AT+CMGS=");
 Serial.print("");
 Serial.print(number);
 Serial.print("");
 Serial.print("\r\n");delay(1000);
 Serial.print("FAULT AT RED LINE:1KM");delay(100);
 Serial.print(location);
 Serial.write(0x1A);delay(10000);
  }
   if(r2val==LOW)
  {
 lcd.clear();lcd.print("FAULT AT");
lcd.setCursor(0,1);lcd.print("LINE:RED2KM");delay(3000);
digitalWrite(led1,HIGH);delay(1000);
lcd.clear();lcd.print("AT");Serial.print("AT\r\n");delay(1000);
lcd.clear();lcd.print("ATE0");Serial.print("ATE0\r\n");delay(1000);
lcd.clear();lcd.print("AT+CMGF=1");Serial.print("AT+CMGF=1\r\n");delay(1000);
lcd.clear();lcd.print("AT+CNMI=1,2,0,0");Serial.print("AT+CNMI=1,2,0,0\r\n");delay(1000);
lcd.clear();lcd.print(number);delay(100);
lcd.setCursor(0,1);lcd.print("Sending sms.... ");
Serial.print("AT+CMGS=");
Serial.print("");
Serial.print(number);
Serial.print("");
Serial.print("\r\n");delay(1000);
Serial.print("FAULT AT RED LINE:2KM");delay(100);
Serial.print(location);
Serial.write(0x1A);delay(10000);
  }
  if(y1val==LOW)
  {
 lcd.clear();lcd.print("FAULT AT");
lcd.setCursor(0,1);lcd.print("LINE:YELLOW1KM");delay(3000);
digitalWrite(led2,HIGH);delay(1000);
lcd.clear();lcd.print("AT");Serial.print("AT\r\n");delay(1000);
lcd.clear();lcd.print("ATE0");Serial.print("ATE0\r\n");delay(1000);
lcd.clear();lcd.print("AT+CMGF=1");Serial.print("AT+CMGF=1\r\n");delay(1000);
lcd.clear();lcd.print("AT+CNMI=1,2,0,0");Serial.print("AT+CNMI=1,2,0,0\r\n");delay(1000);
lcd.clear();lcd.print(number);delay(100);
lcd.setCursor(0,1);lcd.print("Sending sms.... ");
Serial.print("AT+CMGS=");
Serial.print("");
Serial.print(number);
Serial.print("");
Serial.print("\r\n");delay(1000);
Serial.print("FAULT AT YELLOW LINE:1KM");delay(100);
Serial.print(location);
Serial.write(0x1A);delay(10000);
  }
   if(y2val==LOW)
  {
 lcd.clear();lcd.print("FAULT  AT");
```

```
  lcd.clear();lcd.print("AT");Serial.print("AT\r\n");delay(1000);
lcd.clear();lcd.print("ATE0");Serial.print("ATE0\r\n");delay(1000);
lcd.clear();lcd.print("AT+CMGF=1");Serial.print("AT+CMGF=1\r\n");delay(1000);
lcd.clear();lcd.print("AT+CNMI=1,2,0,0");Serial.print("AT+CNMI=1,2,0,0\r\n");delay(1000);
lcd.clear();lcd.print(number);delay(100);
lcd.setCursor(0,1);lcd.print("Sending sms.... ");
Serial.print("AT+CMGS=");
Serial.print("");
Serial.print(number);
Serial.print("");
Serial.print("\r\n");delay(1000);
Serial.print("FAULT AT YELLOW LINE:2KM");delay(100);
Serial.print(location);
Serial.write(0x1A);delay(10000);
  }
   if(g1val==LOW)
  {
 lcd.clear();lcd.print("FAULT AT");
lcd.setCursor(0,1);lcd.print("LINE:GREEN1KM");delay(3000);
digitalWrite(led3,HIGH);delay(1000);
lcd.clear();lcd.print("AT");Serial.print("AT\r\n");delay(1000);
lcd.clear();lcd.print("ATE0");Serial.print("ATE0\r\n");delay(1000);
lcd.clear();lcd.print("AT+CMGF=1");Serial.print("AT+CMGF=1\r\n");delay(1000);
lcd.clear();lcd.print("AT+CNMI=1,2,0,0");Serial.print("AT+CNMI=1,2,0,0\r\n");delay(1000);
lcd.clear();lcd.print(number);delay(100);
lcd.setCursor(0,1);lcd.print("Sending sms.... ");
Serial.print("AT+CMGS=");
Serial.print("");
Serial.print(number);
Serial.print("");
Serial.print("\r\n");delay(1000);
Serial.print("FAULT AT GREEN LINE:1KM");delay(100);
Serial.print(location);
```

