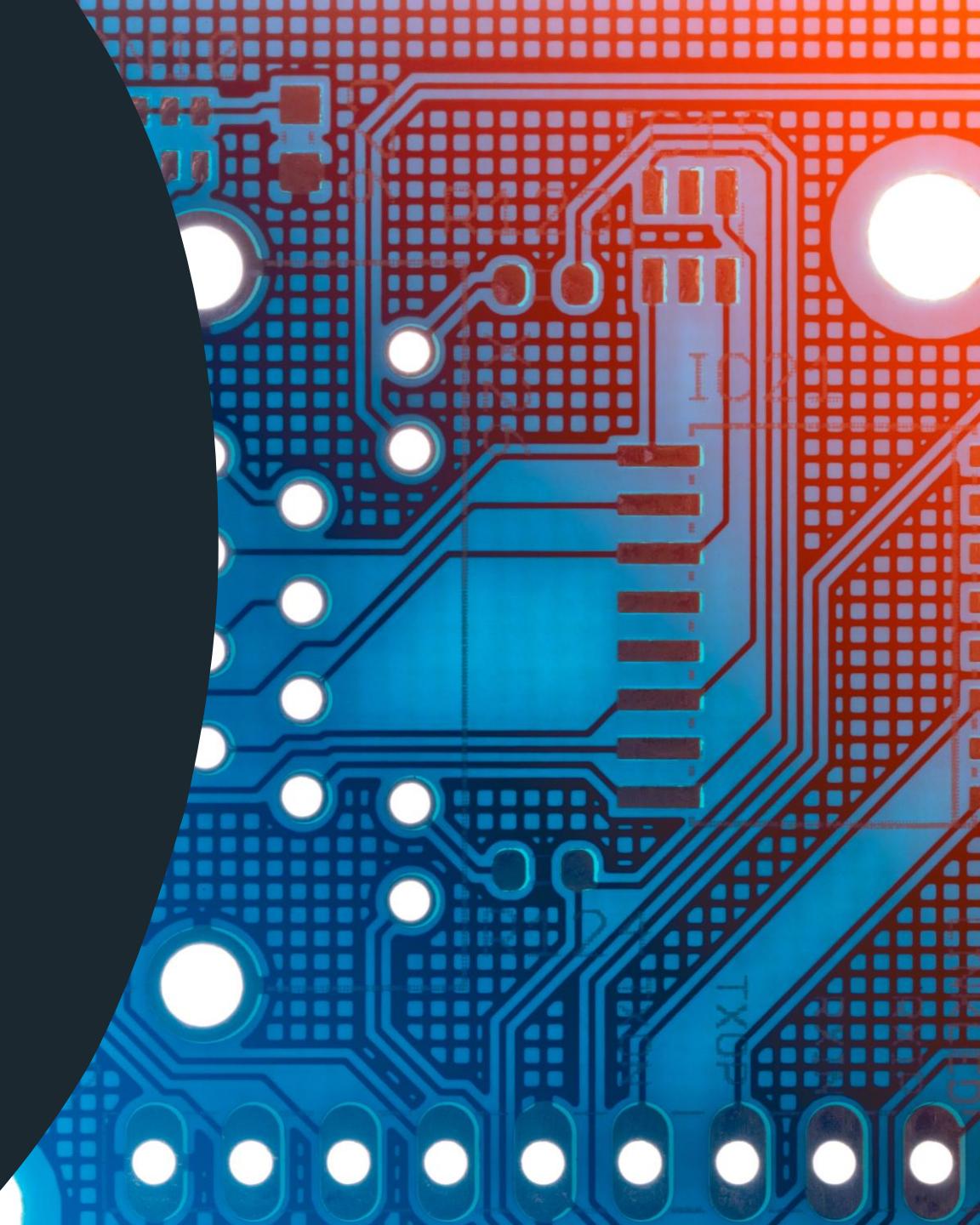


Autonomous Ambulance System

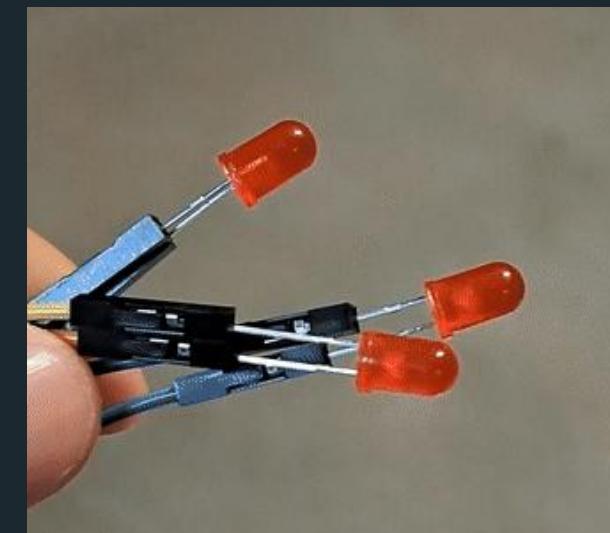
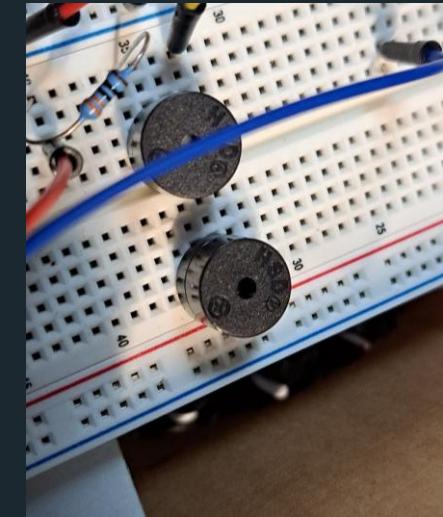
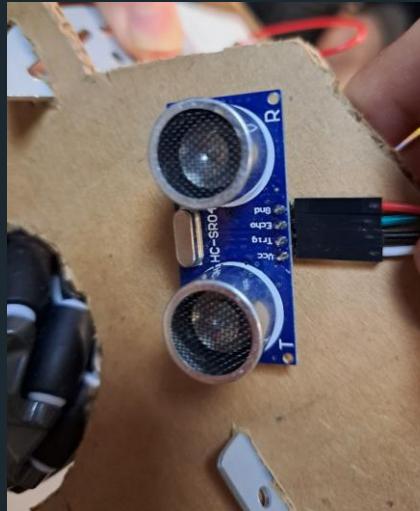
By: Enrique Garcia, Luis Garcia, Yahir Dominguez,
Jacob Tenorio, Sam Herrea, Jorge Del Angel



