



# KTH MECHATRONICS ADVANCED COURSE

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FINAL REPORT

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## ESS-NW/ESS-CAR

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## Abstract

Abstract starts here, what should be included:

- The problem issue subject being addressed

- How the problem is tackled

- Overview of the results, and indication as to what level they solve the problem.

- Implications of the results

## Contents

1	Introduction	5
1.1	Background . . . . .	5
1.1.1	Background subsection blabla . . . . .	5
1.2	Project Description . . . . .	5
1.2.1	Project Description sub blabla . . . . .	5
1.3	Delimitations . . . . .	5
1.4	Report disposition . . . . .	5
2	Literature Review and State of the Art	6
3	Methodology	7
3.1	Engineering approaches ? . . . . .	7
3.2	Tool-chains ? . . . . .	7
3.3	Project management . . . . .	7
4	Implementation	8
4.1	System overview . . . . .	8
4.2	Implementing SDN network . . . . .	8
4.3	Communication between Beaglebone and Arduino ? . . . . .	8
4.4	Sensors . . . . .	8
4.4.1	Ultrasonic sensor . . . . .	8
4.4.2	Reflective object sensor . . . . .	8
4.4.3	Camera . . . . .	8
4.5	Controlling actuators . . . . .	9
4.5.1	Steering servo . . . . .	9
4.5.2	Motor ESC . . . . .	9
4.6	Assemble the car, power supply, etc . . . . .	9
5	Verification and Validation	10
6	Results	11
7	Discussion and Conclusion	12
8	Future Work	13

## List of Figures

## List of Tables

## 1 Introduction

This report presents the process and results of two projects "Embedded Service for Self-adaptive Network" (ESS-NW) and "Embedded Service for Self-adaptive Car" (ESS-CAR). This chapter will start by describing the background of the two projects. The next thing to be described is formulation, goals and motivation of the two projects. Following this will be a short discussion on the delimitations for our team. The last part of this chapter will present an explicit report disposition which helps readers to get a sense of the overall report.

### 1.1 Background

#### 1.1.1 Background subsection blabla

### 1.2 Project Description

#### 1.2.1 Project Description sub blabla

### 1.3 Delimitations

### 1.4 Report disposition

## 2 Literature Review and State of the Art

### 3 Methodology

#### 3.1 Engineering approaches ?

#### 3.2 Tool-chains ?

#### 3.3 Project management

Scrum project management is used during the process of our projects.



## 4 Implementation

### 4.1 System overview

maybe put communication diagram here

### 4.2 Implementing SDN network

### 4.3 Communication between Beaglebone and Arduino ?

### 4.4 Sensors

Three categories of sensors are implemented in the prototype vehicle to monitor its surrounding environments. Data from distance sensors and speed sensor will be sent to an Arduino initially, then sent to corresponding Beaglebone. Data from Pi Camera will be sent to the Raspberry Pi which is directly connected to the main network.

#### 4.4.1 Ultrasonic sensor

To get data from HC-SR04, a short 10 $\mu$ s pulse should be supplied to the trig pin of ultrasonic sensor, then the sensor will send out an 8 cycle burst of ultrasound at 40 kHz and raise echo. The echo signal we get is a distance object which is pulse width and the range of the signal is in proportion.

An Arduino Micro handles both the generating the trig pulse and interpreting the echo signal. After the Arduino sends out the trig pulse, it waits for 2 ms, then reads the value from the pin connected to sensor's echo pin.

#### 4.4.2 Reflective object sensor

#### 4.4.3 Camera

In computer vision part, we tried to compare the performance of two different methods, which are object detection based on neural network and color detection using OpenCV.

The technique of transfer learning is used to apply MobileNet on RPI, which is an efficient model for mobile and embedded vision applications. The speed remains slow although hardware acceleration and multiprocessing have been carried out to improve.

By using OpenCV's DNN module, we are able to pass input images through the deep neural network and get a output image with bounding box of specific object and label.

Since we are working on source constrained device Raspberry Pi, we need to make the network simple and decrease the computational cost, so we combined MobileNet with Single Shot Detector.

In order to optimize the Raspberry efficiently and use sufficiently limited resource and memory on it when running neural network, we firstly apply hardware optimization which is to install optimized OpenCV complie. So, ARM NEON as an optimization architecture extension for ARM processors is used. It is used for faster video stream processing, image analysis and speech recognition that is exactly what we are look for in our application. This architecture can execute multiple processing in the pipeline by a single instruction. Besides, VFPV3 as a floating point optimization is also used. After the first stage improvement, we get a 30 percent speed increase since we have make full use of the 4 $\times$  ARM Cortex-A53, 1.2GHz processor on Raspberry Pi, now the network is able to classify an object in 1.5 seconds.

When it comes to second stage of optimization, multiprocessing is used to increase the speed of processing video stream. The I/O tasks, dislike CPU bound operations, always take lots of time and delay the process. So moving the reading of frames to a separate thread from frame processing can obtain higher speed. Otherwise, every time I/O port access Pi camera, the main thread of script is

blocked until the frame is captured and return to script. Multiprocessing can decrease the influence of I/O on CPU heavy application like video stream processing, especially in our real-time case. Now we can obtain a detection result within 1 second.

Additionally, there is a trade off between accuracy and output speed. In our application, we set a threshold for the output, in more details, only when the confidence score of detection result is high enough (above the specified threshold), the result can be output as a signal to steer the car. Otherwise, it will grab another frame and do the object detection for the other iteration. As a result, if the threshold confidence score of output increase, the output speed will decrease.

Since the object detection method outputs result slowly, we move on to the other method which is color detection using OpenCV to see whether the speed is fast enough to be applied on a car prototype. We define the upper and lower limits for pixel values to classify three colors. Then specify which pixels fall into specified upper and lower range by masking. The speed of color detection is fast and also accurate enough for real-time application.

So we finally apply the color detection on our car, we use the result of detection to steer the car.

## 4.5 Controlling actuators

### 4.5.1 Steering servo

### 4.5.2 Motor ESC

## 4.6 Assemble the car, power supply, etc

## 5 Verification and Validation

## 6 Results

## 7 Discussion and Conclusion

## 8 Future Work