

# EEE4113F Literature Review



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May 12, 2024

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# Chapter 1

## Introduction

Philosophers have hitherto only interpreted the world in various ways;  
the point is to change it.

—Karl Marx

### 1.1 Background

#### 1.1.1 Problem Statement

Sally, a researcher at the FitzPatrick Institute, needs a way to weigh the red-winged starlings without startling them, because interestingly, they record their weight manually using a kitchen scale.

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## Literature Review

### 3.1 Introduction

Weight is an important metric for evaluating the overall health, behavior and ecology of a bird in ornithological research. However obtaining this weight data presents several challenges due to their size, fragility and often rapid movements. This literature aims to explore and evaluate the different techniques and technologies researchers employ to obtain weight data, the different ways this data could be transmitted and recorded, and the types of devices needed to power such a system. This literature review will also consider the challenges described above and, other environmental and ethical factors that must be taken into account when weighing birds in the wild.

### 3.2 The Importance of Monitoring Avian Weight Changes

According to Clark, “Weight summarizes the total biomass of an individual and is probably the most convenient standard of energetic comparisons.” [2], which emphasizes how valuable the weight data of an individual bird can be. Baldwin and Kendeigh state that “The weight of birds and the variations and fluctuations of these weights furnish criteria of considerable importance in the understanding of the physiological and ecological reactions of the bird as a living organism [3], which further establishes how important the tracking of an individual bird’s weight data can be. Both of these statements cement how valuable weight data can be for ornithologists studying individual birds.

Clark goes on to say, “Weights have been used in analyses of the factors that influence differences in species diversity between communities.” [2]. They also state that “Weights and census data have often been combined to calculate the total biomass of a particular species or group of species in an area”. These statements add that weight data could also be invaluable for the analysis of an entire community of birds as opposed to just monitoring individuals.

### 3.3 Current Weighing Methods

This section examines the different methods and tools used to obtain weight data in ornithological research today.

### 3.3.1 Spring Scales

Spring scales measure weight based on the extension of a spring when a force (the weight of the bird) is applied. Their main advantage, as described by Manolis [4], is that they are “relatively inexpensive and sufficiently portable to suffice for short-term field project[s]”. However, within the same study, the scale was only accurate to within 0,5g and when smaller birds can weigh less than 50g, spring scales may lack the precision for such research applications.

### 3.3.2 Electronic Scales

Electronic scales utilize load cells or strain gauges to convert the weight of the bird into an electronic signal, which can then be displayed on a digital screen. These scales offer precise measurements as shown by Carpenter et al. [5], where they were able to improve the precision of their measurements from 0,05g to 0,01g, by simply replacing their spring scales with electronic ones. Another advantage over spring scales, is that they do not have to be recalibrated after moving [5] and they tend to come with features such as taring functions to account for the weight of the housing holding the bird.

### 3.3.3 Perching Scales

Perching scales integrate a weighing platform into an artificial perch or nest. In Poole and Shoukimas' [6] study, birds landing on perch would deflect a transducer (a metal beam with 4 strain gauges bonded to it), thus generating an electronic signal. Reid et al. [7] used artificial nests rigged with a load cell in much the same way. In both studies, these electronic signals would then be recorded via some kind of electronic storage medium. This meant the birds could be weighed remotely, which minimizes stress and reduces the risk of injury, making perching scales particularly useful for long-term monitoring studies or behavioural observations. However, for such long-term studies, researchers would need to keep track of a large number of birds, which would also result in a large amount of data that needs to be stored.

Manolis [4] provides a solution to these issues by urging other researchers to make use of telemetry. One such technology is Radio Frequency Identification (RFID) which enables researchers to track individual birds and record their weight automatically. Wang et al. [8] made use of RFID by attaching two transponders to each bird, which would be detected by antennas placed under the perches. When a tagged bird interacts with the RFID reader, its unique identifier and weight are recorded electronically, making the data much easier to organise. It also reduces the volume of data created as the weight is only taken when the birds are on top of the perch. This allows researchers to collect data on a larger scale but this data need not be stored locally.

## 3.4 Data Transmission and User Interface

The method that the FitzPatrick Institute currently have for reading the bird weight is having one of the researchers go up to the scale and read off the screen. They then record the weight into *Cybertracker* [9], a mobile app that creates an Excel spreadsheet for them to analyze later. This highlights a need for a way to access that data remotely; or perhaps, a way to send that data directly to the Cybertracker app.

There are many communication protocols for transmitting data from a microprocessor. In a comparative performance study by Eridani et al., three protocols were compared: Bluetooth, Wi-Fi direct, and ESP-NOW ('a new protocol that allows multiple devices to communicate with each other without the use of Wi-Fi, with low power consumption' [1]). Five metrics were used in the tests: maximum range, transmission speed, latency, power usage, and signal resistance to obstructions [1]. A brief summary of the performance of each protocol is shown below in Figure 3.1.

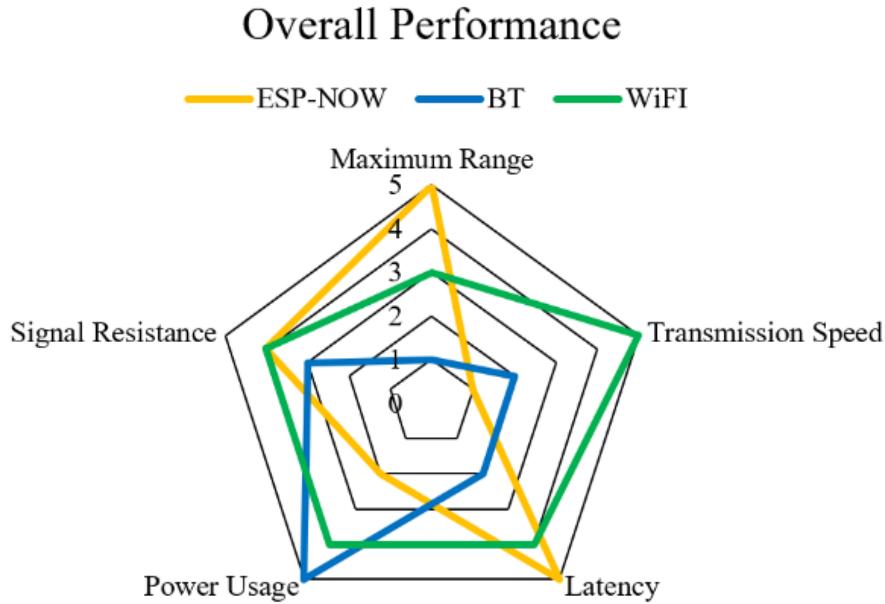


Figure 3.1: Overall Performance of each Protocol [1]

ESP-NOW performs best in range and latency; Bluetooth in power usage; and Wi-Fi in transmission speed.

Budoyo and Andriana used the internet when designing a prototype of a digital scale to measure the weight of onions. [10]. They interfaced the microcontroller (an ATMega2560) to the internet using an ESP8266 Wi-Fi module. The weight data is sent to a website where it is stored in a database. A database is useful in creating an Excel spreadsheet with many fields which is the end product that the client requires.

## 3.5 Power supply

Traditional weighing scales have relied on either battery or electric power sources for operation. Battery-powered scales utilize internal batteries, commonly alkaline or lithium-ion, to supply the necessary electrical power. This section will discuss the different types of power supplies available for bird scales and the power limitations on what type of power source the final design can use.

### 3.5.1 Wall Power

For indoor scales, which are in a fixed to one spot, the electric-type scales are directly connected to a power source via a cord, typically drawing from AC power provided by a wall outlet. These type of

scales are used in laboratories and residential environments.

### 3.5.2 Energy Harvesting

One other method researchers use in low powered bird scales is Energy Harvesting. Energy Harvesting is used to extend the lifespan of the scale and sensing devices, however the process is not always effective [11]. An example of energy harvesting would be using wind or solar as a power source to the scale device. This concept is useful in situations where the scale is left in the field for data capture, and only accessed after a prolonged period of time. It is worth noting that low-power weighing scales are an existing topic, where in some cases there are scales and sensors that are able to take measurements, read and communicate the data in real time [12].

### 3.5.3 Limitations

The reliance on electrical power poses serious constraints, particularly in terms of mobility. This limitation becomes pronounced in specialized applications such as bird weighing scales, especially for very mobile birds such as the starlings. A better solution is to use a rechargeable battery source, such as the alkaline batteries mentioned above. Environmental conditions also pose a risk to the battery lifespan. Solar panels can pose collision risks for birds, particularly if the panels are highly reflective. Some birds may collide with solar panels while flying, leading to injury or mortality.

## 3.6 Challenges and Considerations

While modern weighing methods offer significant advantages in terms of accuracy, convenience, and animal welfare, researchers must consider several factors when selecting the most appropriate technique for their study.

### 3.6.1 Size and Species

The size and behaviour of the target bird species may influence the suitability of different weighing methods. Some birds may become skittish around researchers which would make measurements unreliable. In Manolis' case [4], they had to use binoculars to take readings of the scale from afar; an inconvenience that is entirely removed from the solutions presented by Poole and Shoukimas [6] and Reid et al. [7]. Smaller birds may require scales with higher precision, while larger species may benefit from perching scale systems capable of handling multiple subjects simultaneously.

### 3.6.2 Environmental Conditions

Field studies often expose equipment to challenging environmental conditions. For example, Manolis [4] had to keep swaying to a minimum to get accurate readings, hence spring scales would not be suitable in windy conditions. Rain can seriously damage electronic components so it was important for Reid et al. [7] to house the amplifier unit in “a small water-resistant case with a sealed connection to the data logger cable”. Researchers must choose weighing methods that are robust and reliable under these circumstances, with weather-resistant features where necessary.

### 3.6.3 Material Considerations

An important consideration that our design would need to fulfill is that it is safe for use on birds. Given that they will be in direct contact with the scale, toxicity is a primary concern when considering the materials used to construct the scale.

In the design of an electronic scale, artificial materials such as plastics are an attractive option due to their naturally weatherproof properties. However, caution must be exercised when considering specific materials. Artificial materials such as polytetrafluoroethylene (PTFE) are a common source for airborne toxicity in avians [13]. However, in a paper by Kroshefsky [14] this material is only cause for toxicity concern when exposed under high temperatures. This is because PTFE begins to decompose in air at around 200°C. Even if the scale is placed outdoors, the ambient temperature will be well under this temperature limit, making this material a viable choice in the housing.

Heavy metal poisoning is another important concern when it comes to our choice of materials. The most common occurrences of which come from the ingestion of lead [15]. When lead is ingested, it can be absorbed in the gastrointestinal tract and then taken up by soft tissues and eventually bone [15]. The paper by C. Pollock includes a list of common sources of lead in household items, the most notable of which is solder. Thus some kind of insulation is required around soldered circuitry to avoid any trace amounts of lead affecting the birds.

### 3.6.4 Ethical Considerations

Ethical guidelines emphasize the importance of minimizing stress and harm to the animals being studied. As such researchers should prioritize methods that avoid the need to handle the birds, as this will minimize the risk of injury to the researchers and the birds. This means that the red-winged starlings will need to be lured such that their weight measurements can be taken. This can be achieved using the many perching scale solutions described earlier, but for more traditional weighing methods, Manolis [7] provides a solution. In their study they used sunflower seeds to entice the birds to land on the scale, and since red-winged starlings tend to scavenge for food, this will prove useful for this application as well.

An automatic feeder device could be implemented as a way to streamline this process. However, researchers have found that the introduction of automated feeders tend to reduce species variety in a given area [16]. Automated feeders are also highly inconsistent with seasonal change, which would result in it being a highly inconsistent form of luring birds [16]. The introduction of an automated feeding strategy would have a noticeable effect on the ecological and weight cycles of local birds, especially those that would be studied.

## 3.7 Conclusion

Based on the reviewed literature, it can be seen that accessing data remotely is very much feasible using accessible technology such as Wi-Fi. The importance of gathering weight data was established and how it would be of benefit to ornithologists was explored. Various challenges and considerations have been presented in the reviewed literature and the importance thereof will be taken into account going forward.