Introduction Arduino-Powered DC Ambulance

Objective: design, manufacture and create a fully autonomous Arduino powered DC motor ambulance with three main functions:

1. Ability to maneuver and detect obstacles(turning when appropriate)
2. Proper LED system
3. Buzzer for sirens



Components of the Ambulance

Breadboard

Arduino
UNO

DC motor

LED lights

Buzzer

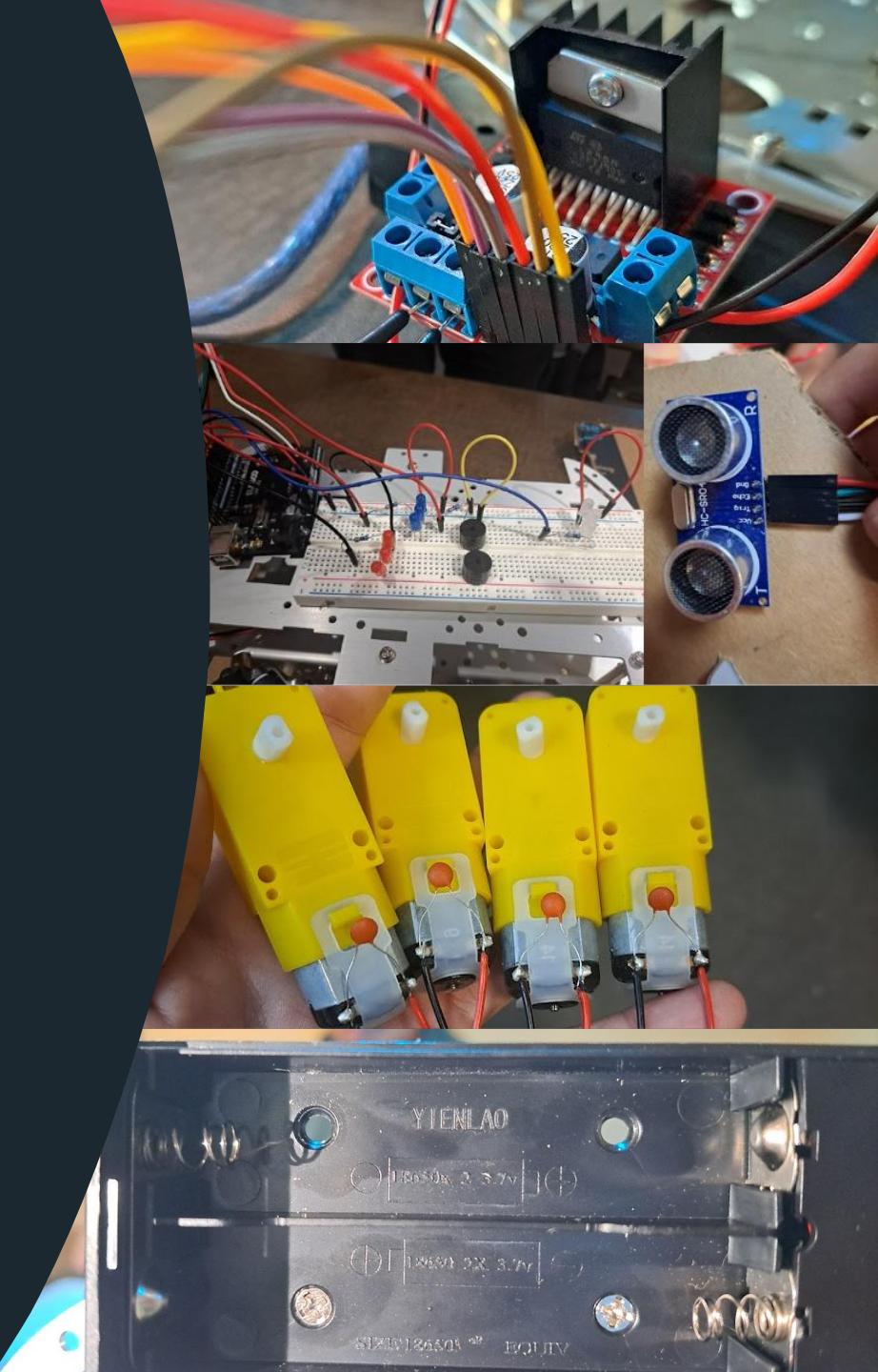
DC motor
drive

Power
supply

Ultra-Sonic
Sensor

Wires (M-F ,
M-M,)