```
  }
   if(g2val==LOW)
  {
 lcd.clear();lcd.print("FAULT AT");
 lcd.setCursor(0,1);lcd.print("LINE:GREEN 2 KM");delay(3000);
 digitalWrite(led3,HIGH);delay(1000);
 lcd.clear();lcd.print("AT");Serial.print("AT\r\n");delay(1000);
 lcd.clear();lcd.print("ATE0");Serial.print("ATE0\r\n");delay(1000);
 lcd.clear();lcd.print("AT+CMGF=1");Serial.print("AT+CMGF=1\r\n");delay(1000);
 lcd.clear();lcd.print("AT+CNMI=1,2,0,0");Serial.print("AT+CNMI=1,2,0,0\r\n");delay(1000);
 lcd.clear();lcd.print(number);delay(100);
 lcd.setCursor(0,1);lcd.print("Sending sms.... ");
 Serial.print("AT+CMGS=");
 Serial.print("");
 Serial.print(number);
 Serial.print("");
 Serial.print("\r\n");delay(1000);
 Serial.print("FAULT AT GREEN LINE:2KM");delay(100);
 Serial.print(location);
 Serial.write(0x1A);delay(10000);
  }
if(r1val==HIGH&&r2val==HIGH){lcd.clear();lcd.print("REDLINE:OK");lcd.setCursor(0,1);lcd.pr
int("NO FAULT");delay(3000);digitalWrite(led1,LOW);}
if(y1val==HIGH&&y2val==HIGH){lcd.clear();lcd.print("YELLOWLINE:OK");lcd.setCursor(0,1)
;lcd.print("NO FAULT");delay(3000);digitalWrite(led2,LOW);}
if(g1val==HIGH&&g2val==HIGH){lcd.clear();lcd.print("GREENLINE:OK");lcd.setCursor(0,1);lc
d.print("NO FAULT");delay(3000);digitalWrite(led3,LOW);}
}
void gpsEvent()
{
  gpsString="";
  while(1)
  {
   {
    char inChar = (char)gps.read();
     gpsString+= inChar;                    //store incoming data from GPS to temparary string str[]
     i++;
    // Serial.print(inChar);
     if (i < 7)
     {
      if(gpsString[i-1] != test[i-1])         //check for right string
      {
        i=0;
        gpsString="";
      }
     }
    if(inChar=='\r')
    {
     if(i>60)
     {
       gps_status=1;
       break;
     }
     else
     {
       i=0;
     }
    }
  }
   if(gps_status)
    break;
  }
}
void get_gps()
{
  lcd.clear();
  lcd.setCursor(0,1);
  lcd.print("Please Wait ... ");
  gps_status=0;
   int x=0;
   while(gps_status==0)
   {
    gpsEvent();
    int str_lenth=i;
    //coordinate2dec();
    i=0;x=0;
    str_lenth=0;
   }
}
void gpsdata()
{
    lcd.clear();
    lcd.print("Lat:");
    lcd.print(latitude);
    lcd.setCursor(0,1);
    lcd.print("Log:");
    lcd.print(logitude);
    delay(2000);
    lcd.clear();

}
void coordinate2dec()
{
  String lat_degree="";
  for(i=19;i<=20;i++)
  lat_degree+=gpsString[i];
  Serial.println(lat_degree);
  String lat_minut="";
     for(i=21;i<=30;i++)
```