# Chapter 4

## Sensing Subsystem (NXSMPI001)

### 4.1 Introduction

In order store the weight data of the Starlings in a database, the weight of the birds must first be obtained. That is the purpose of this subsystem, to translate the weight force of each bird on the scale into a digital reading that can be transmitted. This section will go through the design process involved in constructing the circuitry that turns the weight into an electrical signal, and developing the algorithms that will convert this signal into a usable measurement. As such, this section not only encompasses the sensors but also the microcontroller and the code responsible for allowing the two to communicate.

### 4.2 Requirements Analysis

From the user requirements discussed in Section 1.3, the non-functional and functional specifications for this specific subsystem were derived. They are shown in Tables 4.1 and 4.2 respectively.

Table 4.1: Non-functional Specifications of the Sensing Subsystem

User Requirement	Specification Description	Specification no.
Portable	The final circuitry must be able to fit in a box that is 100x100x50mm.	SS1
Long battery life	The final circuitry should consume less than 30mA.	SS2

Table 4.2: Functional Specifications for Sensing Subsystem

User Requirement	Specification Description	Specification no.
The scale must measure weights of up to 500g.	The weight sensor must have a maximum capacity greater than 750g (1.5 times safety factor).	SS3
	The sensor and amplifier must output a voltage proportional to the weight force applied up to a weight of 500g.	SS4

	The microcontroller must run an algorithm that converts output codes from the ADC into a weight measurement.	SS5
The scale must measure weight accurate to 0.1g.	The ADC must be able to resolve voltage changes from weight changes that are less than 0.1g.	SS6
	The ADC must have a full-scale error less than a voltage change resulting from a change in weight of 0.1g.	SS7
The scale must have a tare function.	The microcontroller must have a digital input pin to read the user's inputs from a button or switch.	SS8
	The microcontroller must subtract the current weight from all subsequent measurements when the digital pin receives an input.	SS9
	There must be an LED that indicates when the scale is in tare mode.	SS10
The scale must be battery-powered.	The microcontroller and all the surrounding circuitry must be able to operate on one positive rail.	SS11

## 4.3 Design Process

### 4.3.1 Microcontroller Unit (MCU)

The Arduino was chosen as its Integrated Development Environment (IDE) has ample support and libraries which will make interfacing with all the different modules simple and straightforward. Within the Arduino family the Arduino Nano was initially chosen as it was one of the cheapest Arduino and it came in a small form factor. However, the User Interface subsystem required a WiFi or Bluetooth module so the Arduino Nano 33 IoT was chosen instead. Although BLE and BLE Sense also meet these requirements, they come with additional sensors that are unnecessary. All the Arduino chips also come with several low power modes that can be leveraged to reduce power consumption.

### 4.3.2 Weight Sensor

A strain gauge is an electrical component whose resistance changes when a force is applied to it. Strain gauges work on the principle that the resistance of a conductor is proportional to its length, as shown in the equation below.

$$R = \rho \frac{L}{A}$$

One solution is to put a strain gauge in series with another resistance, then place the strain gauge on a beam. When the beam deflects under the bird's weight, the change in voltage across the strain gauge

can be measured. The issue with this setup is that the change in resistance, and thus the subsequent change in voltage, will be very small. This means a very high resolution ADC will be required to resolve these small changes in voltage. The resolution required could be reduced by amplifying the signal, however this would also amplify the DC offset introduced by the voltage divider, quickly saturating the output.

A better solution is a load cell which has 4 strain gauges in a Wheatstone configuration. This means that when the load cell has no load on it, the voltage will be zero, and when the device deflects, there will be a slight voltage difference between its 2 output terminals. As discussed above, this output can be sent through an amplifier thus reducing the resolution required for the ADC. To meet the sensor specifications, a 1kg load cell will be used.

The specifications for one such load cell by HKD is shown in Table 4.3 below.

Table 4.3: Table on load cell specifications

Rated Load	1kg
Rated Output	$1.0 \pm 0.15\text{mV/V}$
Zero Output	$\pm 0.1\text{mV/V}$
Input Impedance	$1115 \pm 10\Omega$
Output Impedance	$1000 \pm 10\Omega$

At the rated load, the output will be  $0.001V_{cc}$ , hence the amplifier needs a gain of 1000.

#### 4.3.3 Sensor Amplifier

From Table 4.3, the output impedance of the load cell is quite significant, meaning there will need to be an input buffer between it and the amplifier to avoid loading. The instrumentation amplifier is thus ideal circuit for achieving this and it is shown in Figure 4.1 below.

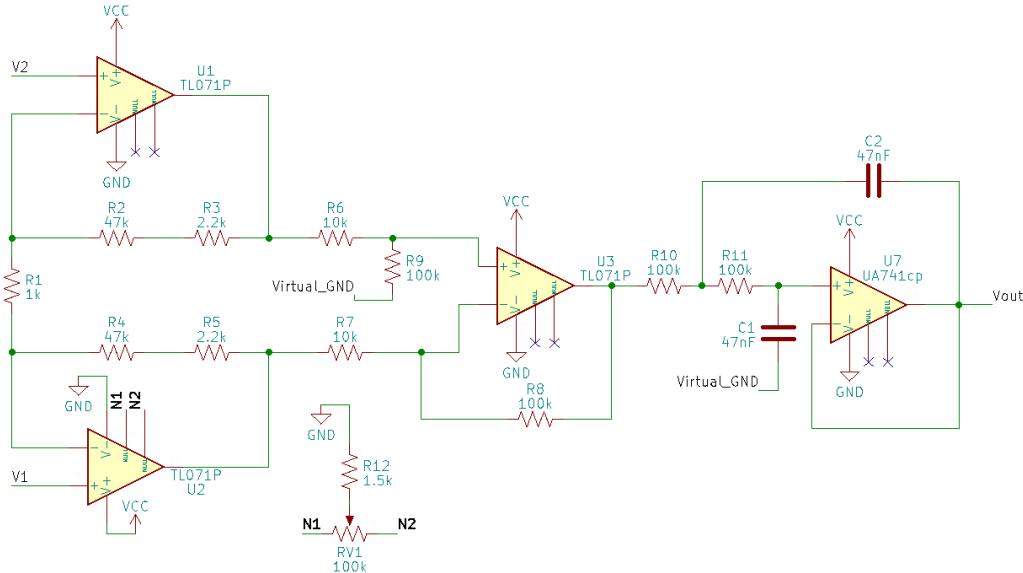


Figure 4.1: Circuit Schematic of Instrumentation Amplifier

The circuit has three stages. The first stage has two input buffers which also amplify the input signal.

The second is a differential amplifier which is a circuit whose output is proportional to the difference between the two inputs. The final stage is a low pass filter. The final output voltage is related to the input voltage by the expression below.

$$V_{out} = (V_2 - V_1) \left( 1 + \frac{2(R_2 + R_3)}{R_1} \right) \left( \frac{R_9}{R_6} \right)$$

Figure 4.2: Output Voltage of the Instrumentation Amplifier

From the expression above, when the load cell is connected to the two input terminals, its output will be amplified by a factor of 994, which is close to the gain required. The amplifier have such a large gain presents two issues.

The first is that real op-amps have an input offset voltage. As the offsets from the input stage propagate through the circuit, they are amplified resulting in the output having a large bias and saturating for very small weights, hence the op-amps used were the TL071P. These are JFET op-amps meaning they have a very low input offset voltage, in this case, of 1mV. This is still large in comparison to the input, but they also come with two NULL pins which allows the input offset to be adjusted, and thus reduced to 0. The is the purpose of potentiometer RV1 in Figure 4.1. Another reason for choosing TL071P is that their minimum recommended supply voltage is 4.5V which means unlike other JFET op-amps they can operate at lower supply voltages. This advantageous since the scale will be battery powered so there will not be a large supply.

The second is that noise from the input will also be amplified as it propagates through circuit, making the final output difficult to measure. The low pass filter in the final stage addresses this. Since output is a DC voltage, ideally the cutoff frequency should be as low as possible to attenuate the most amount of noise, but this would have a negative impact on the rise time. A lower cutoff frequency would also require larger capacitors. The sample rate for final system will be 10Hz (discussed later). This equates to a period of 0.1s and ideally the output should settle within half that time. It takes 5 time constants for the output to settle to 99% of its final value. This means that  $5RC = 0.05s$  or  $RC = 0.01s$ . If a  $100k\Omega$  resistor is used then the capacitor would need  $100nF$ . The filter also needs a steep roll-off to ensure a clean output, so a second stage can be added at the input, to make it a second order filter. The input stage of this filter needs to have much lower impedance than output stage to avoid loading, which would resulting in the filter having a larger cutoff frequency than was calculated. Using a  $10k\Omega$  resistor, the capacitor needed would be  $1uF$ . The equates to a cutoff frequency of 16Hz. It is difficult to know the exact rise time for higher order filters from calculation alone, as such, this filter was simulated in LTSpice. The circuit diagram is shown in Figure 4.3 below.

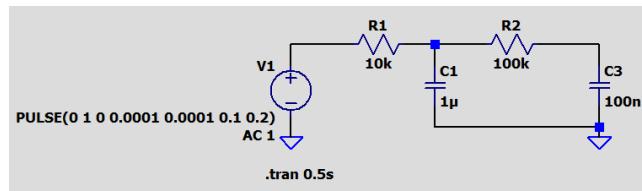


Figure 4.3: Circuit Schematic of Low Pass Filter

The input was set to a  $1V_{pp}$  square wave with a frequency of 5Hz. Figure 4.4 below shows the input and output of the circuit.

### 4.3. Design Process

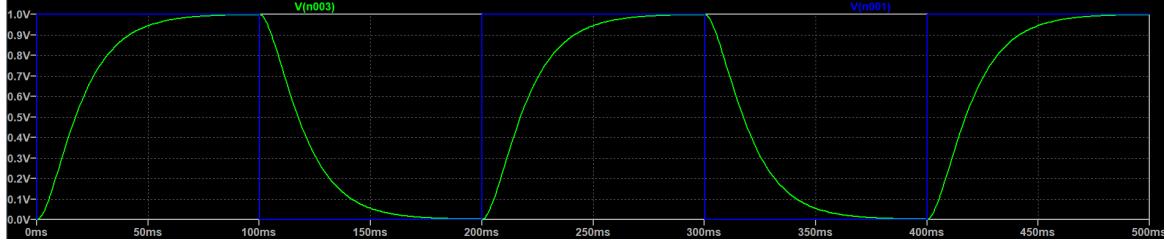


Figure 4.4: Input and Output Waveform of Filter

From the waveform above it can be seen that the rise time is too large, as the output (in green) is barely settling in time for the next half-cycle. This can be rectified by halving the size of the capacitors to 470nF and 47nF, as seen in Figure 4.1. The new output is shown in Figure 4.5 below.

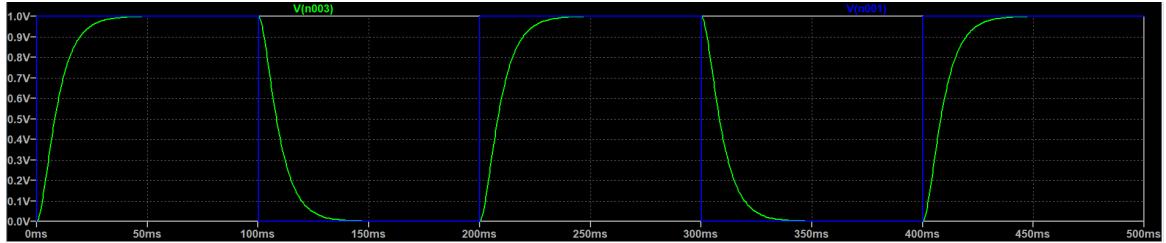


Figure 4.5: Input and Output Waveform of the Final Filter

As seen above, the filter now meets the speed requirements. Since the instrumentation amplifier has op-amps, it needs 2 rail voltages, a positive and a negative. Unfortunately there is only a single supply, however this supply can be split in two with a simple op-amp circuit, as shown in Figure 4.6 below.