Resistors



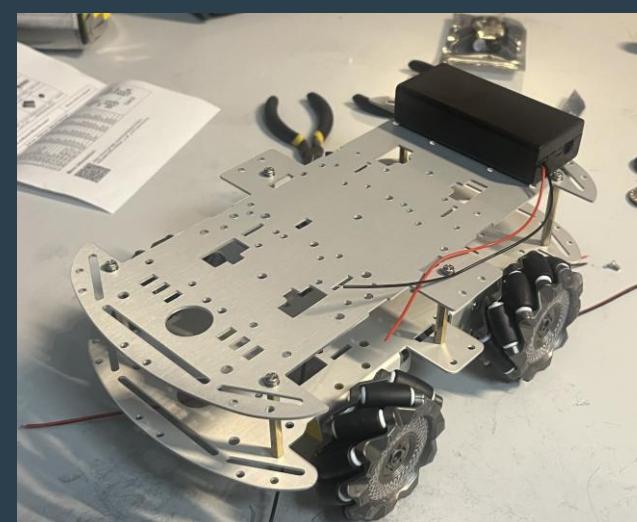
Items and their prices

Item Description	Vendor/Store	Cost (USD)
ELEGOO UNO Project Super Starter Kit	Amazon	\$35.99
Car Kit with Metal Chassis and TT Motor Smart Robot 4WD	Amazon	\$26.90
Buzzers(Pack of 10)	Amazon	\$6.98
3.7V Batteries(2)	Amazon	\$9.98
Motor Driver Controller Board	Amazon	\$6.99

Initial attempt to making the Body of the Ambulance

Initial Problems

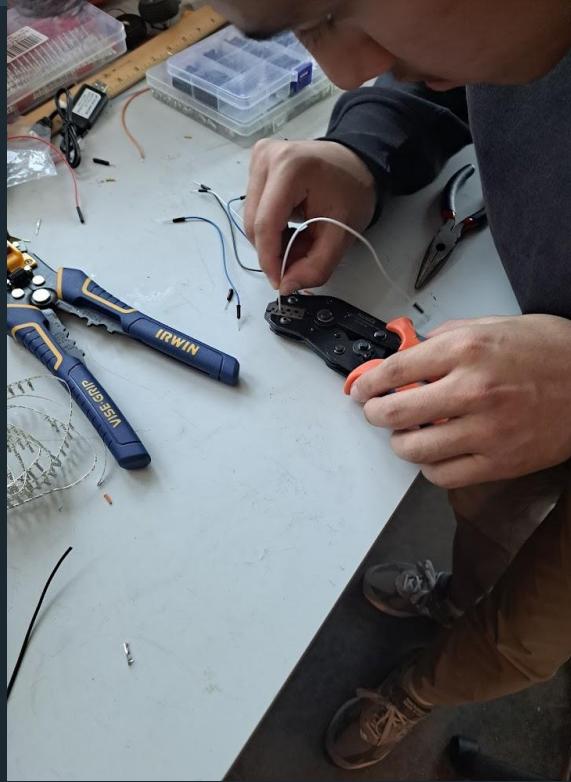
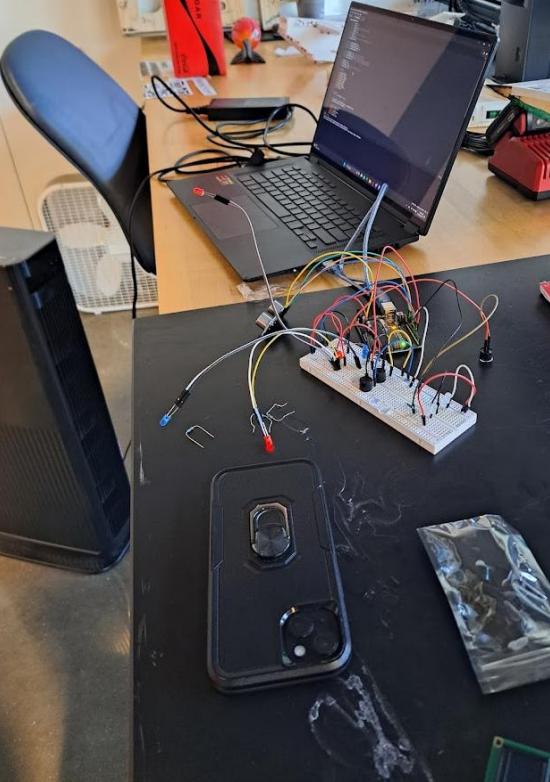
- Motors were not pre-soldered with wires
- No clear instructions provided to assemble
- We didn't know how to make the LED light or buzzers work