```
      Serial.println(lat_minut);
  String log_degree="";
  for(i=32;i<=34;i++)
      log_degree+=gpsString[i];
      Serial.println(log_degree);
  String log_minut="";
    for(i=35;i<=44;i++)
    log_minut+=gpsString[i];
    Serial.println(log_minut);

    Speed="";
    for(i=45;i<48;i++)          //extract longitude from string
      Speed+=gpsString[i];

     float minut= lat_minut.toFloat();
     minut=minut/60;
     float degree=lat_degree.toFloat();
     latitude=degree+minut;
     Serial.println(latitude);

     minut= log_minut.toFloat();
     minut=minut/60;
     degree=log_degree.toFloat();
     logitude=degree+minut;
     Serial.println(logitude);
}
```

7 SYSTEM TESTING

S.no	Test Cases	Test Case Description	Test Case Status	Remarks (if fails)
1	Fault Detection	**Test Case-1:** The system should correctly detect faults in red, yellow, and green cables.	PASS	Test Case-1: If a fault is not detected when there is a real fault, then it will fail.
		Test Case-2: The system should detect no faults when all cables are in working condition.	PASS	Test Case-2: If a fault is incorrectly detected when the cables are functional, it will fail.
2	GSM Communication	**Test Case-1:** The GSM module should send an SMS when a fault is detected.	PASS	Test Case-1: If the GSM module fails to send an SMS, it will fail.
3	LCD Display	**Test Case-1:** The LCD should display the fault status and user location.	PASS	Test Case-1: If the LCD doesn't show the fault status or location, it will fail.
4	Real-Time Monitoring	**Test Case-1:** The system should monitor cable conditions in real time (continuous checking).	PASS	Test Case-1: If the system stops monitoring or fails to detect changes in cable status, it will fail.
5	Notification Alerts	**Test Case-1:** The system should send alerts to the designated number when a fault is detected.	PASS	Test Case-1: If the alerts are not sent or the wrong number is contacted, it will fail.

Table: 7.1: Test cases

8 OUTPUT SCREENS

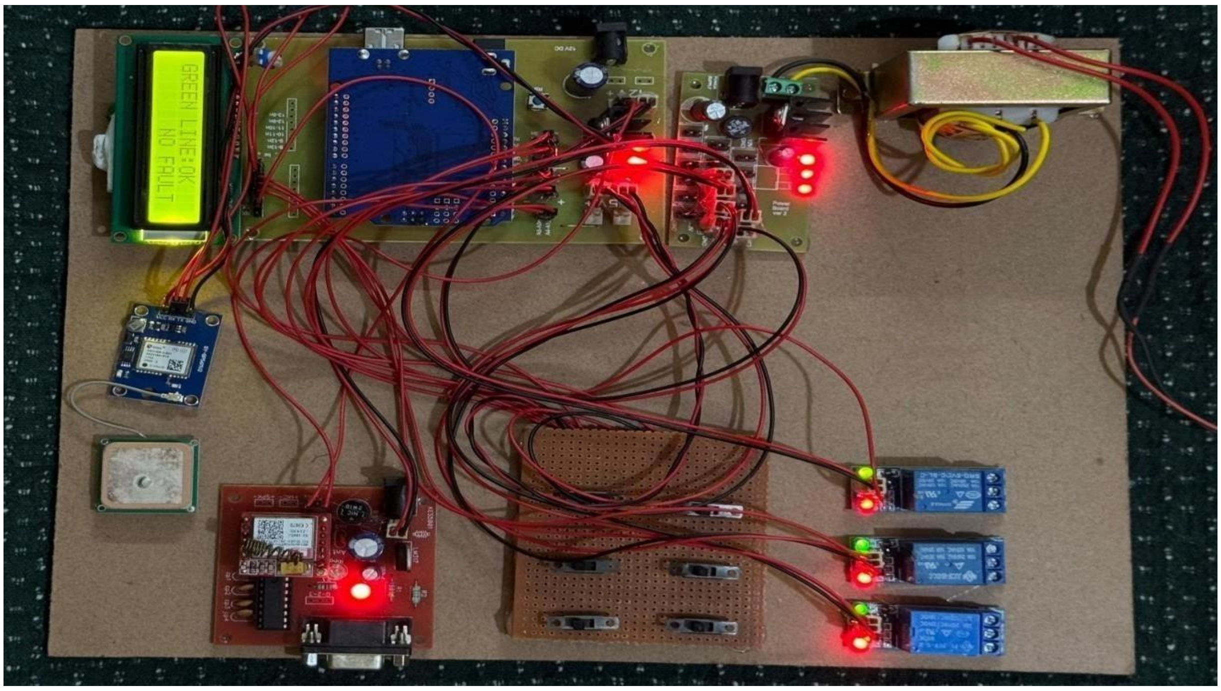
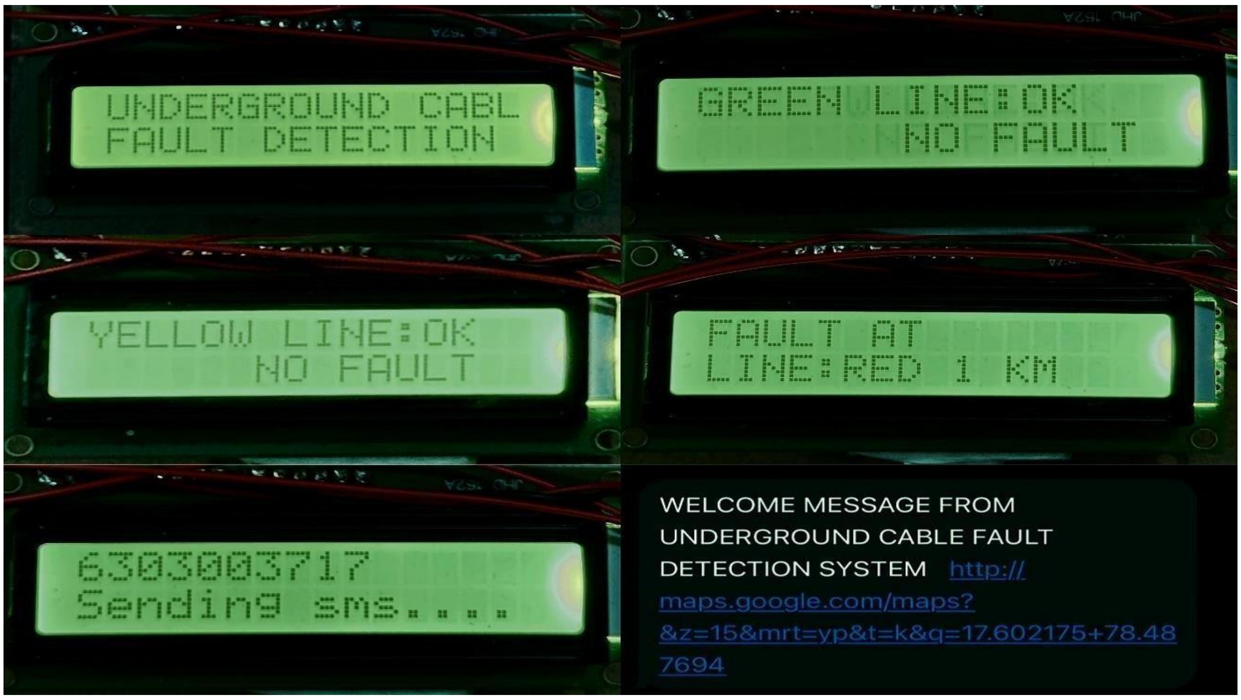


Figure: 8.1 Underground Cable Fault Detection Device