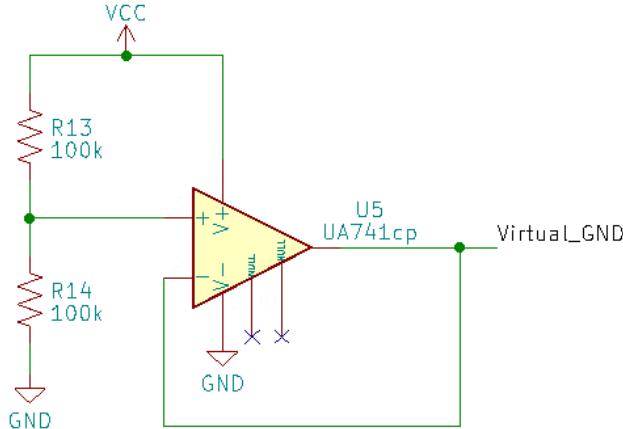


Figure 4.6: Schematic of Split Supply Circuit

If the new reference point is made to be ‘Virtual GND’, then two rail voltages equal to  $\pm \frac{V_{cc}}{2}$  are obtained. This does mean that output of the amplifier will have an offset of  $\frac{V_{cc}}{2}$ , but this can be stepped down using a voltage divider as to not damage the input to the microcontroller. In testing, a 5V supply was initially used but this resulted in the op-amps saturating. In the early stages of the design process, the amplifier was tested using  $\pm 3.3V$  and this worked fine so in the end a 6.6V supply was chosen. This will be the supply voltage required from the Power Subsystem. The Arduino Nano 33 IoT has an operating voltage of 3.3V so the voltage divider must have a gain of 0.5.

Finally, because the output from the amplifier will no longer go directly to the microcontroller, an op-amp must be included in the low pass filter to buffer the input of the voltage divider. The new active low pass filter will be in a Sallen-Key configuration with  $R = 100k\Omega$  and  $C = 47nF$  as shown in Figure 4.1.

#### 4.3.4 Analogue to Digital Converter (ADC)

Since the weight force on the load cell is proportional to output voltage out of the load cell, the change in weight is equal to the change voltage as shown in the equation below.

$$\frac{W_1}{W_2} = \frac{V_1}{V_2}$$

Figure 4.7: Relationship between Weight and Voltage

By substituting in the rated load, rated output and the minimum weight, the smallest change in the output can be determined.

$$\frac{0.1g}{1000g} = \frac{V_{min}}{0.5(994(3.3mV))}$$

$$V_{min} = 0.164mV$$

As such, 1 LSB (Least Significant Bit) of ADC must be less than 0.164mV. Since the supply voltage from the Arduino is 3.3V, an ADC with a minimum resolution of 15 bits is required. The Arduino only comes with a 12-bit ADC so an external module will be needed. The module that was chosen is the ADS1115 16 bit ADC its specification for this application are summarized in Table 4.4 below.

Table 4.4: Table on ADS1115 specifications

	<b>Min</b>	<b>Typical</b>	<b>Max</b>	<b>Unit</b>
<b>Supply Voltage</b>	2	-	5.5	V
<b>Data Rate</b>	8	-	860	SPS
<b>Offset error</b>	-	$\pm 3$	-	LSB
<b>Gain error</b>	-	0.01	0.15	%

From Table 4.4, the offset error is equivalent to 0.151mV which is less than  $V_{min}$ . The maximum gain error is quite large, translating to an offset of 4.95mV at the last output code. Even under typical conditions the offset will be 0.33mV. However this is not a big issue, as the scale only needs to be accurate over half the range and the gain error can be compensated for in software. The noise performance is also great as at low data rates, not a single bit of resolution is lost to quantization noise. The final reason this module was chosen is that most ADC come standalone in a SIOC package, but this one comes as a development board kit with headers allowing for easy soldering onto a Veroboard. The circuit diagram for this module is shown in Figure 4.8 below. The ADC communicates with Arduino the I2C communication protocol, hence their SDA and SCL lines are connected. The Arduino has internal pull-up resistors on these lines so there's no need for external ones. The output from the amplifier is halved by the voltage divider and sent to channel 0 on the ADC. This is necessary as the ADC can only take 0.3V above the supply. In this case the supply will be the regulated 3.3V from the Arduino.

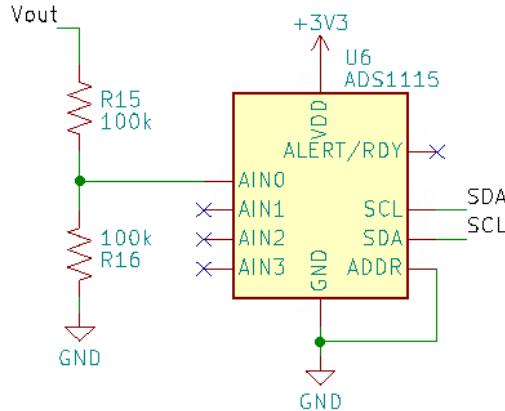


Figure 4.8: Circuit Schematic of the ADS1115

#### 4.3.5 Weight Measurement Algorithm

The ADC was read from in code using the ADS1X15 Arduino library by Rob Tillaart [17]. The ADS1115 has a programmable gain amplifier (PGA) that allows it take more precise measurements at the cost of a reduced input voltage range. The different options for the gain with corresponding full scale range and precision are shown in 4.5 below.

Table 4.5: Table on ADS1115 gain options

FSR [V]	LSB Size [uV]
+/- 6.144	187.5
+/- 4.096	125
+/- 2.048	62.5
+/- 1.024	31.25
+/- 0.512	15.625
+/- 0.256	7.8125

The second option for the gain was chosen since the input is expected to be between 1.65V and 3.3V. The LSB size for this gain also meets the accuracy requirements. The data rate was also set to 16 samples per second as the sample rate for the system will 10 samples per second, and the lower the sample rate, the lower the noise. These were both set in code using the setGain() and setDataRate() functions from the library. Once setup, the sampled value would be read from the ADC using the readADC() function. The ADC value was then converted into voltage in Volts by multiplying it by the value returned by the toVoltage() function from the same library. That voltage would then be converted to a weight in grams using the voltsToGrams() function shown in Figure 4.9 below.

```
float voltsToGrams(float V) {
    float Vin = (2*V - 3.3)/994;           // Determine input voltage from output voltage
    float weight = 1000*Vin/(3.3*0.001);   // Determine weight from input voltage
    // float weight = (V-1.5935)/0.0015;   // Linear regression model
    return weight;
}
```

Figure 4.9: Code Snippet of the Function that converts voltage to a weight

From Equation 4.2, the output voltage of the amplifier is...

$$V_{out} = \frac{1}{2} (994V_{in} + 3.3)$$

And from this, the input voltage from the load cell can be determined. The weight is then calculated using Equation 4.7, and this was implemented in code as shown in 4.9 above.

The final outputted weight value was the ten-point moving average of all the measurements. The purpose of this was to reduce the effect of the bird's rapid movements on the weight measurement, as a moving average changes slower when compared to the input. This algorithm is implemented in code by the movingAverage() function shown in Figure 4.10 below.

```
float movingAverage(float* values, int index)
{
    float sum = values[SIZE];
    sum += values[index];
    if(index+1<SIZE) {
        sum -= values[index+1];
    }
    else {
        sum -= values[0];
    }
    values[SIZE] = sum;
    return sum/SIZE;
}
```

Figure 4.10: Code Snippet of the Function that takes the Moving Average of the weights

If 'SIZE' is set to 10, the 'values' array is a circular buffer that stores last 10 weight measurements, along with the sum of the whole array. The index increases incrementally with each new measurement and wraps back around to 0 once it goes past 9. This means that the latest value is stored at position 'index' within the array, while the value one position ahead of it is the oldest. When a new value is added to the array, it is added to the sum while the oldest value is removed from the sum. The sum divided is subsequently by 'SIZE' or 10 and that is the average that gets returned. By storing the sum in memory it removes the need to add up all the values in the array with every new measurement, making the program run more efficiently.

#### 4.3.6 Tare Functionality

The tare function was implemented using an interrupt tied to the input of a push button. The button is made active low by connecting an internal pull up resistor in code. The interrupt is set to trigger whenever there is a falling edge from the button, which occurs when it is initially pressed. The corresponding Interrupt Service Routine (ISR) toggles the LED when this occurs as shown in Figure fig:S16 below. Within the main loop the change in the LED state is detected and the current weight is stored and added to an offset value. When the LED is toggled ON, all subsequent measurement will now be the difference between the weight and this offset, unless the offset is larger, in which it is just 0. When a button is pressed it does not close shut immediately. Instead its contacts bounce off one another many times within a split second, resulting in the microcontroller reading multiple inputs from

one button press. Hence a delay of 250ms is added to allow the button to settle before taking input from it again.

```
void buttonPressedISR()
{
    if(millis() - last_press > DEBOUNCE_DELAY){      // Button debouncing
        digitalWrite(LED_PIN, !digitalRead(LED_PIN)); // Toggle LED
        last_press = millis();
    }
}
```

Figure 4.11: Code Snippet of Interrupt Service Routine for push button

## 4.4 Acceptance Test Procedure (ATP)

### 4.4.1 Load Cell and Amplifier tests

The amplifier circuit built on the breadboard and connected to a 6.6V power supply. The split supply was tested by measuring the voltage of the positive and negative rail with respect to ‘Virtual GND’ using a multimeter as shown in Figure A.1 in Appendix A4. The input into the amplifier was connected to the waveform generator on the oscilloscope. The output with respect to ‘Virtual GND’ was measured using the oscilloscope and the output with respect to GND was measured using the multimeter (this is what the ADC would measure). The input was set to 0V DC and the potentiometer was adjusted until the measured output on the oscilloscope was also 0. The output to the Arduino was then measured using a multimeter. This was repeated for different input values until the output saturated. This was compared to the ideal output given by the following expression.

$$V_{out} = \frac{1}{2} (994V_{in} + 3.3)$$

The measurement for the output when the input was 1mV DC can be seen in Figure A.2 in Appendix A4.

The load cell was attached to a mock scale as shown in Figure 4.12 below. Header pins were soldered to each of leads from the load cell. Within the same figure, the red and black leads were connected to  $V_{cc}$  and  $Virtual\_GND$  respectively, while the white and green wires leads connected to the  $V_1$  and  $V_2$  inputs of the amplifier respectively. A kitchen scale was then used to measure and record the weight of an empty water bottle. This bottle was then placed on the front of the scale above the nails. The output voltage from the amplifier was measured and recorded the same as before. This is shown in Figure below. This process was repeated for different weights up until the amplifier’s output saturated. The weight of the bottle was varied by filling it up with different amounts of water. The bottle was placed at the same position on the scale in each run to ensure that the bottle’s distance from the other end, or moment arm, was the same.