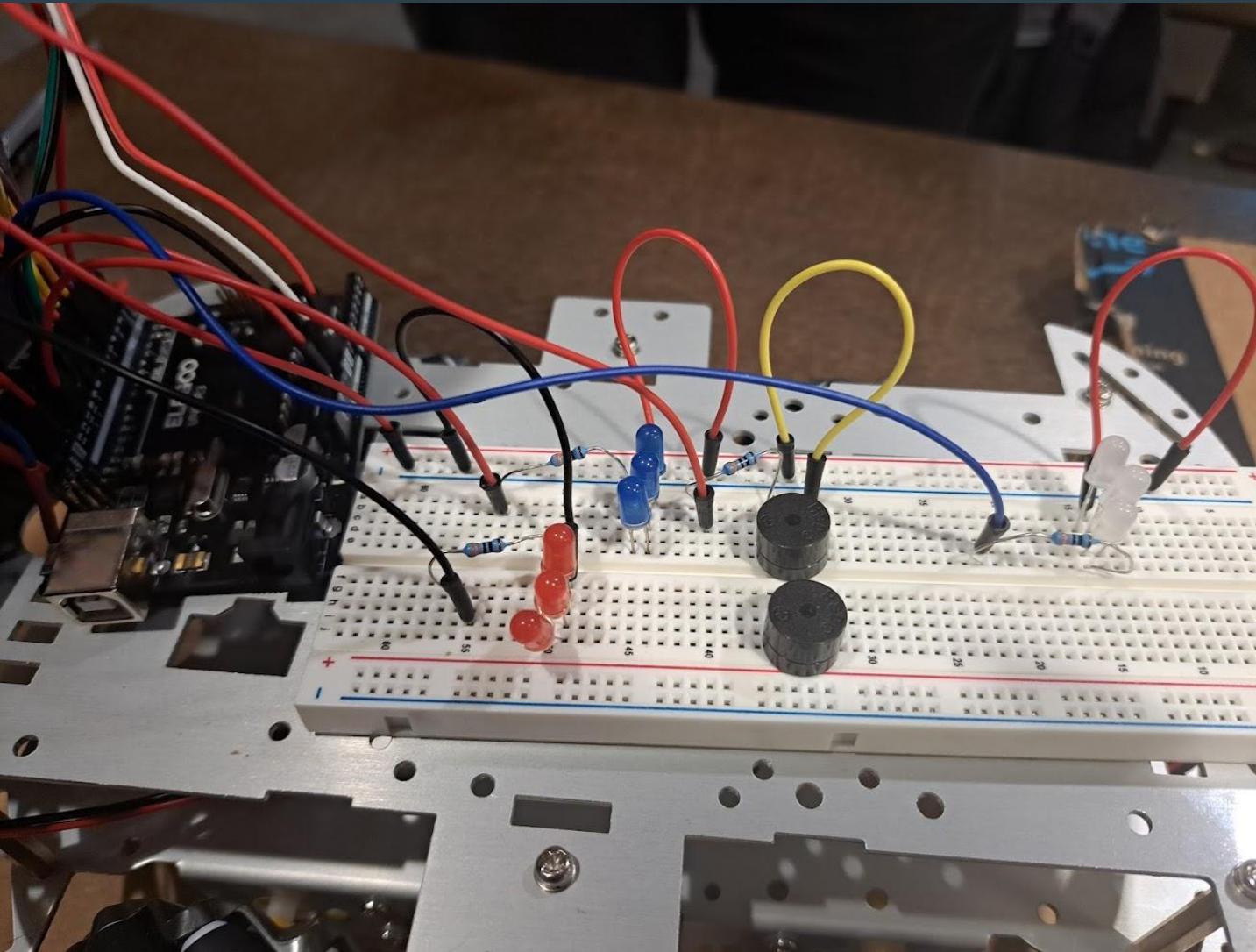
Initial attempt into making the Circuits work

Initial Circuits Problems

- No Motor Drive (without it motors won't run)
- No batteries (no power in the circuit)
- Didn't have enough M-F wires (LED lights needed extension)
- We forgot to use Resistors causing an LED to pop



