

CMPSC 497: Special Topics (Spring 2024)

Final Project: Autonomous Mobile Robot Car

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* **INTRODUCTION**

This project involved programming and testing a robot car to make it run autonomously. The car is able to use its many sensors and additional hardware to navigate a custom-built track all on its own without user input. The car uses an IR sensor to detect what is and isn't track, an ultrasonic sensor to detect when an obstacle is too close, and an additional Raspberry Pi camera to identify road signs such as stop signs, yield signs, and speed limit signs and perform correspondings actions when identified, such as stopping, slowing down, and speeding up. All of this is accomplished through autonomous communication between the robot car's Arduino, and the camera's Raspberry Pi.

* **BACKGROUND**

The Freenove robot car that we recieved came equipped with multiple different features that were all used in our project. The most important is the two-board Arduino that provides power and instruction to the car to allow it to perform it's functions. The car also came equipped with two major sensors, the IR sensor and the ultrasonic sensor.

The IR sensor is located on the bottom of the car, and has three different input pieces. These pieces each individually detect what is beneath the car as it drives. We used the sensors to allow the car to identify when it is and isn't on the track we designed. The car is able to sense the track, which is black with white outlines, using this IR sensor. When it detects black, the car will move, and when it detects white, it will not. When one piece detects white and the others detect black, this will inform the car to turn.

The ultrasonic sensor is located on the front of the car, and is able to send an ultrasonic wave out and accept it's rebound back. Doing this allows the car to determine how far away an obstacle is from itself. We used this sensor to allow the car to have an "emergency brake" feature, that will cause it to automatically stop if it detects an obstacle is too close.

Our final and most important addition to the robot car is the Raspberry Pi and its camera. The Raspberry Pi is able to create a live feed of the connected camera, and using OpenCV, can analyze and identify signs that enter the camera's view. We programmed the Raspberry Pi to be able to identify stop signs, yield signs and speed limit signs. Using the serial monitor of the Arduino, we can send messages from the Raspberry Pi to the Arduino, which will in turn allow the Arduino to command the robot car perform certain actions when the Pi tells it to. This is the system and communication we established between the Arduino and the Pi in order to command the car to stop, slow down or speed up when corresponding road signs are identified by the camera.

* **DEVELOPMENT**

The development process of our project began as soon as we received the robot car. The first thing we did was analyze what materials we would need to complete our project, and we determined what Raspberry Pi camera we would need and asked the professor to order it for us. As we waited for the camera's delivery, we began work on preliminary code for the robot, to test it's basic movement functions and operation.

Using the sample code provided by Freenove as a base, we created a basic functioning code to test the car's movement using an IR remote. This remote sent an IR signal to an input sensor on the top of the car, which would allow us to move the car manually using the remote. However, our project requires the car to be autonomous, and this was only for basic demonstration and testing. Unfortunately, as we began to develop the autonomous code for the car's Arduino, we ran into a problem.

For some reason that alluded us for quite some time, the robot car which functioned perfectly fine with the IR remote before stopped working. Despite the fact that we could tell through LED lights and the serial monitor in the Arduino that the car was indeed recieving input from the remote, the car would not move at all. After trying everything we could, we ended up taking the entire car apart and testing the motors of each wheel individually, as this was the only cause of the problem we could think of. When we confirmed that the motors did indeed work correctly, we eventually solved the error, which ended up being a wiring issue that prevented the motors from receiving the necessary power.

When the Raspberry Pi camera finally came in, we began working with it in order to establish a live video feed. At first, we needed to use a keyboard and monitor in order to connect with the Pi, but eventually we managed to establish a wireless connection to a laptop. At first the camera's feed was rather rough, and would be zoomed in too far into a corner and not show a full view of what is in front of it. Eventually, we fixed this issue by messing with the camera's size settings and the system it was running through. Using OpenCV and training with Cascade files, we were able to train a program to identify a stop sign. We then used this same method to train the program to at first identify right turn and left turn signs. Eventually, we determined that the turn signs were too complex and the training data was not accurate enough, so we abandoned the turn signs in favor of a yield sign and a speed limit sign. We once again used the Cascade files to train the program to now identify yield signs and speed limit signs.

With the basic programming of the Arduino and the Pi almost complete, we began to construct the track that the robot car would run on. We took black paper and white duct tape and created track shaped like the letter P. The car managed to run this track somewhat well, being able to identify what is and isn't track using it's IR sensor to see if it is on black paper or white tape. Unfortunately, the car was not able to follow this track completely accurately, and suffered a lot of errors. We decided to start over with a new track, which was smaller and more manageable. While still shaped like the letter P, we decided to make the track more angular rather than curvy, as the first track was. This way, the car could make turns easier and quicker, as well as not accidentally veer off the track when it hits a turn too quickly.

While the basic Arduino code managed to run the car across this track well enough with minimal issue, when we began to implement the Arduino-Pi communication code, something went wrong. The car began to act awkwardly, and seemingly made wrong turns and wrong decisions when presented with certain obstacles, such as turning when it detects something too close rather than stopping, or making left turns on a right turn when it had no problem doing so before. This was a confusing and shocking change in the car's behavior, as before this, the car seemed to be working perfectly fine. It was following the track correctly with only minimal problems, and was successfully identifying and reacting to obstacles and road signs.

* **PERFORMANCE**
* **CONCLUSION**
* **REFERENCES**
* **APPENDIX**