### 4.4.2 Weight Measurement Test

The ADC was connected to the Arduino as shown in Figure 4.8 on the breadboard. The output from the voltage divider in Figure 4.12 was connected to channel 0 on the ADC. The Arduino was connected to the PC, the weight measurement program was run and a serial connection was established to see the output in the terminal. Once again, a bottle filled with different amounts water was placed on top of

#### 4.4. Acceptance Test Procedure (ATP)

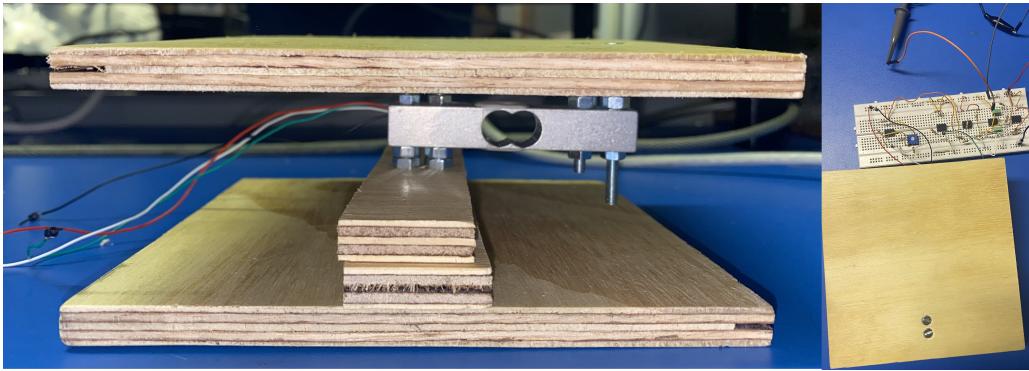


Figure 4.12: Image of mock scale

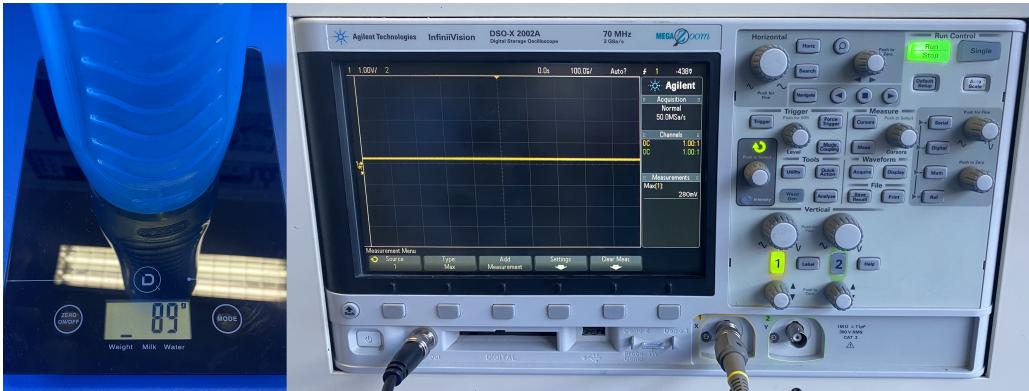


Figure 4.13: Image of load cell and amplifier test

the load cell. The weight of the bottle measured by the scale and the weight measurement determined in code were both recorded. The measurement for the empty 66g bottle is shown in Figure A.1 below.

```
Output  Serial Monitor X
Message (Enter to send message to 'Arduino NANO 33 IoT' on 'COM8')
v = 1.74      Weight = 57.3
```

Figure 4.14: Image of Weight measurement in terminal

#### 4.4.3 Tare Function Test

The push button was now connected to pin D2 on the Arduino while the LED was placed in series with a  $100\ \Omega$  resistor and connected to pin D3. The button was pressed and the resulting weight change in the terminal was observed.

## 4.5 Results and Discussion

### 4.5.1 Load Cell and Amplifier test

The plot of the output voltage w.r.t. GND and ‘Virtual GND’ against the input voltage from the oscilloscope can be found in Figure A.3 in Appendix A4. The plot of the output voltage against the weight is shown in Figure 4.16 below. It can be seen that the output voltage has linear response with the weight.

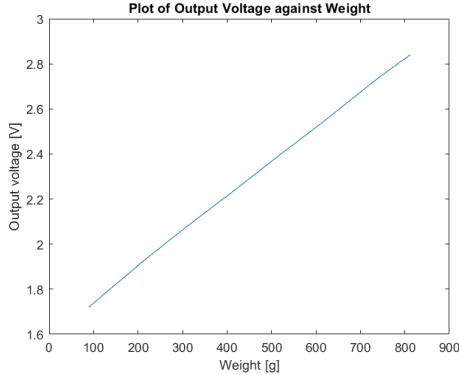


Figure 4.15: Plot of the output voltage against the weight

### 4.5.2 Load Cell and Amplifier test

The plot of the output voltage w.r.t. GND and ‘Virtual GND’ against the input voltage from the oscilloscope can be found in Figure A.3 in Appendix A4. The plot of the output voltage against the weight is shown in Figure 4.16 below. It can be seen that the output voltage has linear response with the weight.

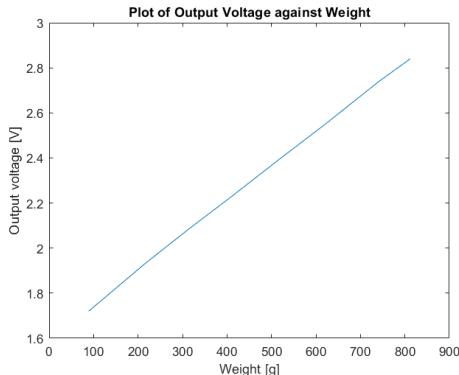


Figure 4.16: Plot of the output voltage against the weight

# Chapter 5

## Power Subsystem (MBSLUN008)

### 5.1 Introduction

The power subsystem is one of the most important subsystems in this design with respect to its functionality. This subsystem is responsible for powering up the micro-controller (MCU) and the sensor. It is very important for the design to have a reliable and safe power supply unit (PSU). This section outlines how the power supply unit design is divided into smaller sections, all with different responsibilities, requirements and specifications, but with the same goal: to achieve a reliable power supply source. The design uses a battery as its primary source of power. The subsection includes sections such as battery charging, overload protection, reverse polarity and a voltage regulation system. Designed were two circuits which work together to complete the whole PSU. First circuit is for battery charging, encapsulated with protection, then the voltage regulation circuit. As above-mentioned, the PSU's goal is to provide a reliable power source to the micro-controller for more efficient performance.

#### 5.1.1 System overview

Shown below is the system overview of the whole power supply unit.

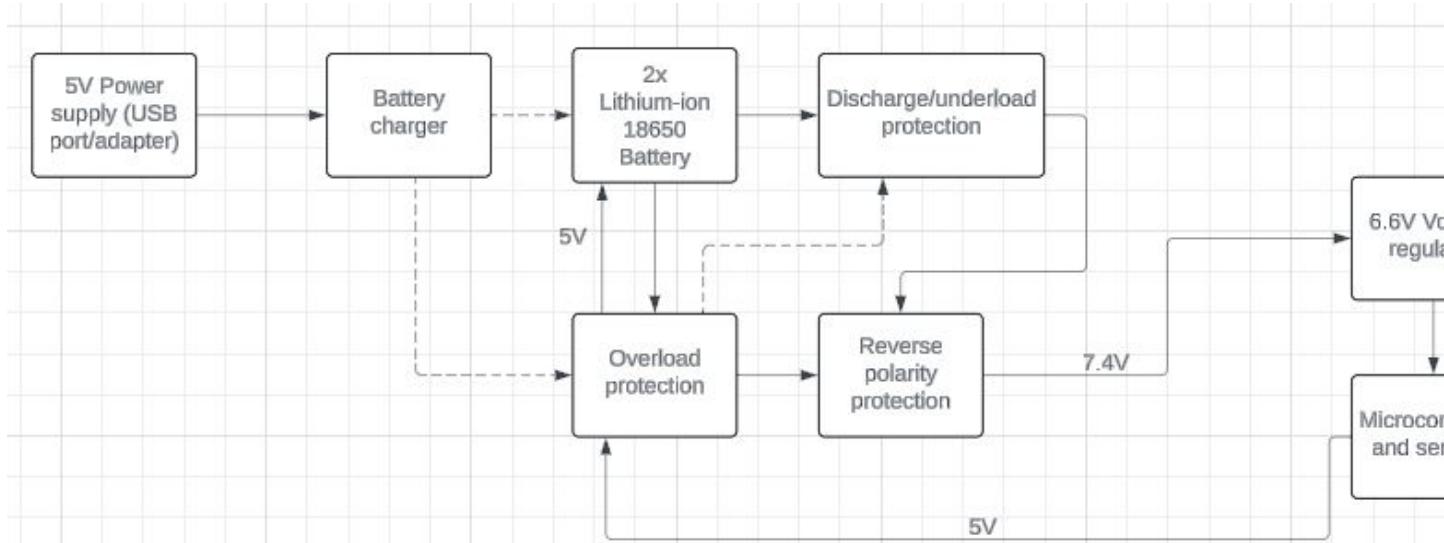


Figure 5.1: System overview

## 5.2 Specifications

### 5.2.1 Non-Functional Specifications

Table 5.1: Non-Functional Specifications for Power Subsystem

No.	Description	Acceptance criteria
PS1	Charging compatibility	The PSU must have a charging system that is easy and compatible to common charging power sources.
	PS2	Safety
The PSU must be designed in such a way that it provides safety to the users (Sally and and birds), as well as safety to the components used.	PS3	Physical Size
The Power supply unit should relatively take less space in the whole design not to scare away the birds.	PS4	Battery monitoring
The user must be able to easily monitor the battery life of the design.		

### 5.2.2 Functional Specifications

## 5.3 Design

### 5.3.1 Battery charging

Lithium-ion batteries are rechargeable, The charging circuit should have a stable power supply. This supply can be achieved by using a wall adapter, USB port, or another power source, such as a power bank. The charging circuit of the 18650 Li-ion batteries uses a BC745 transistor as the driver of the circuit. The circuit diagram is shown below. The circuit takes in a voltage of between 8V - 5V. This circuit is designed to charge one battery at a time, making it more efficient and reliable. The charging circuit has two LED indicators. These LEDs are designed to indicate the level of the battery power

Table 5.2: Functional Specifications for Power Subsystem

No.	Description	Acceptance criteria
PS5	Output voltage	The PSU must have a regulated output voltage of 6.6V to power up the microcontroller and sensor as required by the Sensing Submodule.
	PS6	Overload Protection
The PSU must ensure that each Li-ion battery does not charge to an overload voltage of 4.2V.	PS7	Physical Size
The Power supply unit should be within the range 0.15x0.15m .	PS8	Physical Size
The Power supply unit should be within the range 0.15x0.15m .	PS9	Physical Size
The Power supply unit should be within the range 0.15x0.15m .	PS10	Physical Size
The Power supply unit should be within the range 0.15x0.15m .	PS11	Physical Size

when it is plugged to the charger. When the voltage is low, i.e the battery power is low, the RED LED will be much brighter than the GREEN LED. When the voltage now approaches the maximum voltage of 4.2V (actual voltage on a 3.7V Li-ion battery), the green LED dominates the RED and the user can know that the battery is charged. This is a sample and cost effective way to monitor the charging process of the batteries.

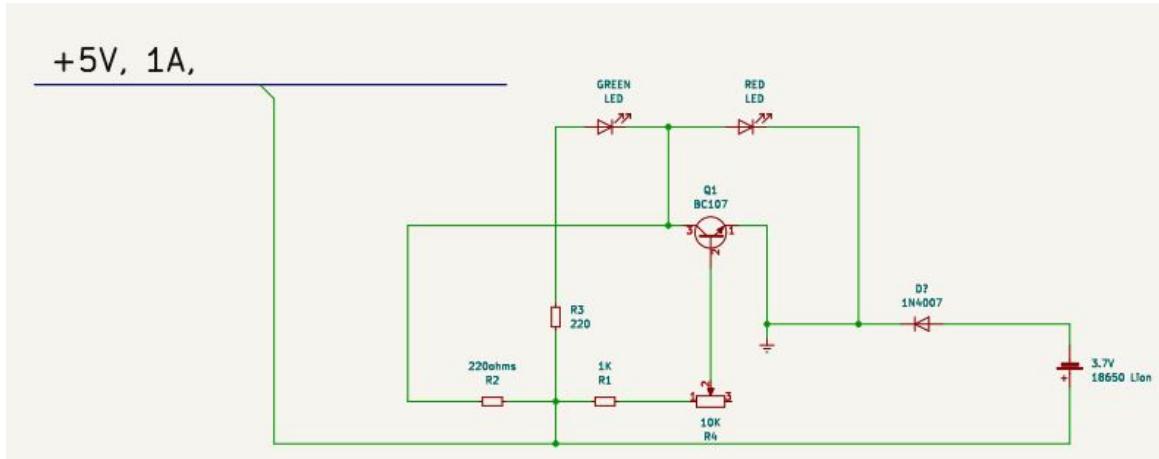


Figure 5.2: Charging circuit

### 5.3.2 Protection circuitry

A good design is one which fulfills its requirements and is safe to use. Protection circuitry is necessary in this design to ensure that the device is safe to use as safety plays a huge role in design engineering. Safety also means protection of the components, this will avoid extra costs and time of the user. To avoid burning components, harming the user or even the birds to be scaled, the following protection measures were taken in the design.