Circuit of the LED light and Buzzer



Initial code for LED lights and Buzzers (sensor too)

```
const int LEDpin = 7;
const int LEDPin = 6;
const int BuzzerPin = 8; // Define the buzzer pin
const int trigPin = 11;
const int echoPin = 12;
const int ledPin = 13; // Built-in LED on pin 13
float duration, distance;

void setup() {
    // Initialize pins
    pinMode(LEDpin, OUTPUT);
    pinMode(LEDPin, OUTPUT);
    pinMode(BuzzerPin, OUTPUT);
    pinMode(trigPin, OUTPUT);
    pinMode(echoPin, INPUT);
    pinMode(ledPin, OUTPUT);
    Serial.begin(9600);
}
```

```
void loop() {
    // Alternate LED flash to simulate ambulance lights
    // Trigger the ultrasonic sensor
    digitalWrite(trigPin, LOW);
    delayMicroseconds(2);
    digitalWrite(trigPin, HIGH);
    delayMicroseconds(10);
    digitalWrite(trigPin, LOW);

    // Measure the distance
    duration = pulseIn(echoPin, HIGH);
    distance = (duration * 0.0343) / 2;

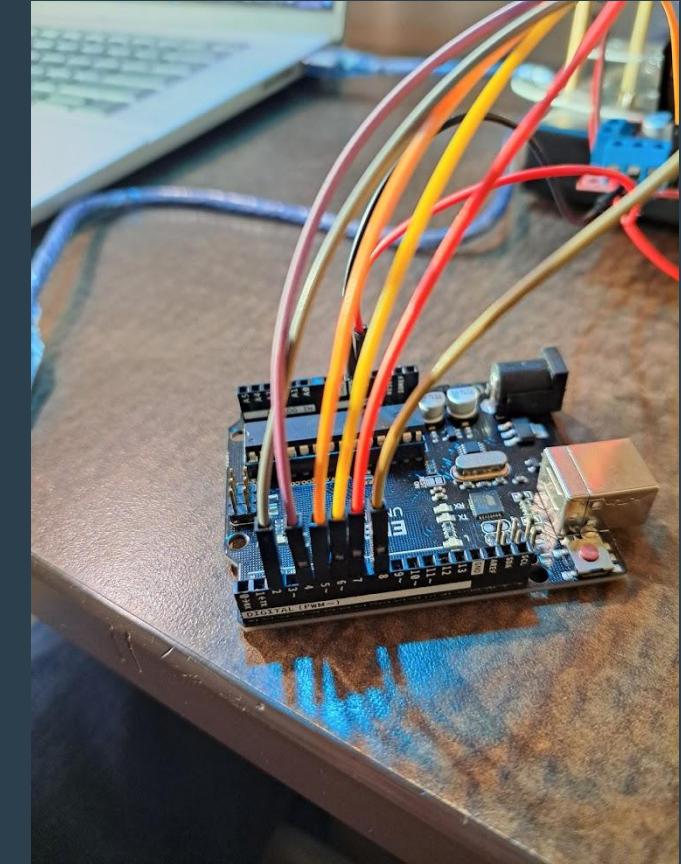
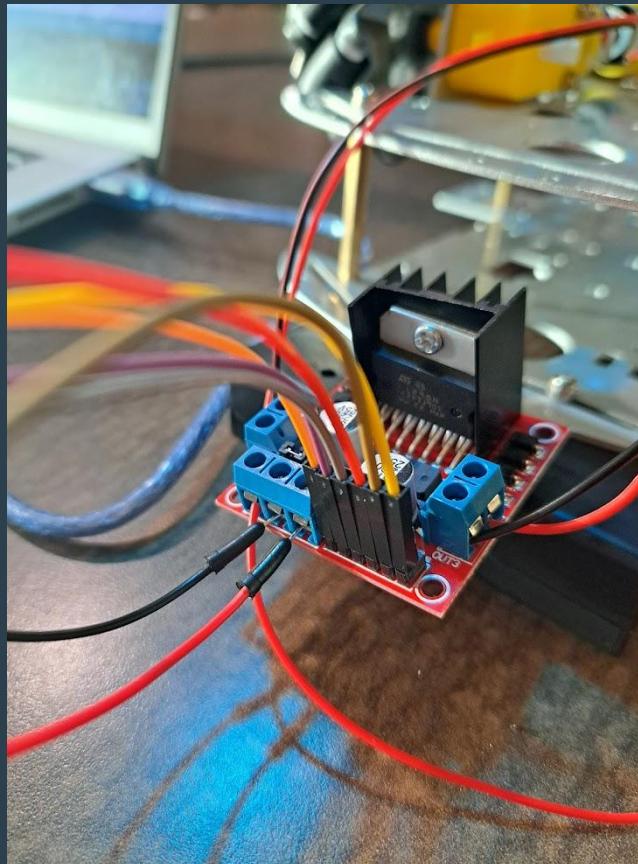
    // Print the distance
    Serial.print("Distance: ");
    Serial.print(distance);
    Serial.println(" cm");

    digitalWrite(LEDpin, HIGH);
    tone(BuzzerPin, 700); // Play 700 Hz sound
    delay(100); // LED on for 250 ms
    digitalWrite(LEDpin, LOW);
    delay(100);

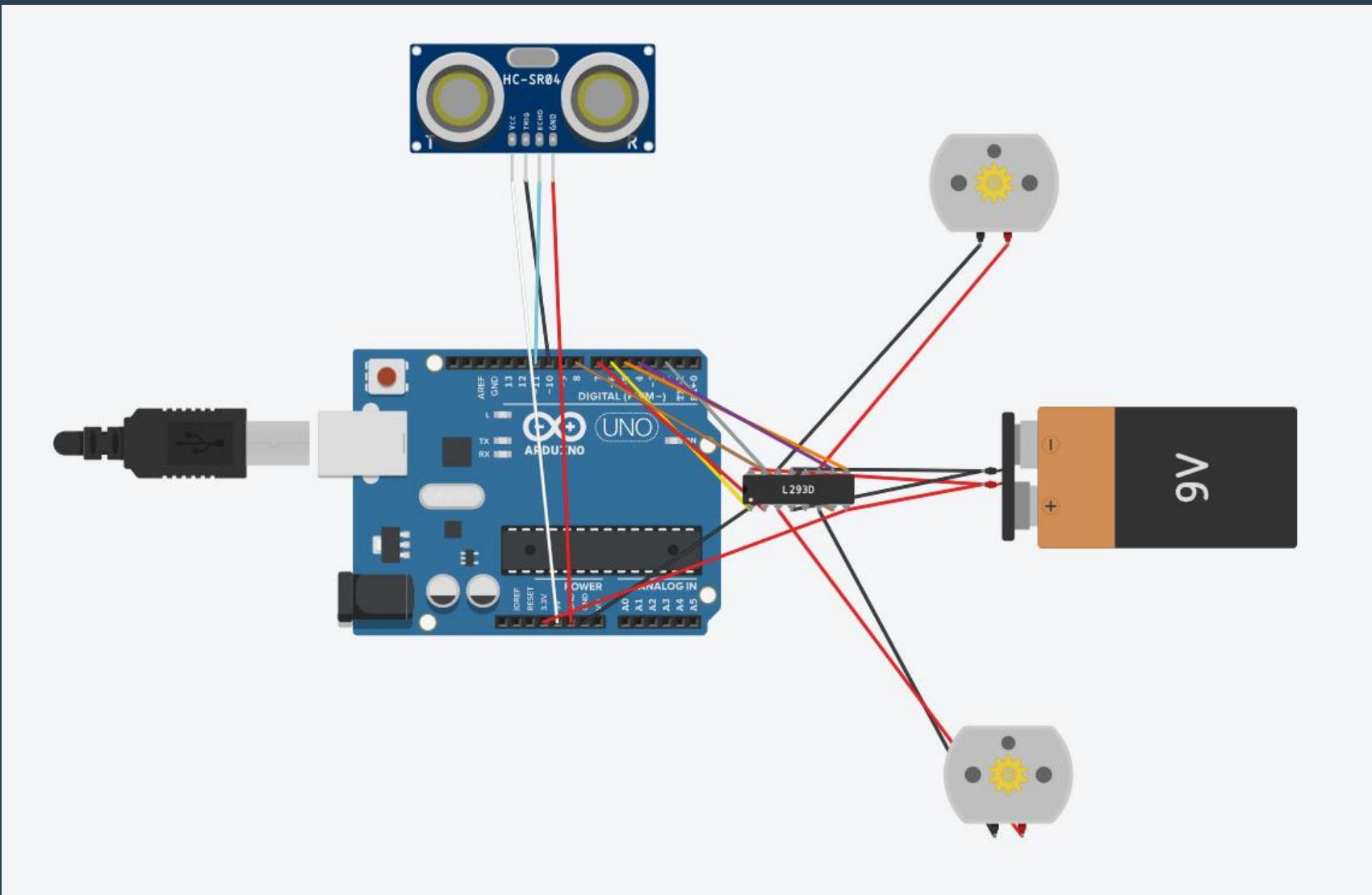
    digitalWrite(LEDPin, HIGH);
```