```
UNDERGROUND CABL
FAULT DETECTION
```

```
GREEN LINE:OK
      NO FAULT
```

```
YELLOW LINE:OK
      NO FAULT
```

```
FAULT AT
LINE:RED 1 KM
```

```
6303003717
Sending sms....
```

WELCOME MESSAGE FROM UNDERGROUND CABLE FAULT DETECTION SYSTEM http://maps.google.com/maps?&z=15&mrt=yp&t=k&q=17.602175+78.487694

Figure: 8.2 Displaying faults and alerting user

9 CONCLUSION

The Smart IoT-based Underground Cable Fault Detection system presents an advanced and efficient solution for monitoring and managing underground cable networks. This cutting-edge system combines several innovative technologies to provide real-time fault detection and precise fault localization, greatly improving the reliability and maintainability of underground cable networks. By utilizing an Arduino microcontroller as the core of the system, the solution seamlessly integrates sensors for current and voltage measurement. These sensors play a critical role in detecting anomalies within the electrical parameters of the cable network. The incorporation of IoT connectivity, via GSM or Wi-Fi modules, enables the system to transmit real-time fault information to technicians or monitoring stations, allowing for swift and informed decision-making. The system's fault detection mechanism is based on the principles of Ohm's Law, which uses electrical resistance variations to identify faults accurately. This method not only determines the occurrence of a fault but also calculates its precise location within the cable. An LCD display is included to visually present the fault details, ensuring that technicians on-site have access to clear and actionable data. Additionally, the system's ability to send remote alerts further minimizes response times, enabling prompt repairs and reducing overall downtime. One of the most notable advantages of this system is its automation, which eliminates the need for manual inspections. Traditional fault detection methods are labor- intensive, time-consuming, and prone to errors, whereas this automated approach streamlines the entire process. By reducing repair times and costs, the system offers a cost-effective and efficient solution for modern cable network management. The integration of IoT technology significantly enhances the system's functionality by enabling remote monitoring and real-time notifications. Maintenance teams can now supervise cable networks from centralized locations, ensuring that faults are addressed promptly and efficiently. This feature is particularly beneficial for large- scale infrastructure, where manual monitoring is impractical.

In conclusion, the Smart IoT-based Underground Cable Fault Detection system represents a transformative approach to maintaining underground cable networks. By combining advanced technologies such as microcontrollers, IoT connectivity, and automated fault detection mechanisms, this system ensures faster, more accurate fault identification and repair. Its ability to reduce downtime, improve operational efficiency, and provide cost-effective solutions makes it an invaluable tool for modern power distribution and cable network management.

10 FUTURE ENHANCEMENTS

The Underground Cable Fault Detection System using IoT offers significant potential for future advancements that could enhance its functionality, scalability, and overall performance. One of the most promising developments would be the integration of cloud-based data storage and processing. By shifting to the cloud, the system could enable real-time data logging and monitoring, while also allowing remote access for users anywhere in the world. Cloud integration would also facilitate the analysis of fault history and enable predictive maintenance through advanced data analytics, allowing for proactive fault detection before they occur. Additionally, incorporating Artificial Intelligence (AI) and Machine Learning (ML) algorithms could further optimize the fault detection process, enabling the system to learn from past incidents and predict potential failures based on trends and patterns, thereby minimizing downtime and reducing the likelihood of future faults. Furthermore, as the system evolves, it could be integrated with broader smart city infrastructure, creating an ecosystem that enhances utility management and improves response times. Through this integration, the system could automate fault detection, reporting, and repairs, making it more efficient and responsive. Another potential enhancement is the use of drones equipped with thermal imaging sensors to visually inspect underground cables. These drones could offer additional insights that are difficult to capture with ground-based sensors alone, improving maintenance and fault diagnosis. In terms of power management, incorporating solar power and advanced battery management systems could make the solution more energy-efficient, sustainable, and cost-effective, especially in areas lacking a stable power supply.

Developing a mobile application for end-users and technicians would further improve the system's accessibility, allowing users to receive real-time updates, fault alerts, and system status directly on their smartphones. Additionally, enhancing the GPS system by integrating multiple global navigation systems like GLONASS or Galileo could provide better location accuracy in areas with poor satellite signals, increasing the reliability of the fault detection system. Lastly, integrating Augmented Reality (AR) technology could offer technicians a more intuitive and efficient way to visualize underground cables and pinpoint faults, transforming the way maintenance is conducted in the field.

By incorporating these future enhancements, the Underground Cable Fault Detection System could evolve into a more intelligent, autonomous, and efficient solution, capable of preventing failures, improving response times, and reducing maintenance costs.

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