#### Overload protection

During the charging process, the 18650 battery must be protected against voltage and current overloading. The overload protection should keep note of key considerations and address to ensure both safety and optimal battery performance. The Li-ion battery has a nominal voltage of 3.7V, it is imperative to note that the specifications of the battery state that the charging voltage should not exceed 4.2V at 0.052A. A common approach involves incorporating a dedicated protection IC that monitors charging parameters such as voltage, current, and temperature. When an overload condition is detected, typically caused by excessive current flow or prolonged charging beyond safe limits, the protection IC triggers a mechanism to shutdown and disconnect the charging circuit from the battery. This prevents overcharging, which can lead to overheating, cell damage, or even fire hazards.

In the circuit below, a 100 ohms resistor was used to limit the current in the base of LM395. Resistors to the values shown below are used to limit the current in the circuit. A power transistor LM395 is used in the overload protection as shown. LM395 is ideal for low power applications such as our small scale sensing design. These transistors act as high gain power transistors, and are capable of power, voltage, current limiting and heat/thermal overloading protection. It is very rare to find a device which is able to provide overload and thermal protection concurrently, which makes the LM395 very reliable to our design. The use of these transistors delivers simplicity and reliability to our design. The thermal limiting circuitry inside the LM395 will terminate the circuit should there be excessive amount of heat, protecting the battery from burning.

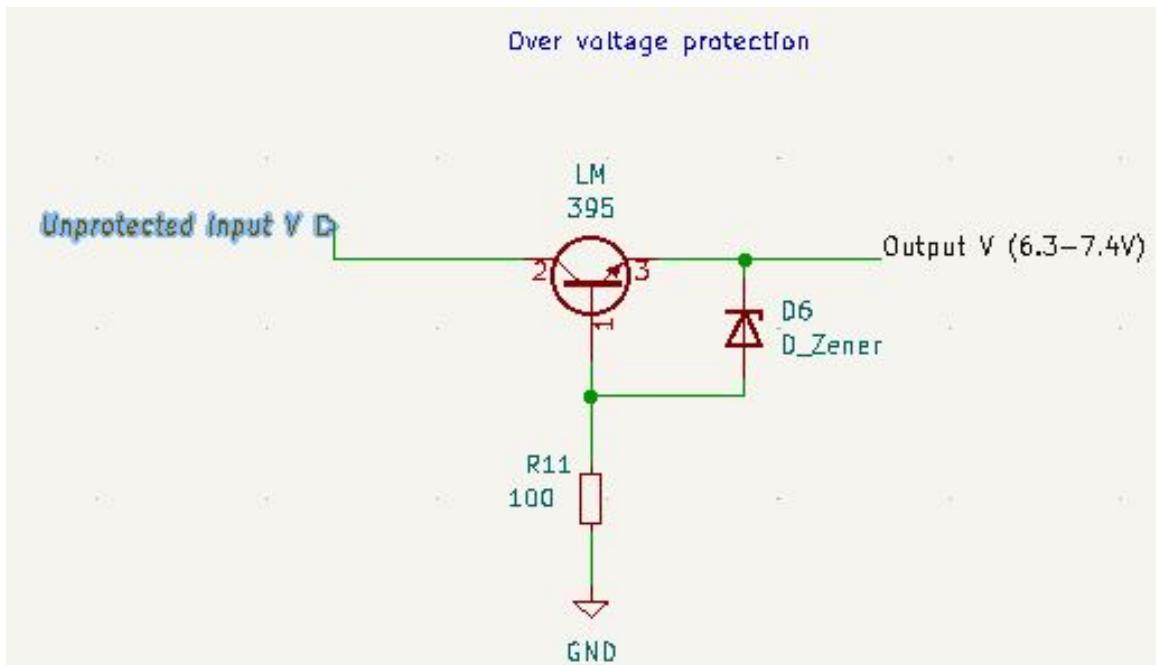


Figure 5.3: Circuit Schematic of Overload protection

### Under voltage protection

As much as the Li-ion batteries need to be protected from overloading conditions, they also need to protection during a discharging process. When the battery is used to power the scale, it gradually discharges as electrical energy is drawn from it. Discharging the battery to 0V damages the battery and reduces its lifespan. To solve this discharge risk, LM358 compactor together with PN2222A, are used in the discharging protection of the battery. The circuitry constantly monitors the battery's voltage level during discharge and charging cycles. When the battery voltage drops below a predefined threshold of 3V, indicating a critically low state of charge, the protection circuit triggers a disconnect mechanism to stop further discharge and protect the battery from damage. This safeguard ensures that the battery remains within safe operating limits, prolonging its lifespan and preventing potentially hazardous conditions. The discharge circuit is shown below.

The circuit above shows a voltage divider which divides the battery voltage by a factor of 10. When the batteries' voltage reaches 6V, the circuit cuts off and isolates the battery from the circuit entirely.

### Reverse polarity protection

The battery is safeguarded against reverse polarity by employing the a Schottky diode 1N5819. This diode is renowned for its efficacy by having a minimal forward voltage drop of 0.2-0.3V. In the event of reversed battery polarity, the voltage potential at the anode of the diode will be lower than that at the cathode, effectively preventing current flow and thereby shutting the circuit down. No power will be drawn back to the battery, further preserving the battery's lifespan and increasing its reliability. Please see diode's specifications below.

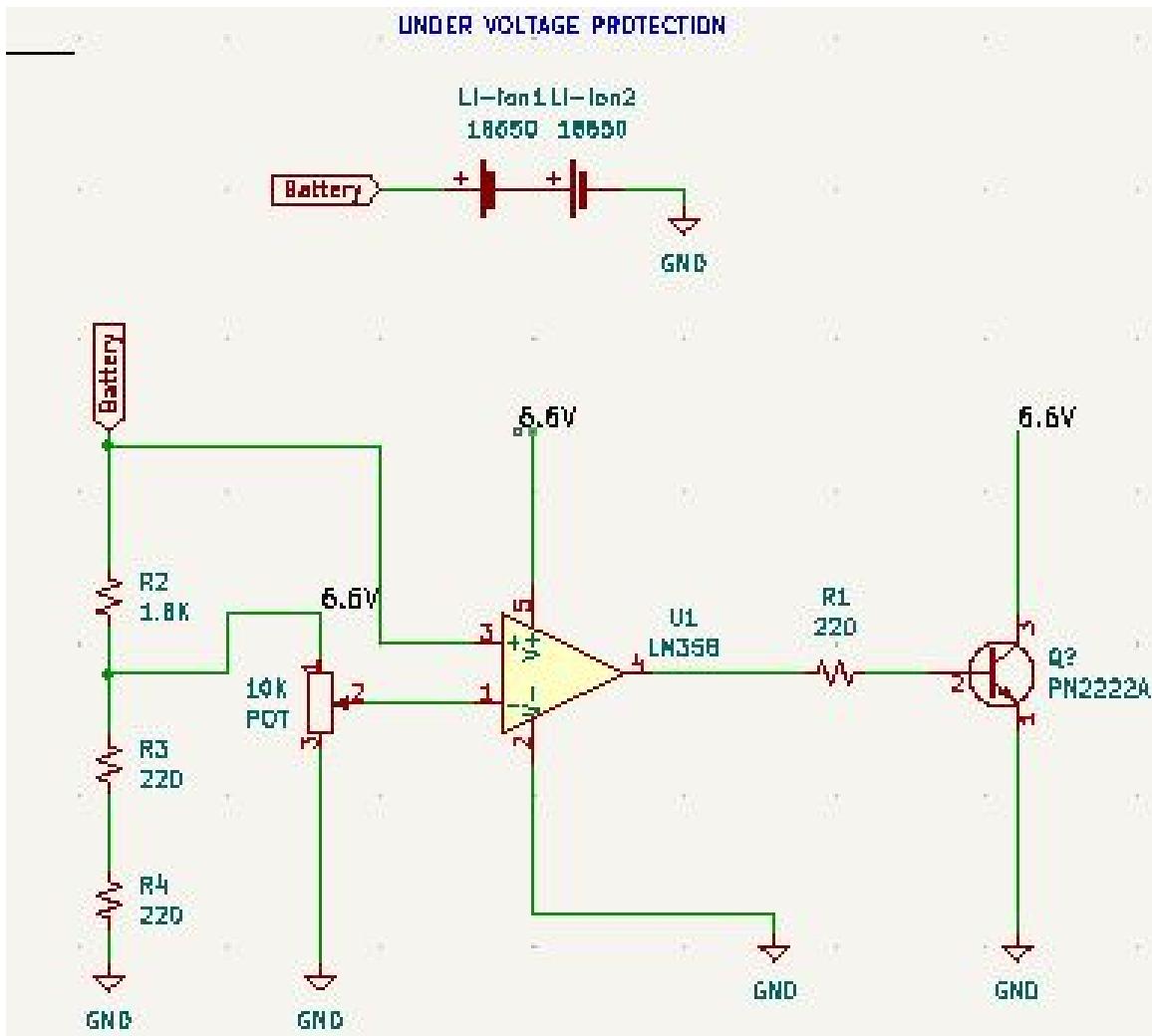


Figure 5.4: Circuit Schematic of Under-voltage protection

### 5.3.3 Voltage regulation

LM117 was used in the voltage regulation process. the IC uses takes in voltages in the ranges of between 3-40V. This makes it an optimal choice for our design. some significant aspects of using this IC includes costs and simplicity. For the same functionality, you spend less and have a simple circuit to deal with. The voltage regulation circuit is shown below. This circuit is integrated with the protection circuits to form a protected regulatory supply. The regulated voltage is 6.6V, which is the exact voltage that drives the microcontroller and the sensors of the Sensing submodule.

### 5.3.4 Battery power level monitoring

For monitoring the battery status, a voltage input is sent to an IC which will convert the voltage into readable battery level indicator. When the voltage level on the batteries reach a certain level, the user will b notified via a notification to charge or change the battery.