Initial attempt to test the motors

- We accidentally didn't connect the wires correctly which lead to one of the motor drivers popping
- Initial code wouldn't work



Initial Motor + Sensor Circuit



Code to test motors

```
#define Lpwm_pin 5      //pin of controlling speed---- ENA of motor driver board
#define Rpwm_pin 6      //pin of controlling speed---- ENB of motor driver board
int pinLB=2;           //pin of controlling turning---- IN1 of motor driver board
int pinLF=4;           //pin of controlling turning---- IN2 of motor driver board
int pinRB=7;           //pin of controlling turning---- IN3 of motor driver board
int pinRF=8;           //pin of controlling turning---- IN4 of motor driver board

long duration;
int distance;

const int trigPin = 11;
const int echoPin = 10;

void setup()
{
  pinMode(pinLB,OUTPUT); // /pin 2
  pinMode(pinLF,OUTPUT); // pin 4
  pinMode(pinRB,OUTPUT); // pin 7
  pinMode(pinRF,OUTPUT); // pin 8
  pinMode(Lpwm_pin,OUTPUT); // pin 5 (PWM)
  pinMode(Rpwm_pin,OUTPUT); // pin6(PWM)

  pinMode(trigPin, OUTPUT);
  pinMode(echoPin, INPUT);
  Serial.begin(115200);
}
```

```
void loop()
{
  digitalWrite(trigPin, LOW);
  delayMicroseconds(2);

  digitalWrite(trigPin, HIGH);
  delayMicroseconds(10);
  digitalWrite(trigPin, LOW);

  duration = pulseIn(echoPin, HIGH);

  distance = duration * 0.034 /2;

  if (distance <= 10){
    stopp();
  }

  else{
    advance();
    Set_Speed(1500);
    delay(2000);
  }
}
```

```
void Set_Speed(unsigned char pwm) //function of setting speed
{
  analogWrite(Lpwm_pin,pwm);
  analogWrite(Rpwm_pin,pwm);
}

void advance() // going forward
{
  digitalWrite(pinRB,LOW); // making motor move towards right rear
  digitalWrite(pinRF,HIGH);
  digitalWrite(pinLB,LOW); // making motor move towards left rear
  digitalWrite(pinLF,HIGH);
}

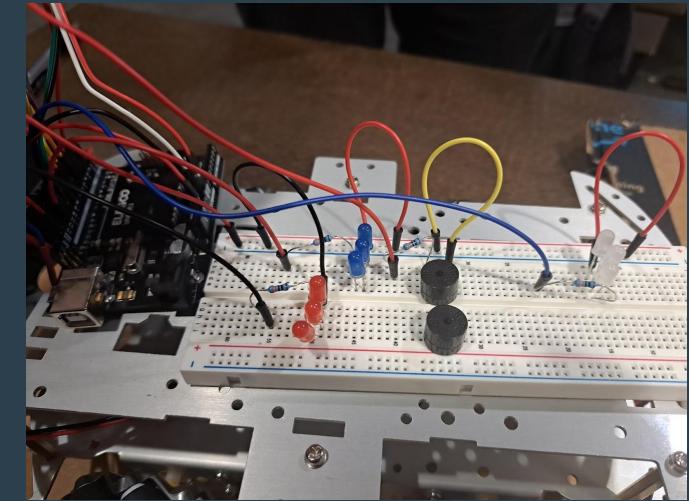
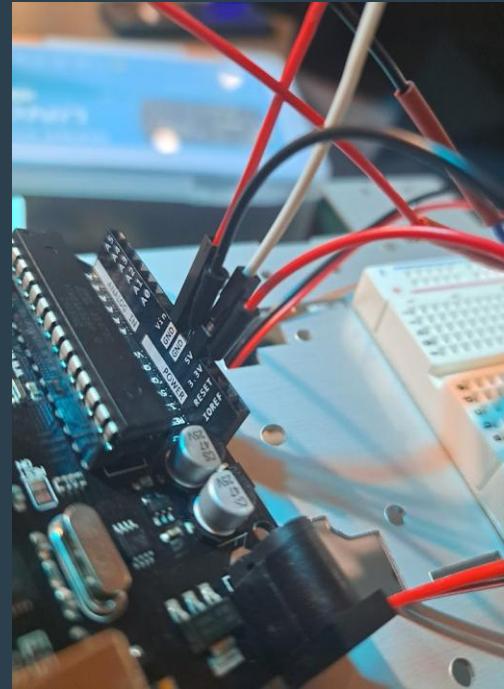
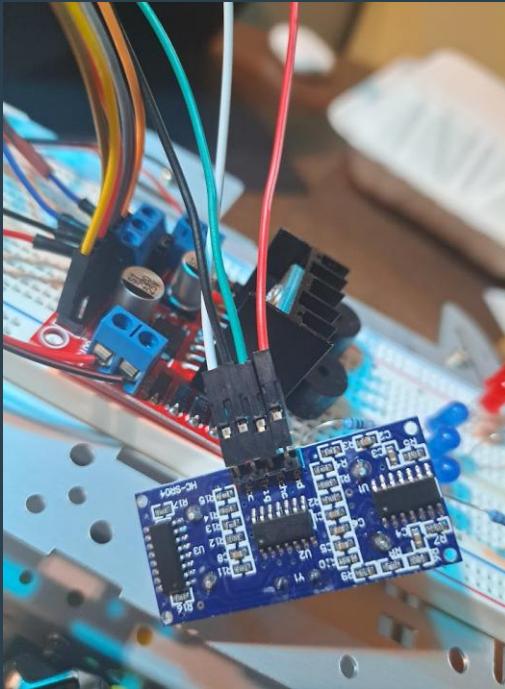
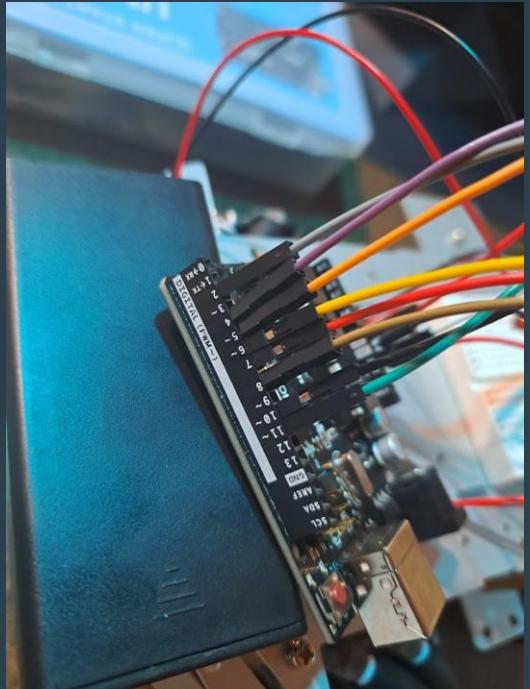
void turnR() //turning right(dual wheel)
{
  digitalWrite(pinRB,LOW); //making motor move towards right rear
  digitalWrite(pinRF,HIGH);
  digitalWrite(pinLB,HIGH);
  digitalWrite(pinLF,LOW); //making motor move towards left front
}

void turnL() //turning left(dual wheel)
{
  digitalWrite(pinRB,HIGH);
  digitalWrite(pinRF,LOW ); //making motor move towards right front
  digitalWrite(pinLB,LOW); //making motor move towards left rear
  digitalWrite(pinLF,HIGH);
}

void stopp() //stop
{
  digitalWrite(pinRB,HIGH);
  digitalWrite(pinRF,HIGH);
  digitalWrite(pinLB,HIGH);
  digitalWrite(pinLF,HIGH);
}

void back() //back up
{
  digitalWrite(pinRB,HIGH); //making motor move towards right rear
  digitalWrite(pinRF,LOW );
  digitalWrite(pinLB,HIGH); //making motor move towards left rear
  digitalWrite(pinLF,LOW );
}
```