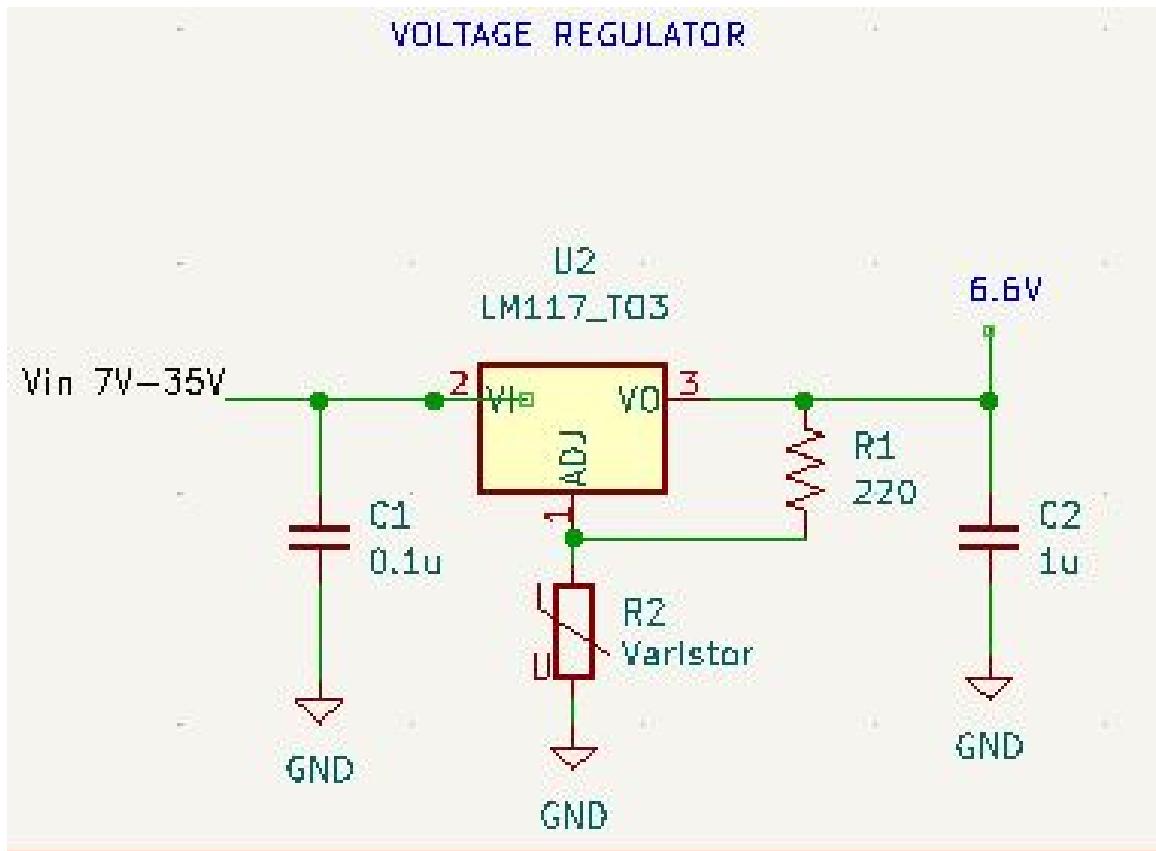


Figure 5.5: Charging circuit

## 5.4 Acceptable Test Procedure

## 5.5 Testing and Results

Battery charging xxxxxxxxxxxxxxxxxxxxxxxxxxxxxxxxx

Overload and under-load protection xxxxxxxxxxxxxxxxxxxxxxxxx

Voltage regulation xxxxxxxxxxxxxxxxxxxxxxxxx

## 5.6 Conclusion

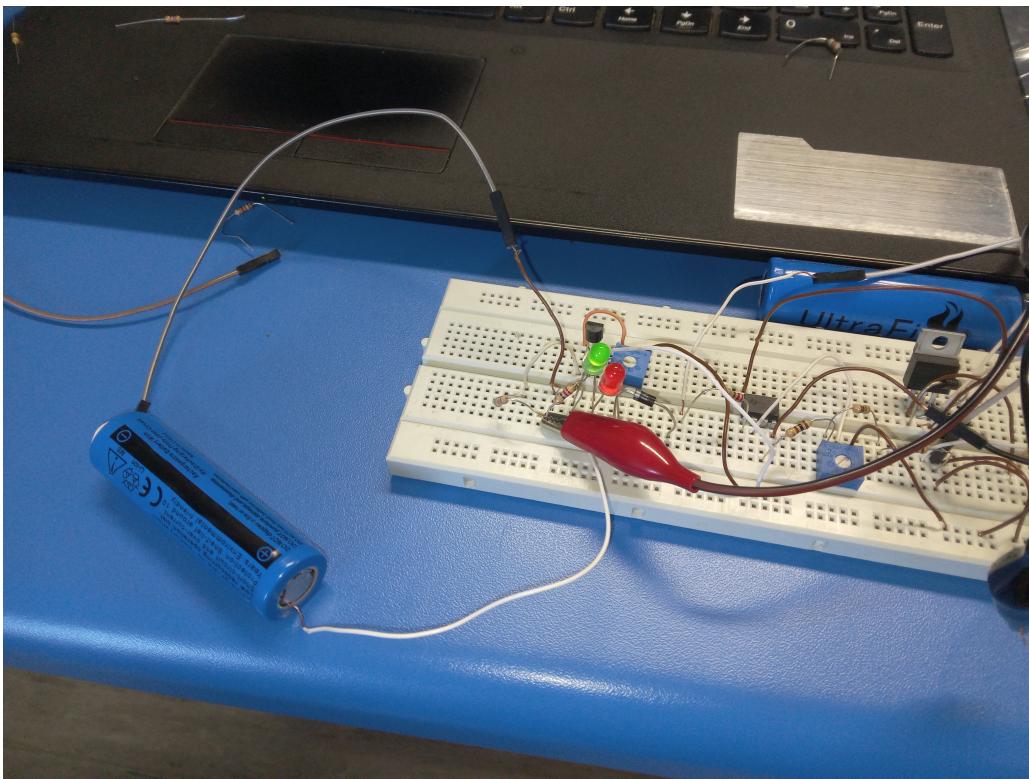


Figure 5.6: Charging circuit



Figure 5.7: Charging circuit

Table 5.3: Acceptable Test Procedure

No.	Description	AAcceptance criteria
Test Result		
ATP1	Charging compatibility	The PSU must have a charging system that is easy and compatible to common charging power sources.
<b>PASSED</b>		
	PS2	Safety
The PSU must be designed in such a way that it provides safety to the users (Sally and and birds), as well as safety to the components used.		
	PS3	Physical Size
The Power supply unit should relatively take less space in the whole design not to scare away the birds.		
	PS4	Battery monitoring
The user must be able to easily monitor the battery life of the design.		
PS5	Output voltage	The PSU must have a regulated output voltage of 6.6V to power up the microcontroller and sensor as required by the Sensing Submodule.
	PS6	Overload Protection
The PSU must be ensure that each Li-ion battery does not charge to an overload voltage of 4.2V.		
	PS7	Physical Size
The Power supply unit should be within the rage 0.15x0.15m .	27	
	PS8	Physical Size

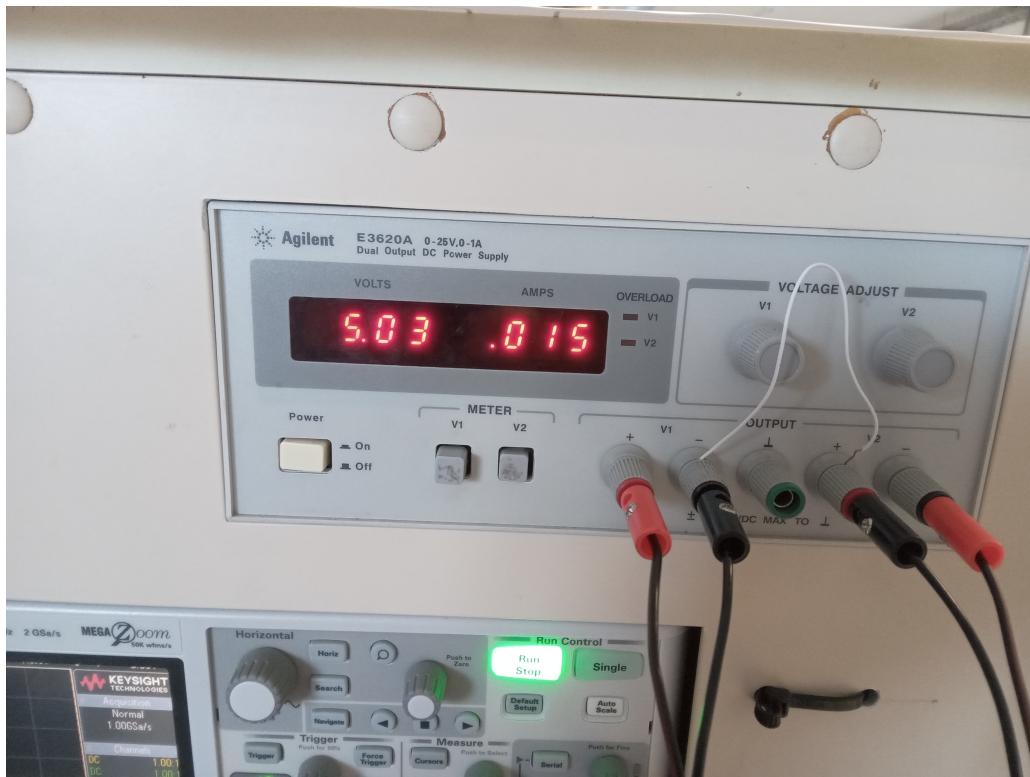


Figure 5.8: Charging circuit

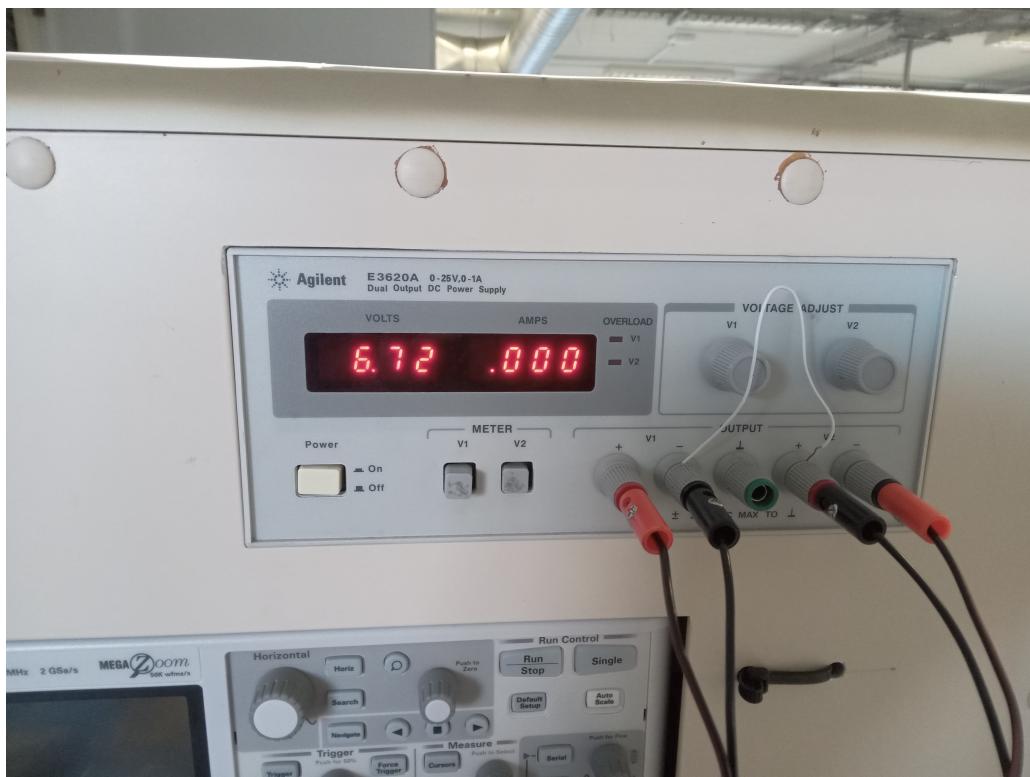


Figure 5.9: Charging circuit

# Chapter 6

## User Interface

### 6.1 Introduction

This chapter deals with the user interface of the system. The user interface is how the client will be able to make use of the system.

### 6.2 Requirements

#### 6.2.1 User Requirements

1. Display weight data on app.
2. App must have interface for manual data.
3. Other data should be automated (time, location).
4. Data must be saved to a spreadsheet. It should have the following fields: FID, Date, Time, ID, Ring type, Sex, Mass, Day status, Day status, Day, Weekday, Term, Name, Weight Session, Location, Notes, People Count 1, People Count 2.

#### 6.2.2 Functional Requirements

1. Establish connection between smart scale (Arduino) and phone (via Bluetooth or Wi-Fi)
2. The GUI should have a text box to input the bird's ID.
3. A CSV file needs to be created where the data will be written.

### 6.3 Design Choices

#### 6.3.1 Sending readings

There are several technologies to transmit data such as: Wi-Fi, and Bluetooth. Wi-Fi has the benefit of connecting to the internet. It requires minimal effort on the user's end if they are already connected to the internet. However, internet access is not feasible as weighing sessions span outside of *eduroam* coverage. Bluetooth is more power efficient, which is important because the scale must be portable. A comparative graph of power usage from Eridani et al. [1] is shown below in figure 6.1.

Figure 6.1: Power Usage Graph

In addition, Bluetooth's speed is sufficient because only several bytes of data are being transmitted at a time. There are two types of Bluetooth: Bluetooth Classic and Bluetooth Low Energy (BLE). BLE is a newer technology that is even more power efficient than Bluetooth Classic; therefore, Bluetooth Low Energy was chosen.

### 6.3.2 Graphical User Interface

A mobile app needed to be developed to receive and record the data. The client uses an Android device; therefore, an the app was developed for Android devices. The official native programming language is Java. Kotlin is a newer language, that Google will be giving more support to than Java, going forward [?]. In addition, Kotlin has more concise and safer code. It has less boilerplate and it has many language features to avoid common programming mistakes, such as null safety [?].

For these reasons Kotlin was chosen since it would mean this program would be easier to maintain for newer Android devices in the future and it would be less error prone.

Its UI App Development Toolkit, Jetpack Compose, was used to develop the GUI for the app. This was used instead of XML (Extended Markup Language), since it is more concise than XML, and is officially supported by Google.

### 6.3.3 Saving data

The data is required to be viewed in a spreadsheet form. The simplest format that can be read in a spread sheet is the CSV (Comma Separated Values) format. The other common option is the Excel Workbook format for Microsoft Excel. This format is more complicated and unnecessary, since only text values are being saved.

## 6.4 Subsystem Design

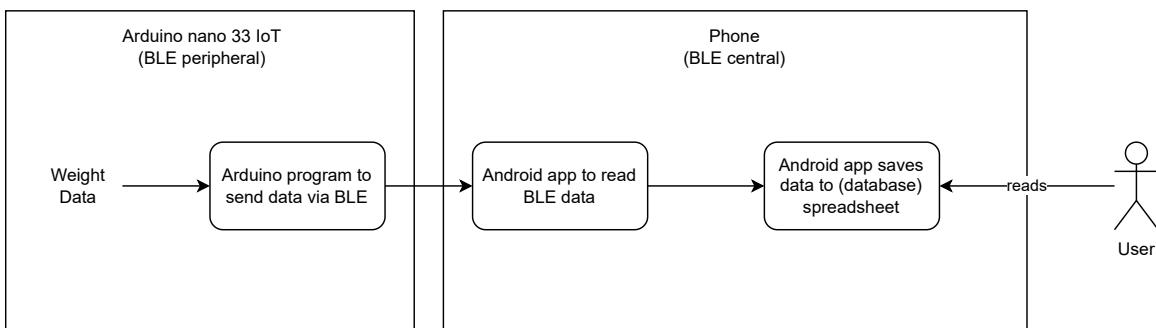


Figure 6.2: Block diagram of subsystem

This subsystem exists in two environments: the Arduino, and the mobile device. The Arduino needs to be programmed to send the weight readings to the mobile device. A mobile app needs to be developed to receive the weight readings. The app needs to provide a GUI that allows the user to input the bird's ID. The app should save the data to a spreadsheet for the user to view.

### 6.4.1 Sending data

BLE works differently to Bluetooth Classic. Bluetooth Classic is based on an asynchronous serial connection. BLE, on the other hand, works like a community bulletin board [?]. The peripheral device posts data for central devices to read [?]. This model is shown below in figure 6.3.

Figure 6.3: BLE Bulletin Board Model [?]

The information presented by the peripheral device is structured as services, which are subdivided into characteristics [?]. BLE includes a mechanism known as notify. This notifies central devices when the data changes.

A program was developed and uploaded to the Arduino. This program, `send_data.ino`, can be found under the `send_data` folder in the project repository. Firstly, in the setup function, the BLE name of the device is set to ‘Arduino Nano 33 IoT’. Then, a custom service is advertised and a characteristic is added to the service. In an infinite loop, the program checks if a central device is connected. If there is, then the weight value is converted to a string and written in to the *weight* characteristic. The connected central device would then be able to read the *weight* reading as a string.

### 6.4.2 Mobile app

<https://github.com/karanimaan/EEE4113F-Project-Group-26/tree/main/Mobile>

The Graphical User Interface (GUI) is responsible for displaying the live reading coming from the Arduino, and allowing the user to capture that reading and input the bird ID. The GUI also needs a save button to save the data to a file, so that the user can view the data in a spreadsheet. The prototype of the GUI is shown below in figure 6.4.

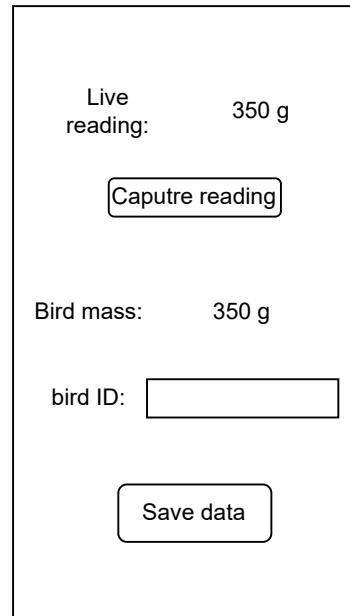


Figure 6.4: GUI prototype

FID	Date	Time	Bird ID	Mass
0	2024-05-11	21:44:58	BMXF	245.7
1	2024-05-11	21:45:41	PBMY	346.9

Figure 6.5

Firstly, a column (vertical layout) is created. Within it, the components are created. A screenshot of the GUI on startup is shown below in figure ??.

#### 6.4.3 Saving data

The spreadsheet should have the following fields: FID, Date, Time, ID, Ring type, Sex, Mass, Day status, Day status, Day (of week), Weekday, Term, Name, Weighing Session, Location, Notes, People Count 1, People Count 2.

FID - pk Date, Time, Day, Weekday, Weighing Session, Location - Kotlin ID, Day status, Name, Notes, People Count 1, People Count 2 - user Ring type, Sex - BirdID table Mass - Arduino Term - Terms table

### 6.5 Acceptance Test Procedure

Testing was done on a Samsung S9 phone running Android 10.

### 6.6 Unit Testing

#### 6.6.1 Sending data

For the purpose of unit testing, the weight value was hard-coded to 346.2. *LightBlue*, a mobile app, was used to test the Arduino sending data. Screenshots of the process are shown below in figure 6.6.

On the homepage, a list of devices is displayed. The device ‘Arduino Nano 33 IoT’ was connected to. The service was selected and the characteristic was read. The data format ‘UTF-8 String’ was selected, and the weight reading was displayed. This reading corresponded with the hard-coded value in `send_data.ino`.

#### 6.6.2 User Acceptance Testing

### 6.7 Conclusion

## 6.7. Conclusion

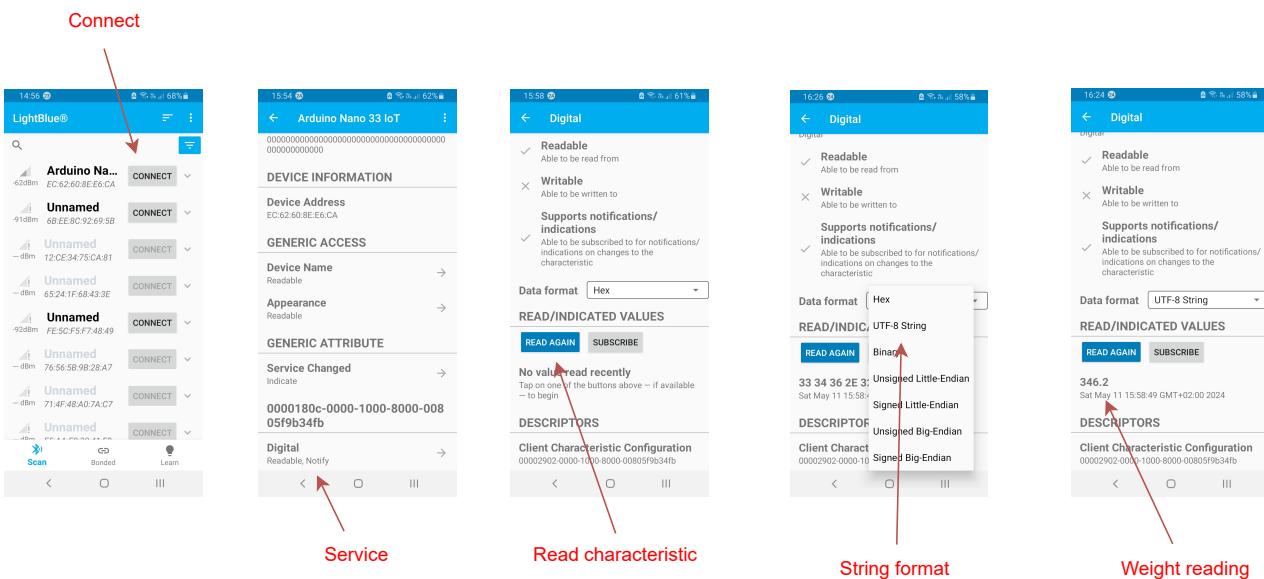


Figure 6.6: Testing the Arduino sending data

# Chapter 7

## Housing Subsystem (VSTMIC004)

### 7.1 Introduction

The aim of this subsection is to discuss the design and implementation of the housing of the final design. This housing will physically contain and protect all other subsystems as well as facilitate their operation.

### 7.2 Requirement Analysis

Table 7.1: Functional Specifications of the Housing Subsystem

User Requirement	Specification Description	Specification no.
Portable	The final internal size of the design must be 100x100x50mm	HS1
Weight Capacity	The final design must be able to support the weight of all other subsystems including the maximum weight of the scale.	HS2
Weight Distribution	The final design must be able to contain all other subsystems in such a way that the overall center of gravity of the final design sits in the middle of the housing subsystem	HS3
External Push Button	The housing must support an external push button that can directly interface with the tare function developed in the Sensing Subsection	HS4

### 7.3 Design Process

#### 7.3.1 Housing Sections

The sections that will make up the housing subsystem can be broadly categorized into two sections; the outer section and the inner section. The outer section will directly interface with the users while the inner section will interface and house the other subsections.

The outer section will need to comply not only with all the user requirements but will also need to comply with any further material considerations, as will be discussed in section [next]. The outer section will directly interact with specifications HS1, HS2, HS3 and HS4.

The internal section will primarily govern the HS3 specification as it will determine how the other subsections will be contained within the final housing. It will need to distribute the weight of all other subsections such that the accuracy of the sensing subsection is not affected.

### 7.3.2 Material Requirements

As emphasized during the literature review, material choice is a component that is of particular importance regarding this subsection. Not only is material choice a variable in the execution of the user requirements, but it is important to choose materials that won't harm or pose any danger to the wildlife that will be interacting with the final design. From the research conducted in the literature review, the following material specifications have been designated,

Table 7.2: Material Requirements

Material Requirement	Requirement Description	Requirement no.
Avian-safe	The materials used should not be toxic in any way towards avian species. The materials used should not have any sharp edges or corners that can harm avians that will be interacting with the final design.	HSM1
User-safe	The materials used should not be toxic in any way to the users that will interact with the final design. The materials used should not have any sharp edges or corners that can harm users that will interact with the final design.	HSM2
Density Consistency	The materials chosen should be evenly dense such that the center of gravity of the final housing design lies equidistant between all edges of the outer section	HSM3
Ease of Modularity	The materials chosen must be easy to modify (either permanent or temporary modifications) by both the designers of the subsection and end users.	HSM4
Environmental Resistance	The materials chosen should be able to resist damage from water and sunlight such that, even if prolonged for long periods of time, the functionality of every subsection (including this one) remains unaffected.	HSM5
Budget Constraint	The total cost of all the materials required should fall within the budget for the entire subsection (R450)	HSM6

### 7.3.3 Material Options

After going over all of the information obtained in the literature review, a common through-line is that synthetic materials and metals tend to raise the most concern regarding avian toxicity. Metals, especially thinner pieces, would struggle adhering to each other without the use of solder or welding as they will be too thin to be screwed together. This is especially cause for concern as direct contact with solder or any lead-based adhesive will direct lead to avian toxicity. Taking all of this into account, all materials that will be considered will be wooden or wood-based. This way we can insure all user requirements are met. Taking into account all viable materials available at local hardware stores, the following list has been compiled alongside all material requirements they fulfill. The following list includes the associated product code at BuCo as of 2024/05/12. From this list, materials that fulfill all requirements will be analyzed further based on their cost-effectiveness.