Bringing the LEDs, buzzer, sensors, and motors all together



Final Code – Initial Part of Code

```
// Define pins for LEDs, Buzzer, Ultrasonic sensor, and motors
const int LEDpinRED = 13;          // Red LED pin
const int LEDpinBLUE = 12;          // Blue LED pin
const int alertLEDpinWHITE = 9;    // White LED for alert indication
const int buzzerPin = 2;           // Buzzer pin for wailing siren

// Motor control pins
#define Lpwm_pin 5                 // PWM pin for left motor speed control (ENA)
#define Rpwm_pin 6                 // PWM pin for right motor speed control (ENB)
const int pinLB = 3;              // Left motor backward control (IN1)
const int pinLF = 4;              // Left motor forward control (IN2)
const int pinRB = 7;              // Right motor backward control (IN3)
const int pinRF = 8;              // Right motor forward control (IN4)

// Ultrasonic sensor pins
const int trigPin = 11;
const int echoPin = 10;

// Variables for distance measurement
long duration;
int distance;

// Timer variables for non-blocking delays
unsigned long previousMillisLED = 0;
unsigned long previousMillisUltrasonic = 0;
unsigned long previousMillisSiren = 0;

// Time intervals for updates (in milliseconds)
const long intervalLED = 250;      // Interval for LED flashing
const long intervalUltrasonic = 100; // Interval for ultrasonic sensor update
const long intervalSiren = 10;       // Interval for wailing siren frequency update

// Wailing siren control variables
bool ledState = false;
int sirenFrequency = 500;          // Initial frequency for the siren
bool sirenIncreasing = true;        // Flag to control frequency increase/decrease
```

```
void setup() {
    // Initialize pins for LEDs, Buzzer, Ultrasonic sensor, and motors
    pinMode(LEDpinRED, OUTPUT);
    pinMode(LEDpinBLUE, OUTPUT);
    pinMode(alertLEDpinWHITE, OUTPUT);
    pinMode(buzzerPin, OUTPUT);

    pinMode(Lpwm_pin, OUTPUT);
    pinMode(Rpwm_pin, OUTPUT);
    pinMode(pinLB, OUTPUT);
    pinMode(pinLF, OUTPUT);
    pinMode(pinRB, OUTPUT);
    pinMode(pinRF, OUTPUT);

    pinMode(trigPin, OUTPUT);
    pinMode(echoPin, INPUT);

    Serial.begin(115200); // Start serial communication for debugging
}
```

Final Code – The Loop

```
void loop() {
    unsigned long currentMillis = millis();

    // Update ultrasonic sensor every intervalUltrasonic ms
    if (currentMillis - previousMillisUltrasonic >= intervalUltrasonic) {
        previousMillisUltrasonic = currentMillis;
        updateUltrasonicSensor();
    }

    // Update LEDs every intervalLED ms
    if (currentMillis - previousMillisLED >= intervalLED) {
        previousMillisLED = currentMillis;
        toggleLEDs();
    }

    // Update wailing siren frequency
    if (currentMillis - previousMillisSiren >= intervalSiren) {
        previousMillisSiren = currentMillis;
        updateSiren();
    }

    // Function to update ultrasonic sensor and control motors based on distance
    void updateUltrasonicSensor() {
        // Trigger the ultrasonic sensor
        digitalWrite(trigPin, LOW);
        delayMicroseconds(2);
        digitalWrite(trigPin, HIGH);
        delayMicroseconds(10);
        digitalWrite(trigPin, LOW);

        // Measure the distance
        duration = pulseIn(echoPin, HIGH);
        distance = (duration * 0.0343) / 2;

        // Print the measured distance
        Serial.print("Distance: ");
        Serial.print(distance);
        Serial.println(" cm");
    }
}
```

```
// Control motors and LED based on distance
if (distance < 10) {

    stopp();
    delay(500);
    back();
    delay(500);
    turnR();
    delay(500);
} else if (distance < 30) {
    digitalWrite(alertLEDpinWHITE, HIGH); // Turn on alert LED
    stopp();
    delay(500);
    turnR();
    delay(500);
} else {
    digitalWrite(alertLEDpinWHITE, LOW); // Turn off alert LED
    advance();
    setSpeed(150); // Set a valid PWM speed
}
```

Final Code – Functions for the Ambulance

```
// Function to toggle LEDs for flashing effect
void toggleLEDs() {
    ledState = !ledState; // Toggle LED state
    digitalWrite(LEDpinRED, ledState ? HIGH : LOW);
    digitalWrite(LEDpinBLUE, !ledState ? HIGH : LOW);
}

// Function to control the wailing siren sound
void updateSiren() {
    tone(buzzerPin, sirenFrequency); // Play the current frequency

    // Adjust the frequency to create the wailing effect
    if (sirenIncreasing) {
        sirenFrequency++;
        if (sirenFrequency >= 1000) sirenIncreasing = false; // Reverse direction at max frequency
    } else {
        sirenFrequency--;
        if (sirenFrequency <= 500) sirenIncreasing = true; // Reverse direction at min frequency
    }
}
```

```
// Function to set motor speed (PWM)
void setSpeed(unsigned char pwm) {
    analogWrite(Lpwm_pin, pwm);
    analogWrite(Rpwm_pin, pwm);
}

// Motor control functions
void advance() { // Move forward
    digitalWrite(pinRB, LOW);
    digitalWrite(pinRF, HIGH);
    digitalWrite(pinLB, LOW);
    digitalWrite(pinLF, HIGH);
}

void turnR() { // Turn right
    digitalWrite(pinRB, LOW);
    digitalWrite(pinRF, HIGH);
    digitalWrite(pinLB, HIGH);
    digitalWrite(pinLF, LOW);
}

void turnL() { // Turn left
    digitalWrite(pinRB, HIGH);
    digitalWrite(pinRF, LOW);
    digitalWrite(pinLB, LOW);
    digitalWrite(pinLF, HIGH);
}

void stopp() { // Stop motors
    digitalWrite(pinRB, HIGH);
    digitalWrite(pinRF, HIGH);
    digitalWrite(pinLB, HIGH);
    digitalWrite(pinLF, HIGH);
}

void back() { // Move backward
    digitalWrite(pinRB, HIGH);
    digitalWrite(pinRF, LOW);
    digitalWrite(pinLB, HIGH);
    digitalWrite(pinLF, LOW);
}
```

Building the Ambulance

- Jubel 225 was the working space
- Budget concerns in terms of CAD and a 2-week queue



Skills List

HARD SKILLS

- Coding
- Crimping
- Soldering
- Wiring (Breadboard)

SOFT SKILLS

- Time management
- Teamwork
- Communication