From the above list the two most viable materials, including their sizing and pricing, are cataloged below,

Taking into consideration the amount of raw material obtained for the price, SupaWood will be selected as the primary material of choice for both the outer and internal sections of the housing.

### 7.3.4 Housing Layout

The outer section will be designed alongside the internal section of the housing to ensure that they interface properly. The outer section will consist of a 110x110x3mm sheet of SupaWood. This will serve as a platform for the birds to stand on top of while their measurements are being taken. The load cell will be connected on the underside of it in the center. The Internal section of the housing will consist of a 100x100x3mm sheet of SupaWood with four 2x100x3mm slabs of SupaWood attached on each edge. This will ensure that all internal components will be fixed in place and protected from environmental conditions. The load cell will be connected to the top of the internal section and hence connects the internal and outer sections of the housing together.

## 7.4 Acceptance Test Procedures and Quality Assessment

It is vital that we test the housing subsystem and ensure its quality to ensure that it will not negatively affect any other subsystem. It is also vital that the housing complies to all requirements. If the housing fails any of the listed requirements, then it will end up negatively affecting the end user and will make the entire design unreliable.

The portability requirement (HS1) is achieved and validated during the layout design stage of the subsystem. With both sections of the layout connected, the entire design will still comply with the specified range of 110x110x50mm. This will ensure that the entire system, including all subsystems and internal components, remain portable and easy to use for the end user.

The weight capacity requirement (HS2) is directly related to the material choice of the housing. As we decided on using SupaWood, which can support weights far greater than the maximum rating of the final design (500g), the housing will be able to support not only the weight of itself but also any weight that will be placed on the scale.

The weight distribution requirement (HS3) is primarily governed by the material choice and housing layout. The layout was designed in such a way that the weight of all internal components and subsystems do not place any external strain on the load cell. This leads to the entire system remaining intrinsically balanced in such a way to ensure accuracy of the sensing subsystem. The material choice also reinforces this, as it was chosen specifically for its low tolerance for density variation.

The external push button requirement (HS4) is easily implemented as the push button can directly be connected to the internal section of the housing without placing any loading or external strain on the load cell while in use. The inclusion of a push button will also not impede on any other requirements, due to the nature of the layout.

## 7.5 Conclusion

In conclusion, through an iterative and analytical design process, a viable housing system was developed. The purpose of this housing is vital to the overall design, as it facilitates the operation of all other subsystems. This housing also ensures that the final design is portable and easy to interface with for the end user. Many materials were considered during the designing of the housing and after consulting several studies the importance of natural materials for this application were made explicit. The final material choice complies with all material requirements laid out and facilitates the ease of execution of the acceptance test procedures. All of these factors combined resulted in a housing design that is suitable for real world application.

Table 7.3: Material Requirements

<b>Product Type</b>	<b>BuCo SKU</b>	<b>Requirements Fulfilled</b>	<b>Requirement Discussion</b>
Plywood	1274706	HSM1,HSM2,HSM3,HSM4, HSM5, HSM6	Fulfills all material requirements
Hardboard	1292581	HSM1, HSM2, HSM3, HSM4, HSM6	Does not fulfill the HSM5 requirement as it has little moisture resistance.
Chipboard	1283947	HSM1, HSM2, HSM3, HSM6	Does not fulfill the HSM4 requirement as it cannot be altered easily without the use of adhesives, which will compromise the structural integrity.

<b>Product Type</b>	<b>Dimensions (mm)</b>	<b>Pricing</b>	
Plywood	2440x1220x3.6	R426.98	
SupaWood	2750x1830x3	R302. 02	

# Chapter 8

## Conclusions

The same rule holds for us now, of course: we choose our next world through what we learn in this one. Learn nothing, and the next world is the same as this one.

—Richard Bach, *Jonathan Livingston Seagull*

The purpose of this project was to...

This report began with...

The literature review was followed in Chapter...

The bulk of the work for this project followed next, in Chapter...

In Chapter...

Finally, Chapter... attempted to...

In summary, the project achieved the goals that were set out, by designing and demonstrating...

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# Appendix A

## Appendix A4

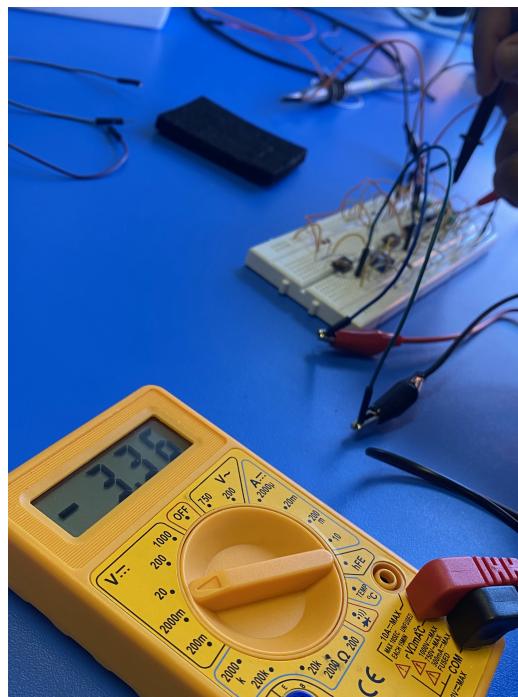


Figure A.1: Image of split supply test

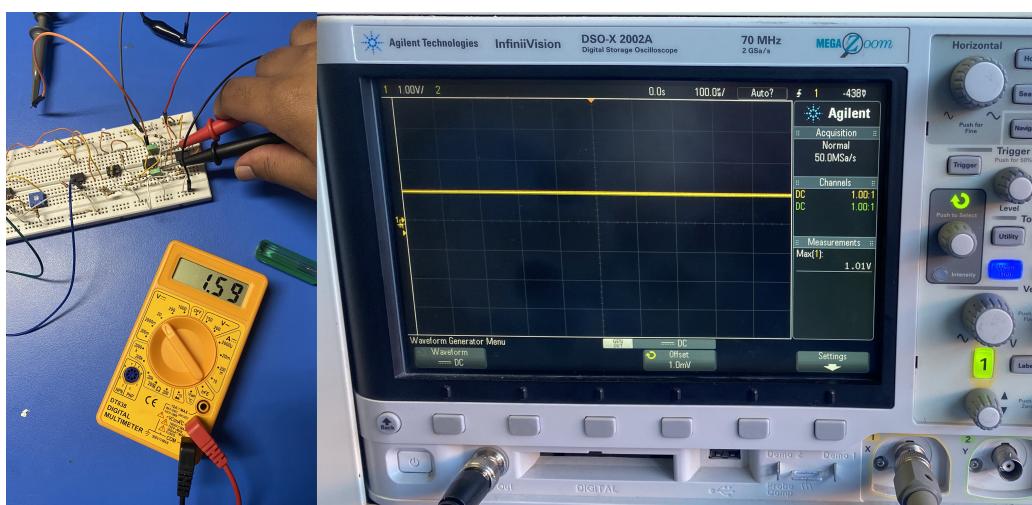


Figure A.2: Image of Amplifier test when input is 1mV

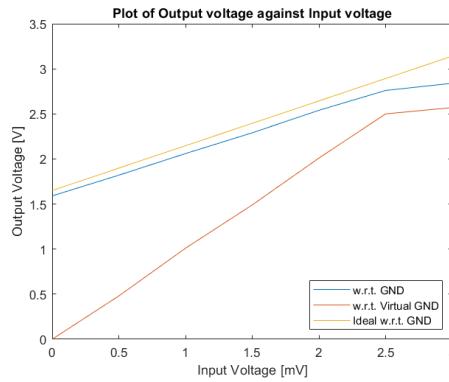


Figure A.3: Plot of Output voltage against input voltage from the oscilloscope

ELECTRICAL CHARACTERISTICS								
Parameter	Conditions	LM195			LM395			Units
		Min	Typ	Max	Min	Typ	Max	
Collector-Emitter Operating Voltage	$I_C \leq I_{C\text{MAX}}$							V
Base to Emitter Breakdown Voltage	$0 \leq V_{BE} \leq V_{BEMAX}$	42			36	60		V
Collector Current								
TO-3, TO-220	$V_{CE} \leq 15V$	1.2	2.2		1.0	2.2		A
TO-5	$V_{CE} \leq 7.0V$	1.2	1.8		1.0	1.8		A
Saturation Voltage	$I_C \leq 1.0A, T_A = 25^\circ C$	1.8	2.0		1.8	2.2		V
Base Current	$0 \leq I_B \leq I_{BMAX}$		3.0	5.0		3.0	10	$\mu A$
	$0 \leq V_{CE} \leq V_{CEMAX}$							
Quiescent Current ( $I_Q$ )	$V_{BE} = 0$		2.0	5.0		2.0	10	mA
	$0 \leq V_{BE} \leq V_{BEMAX}$							
Base to Emitter Voltage	$I_C = 1.0A, T_A = +25^\circ C$		0.9			0.9		V
Switching Time	$V_{CE} = 36V, R_L = 36\Omega, T_A = 25^\circ C$	500			500			ns

(1) Unless otherwise specified, these specifications apply for  $-55^\circ C \leq T_J \leq +150^\circ C$  for the LM195 and  $0^\circ C \leq +125^\circ C$  for the LM395.  
(2) Selected devices with higher breakdown available.  
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Product Folder Links: [LM195](#) [LM395](#)

Figure A.4: LM395 Electrical Specifications

# Appendix B

## Appendix A5

ELECTRICAL CHARACTERISTICS									
Parameter	Conditions	LM195			LM395			Units	
		Min	Typ	Max	Min	Typ	Max		
Collector-Emitter Operating Voltage	$I_C \leq I_{C\text{MAX}}$			42			36	V	
Base to Emitter Breakdown Voltage	$0 \leq V_{BE} \leq V_{BEMAX}$	42			36	60		V	
Collector Current									
TO-3, TO-220	$V_{CE} \leq 15V$	1.2	2.2		1.0	2.2		A	
TO-5	$V_{CE} \leq 7.0V$	1.2	1.8		1.0	1.8		A	
Saturation Voltage	$I_C \leq 1.0A, T_A = 25^\circ C$		1.8	2.0		1.8	2.2	V	
Base Current	$0 \leq I_B \leq I_{BMAX}$		3.0	5.0		3.0	10	$\mu A$	
Quiescent Current ( $I_Q$ )	$V_{CE} = 0V, T_A = 25^\circ C$		2.0	5.0		2.0	10	mA	
Base to Emitter Voltage	$I_B = 1.0A, T_A = +25^\circ C$		0.9			0.9		V	
Switching Time	$V_{CE} = 36V, R_L = 360\Omega, T_A = 25^\circ C$	500			500			ns	

(1) Unless otherwise specified. These specifications apply for  $-55^\circ C \leq T_J \leq +150^\circ C$  for the LM195 and  $0^\circ C \leq +125^\circ C$  for the LM395.  
(2) Selected devices with higher breakdown available.

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Figure B.1: LM395 Electrical Specifications

# Appendix C

## Appendix A6

### C.1 GA Table: VSTMIC004

Table C.1: GA Table for VSTMIC004

Housing Subsystem	Where met
GA 3: Engineering Design	Sections 3 and 6
GA 7: Sustainability and Impact of Engineering Activity	Section 6
GA 8: Individual, Team and Multi-Disciplinary Working	See Teams group for meeting minutes
GA 10: Engineering Professionalism	All submission activities met including final report and presentation