

Ngày 5 tháng 6 năm 2023

Buổi sáng

Buổi chiều

Ngày 6 tháng 6 năm 2023

Buổi sáng

Làm mô phỏng quạt ốc sên (lỗi)

Buổi chiều

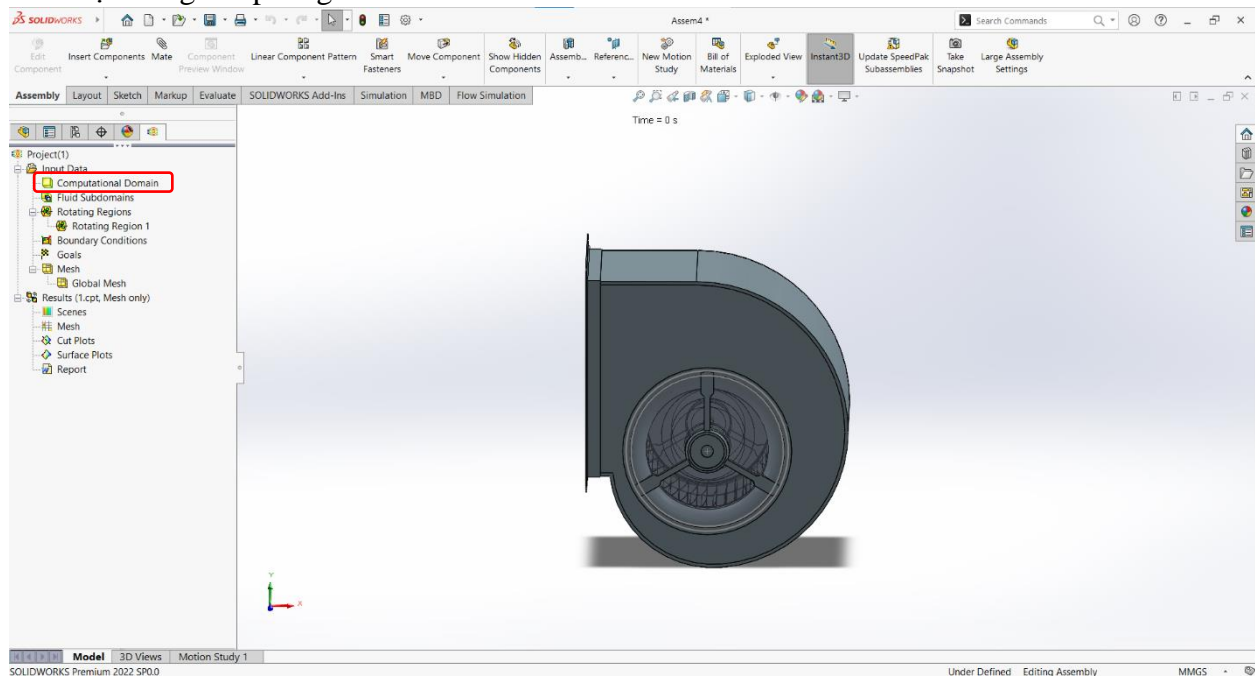
Làm mô phỏng quạt ốc sên (lỗi)

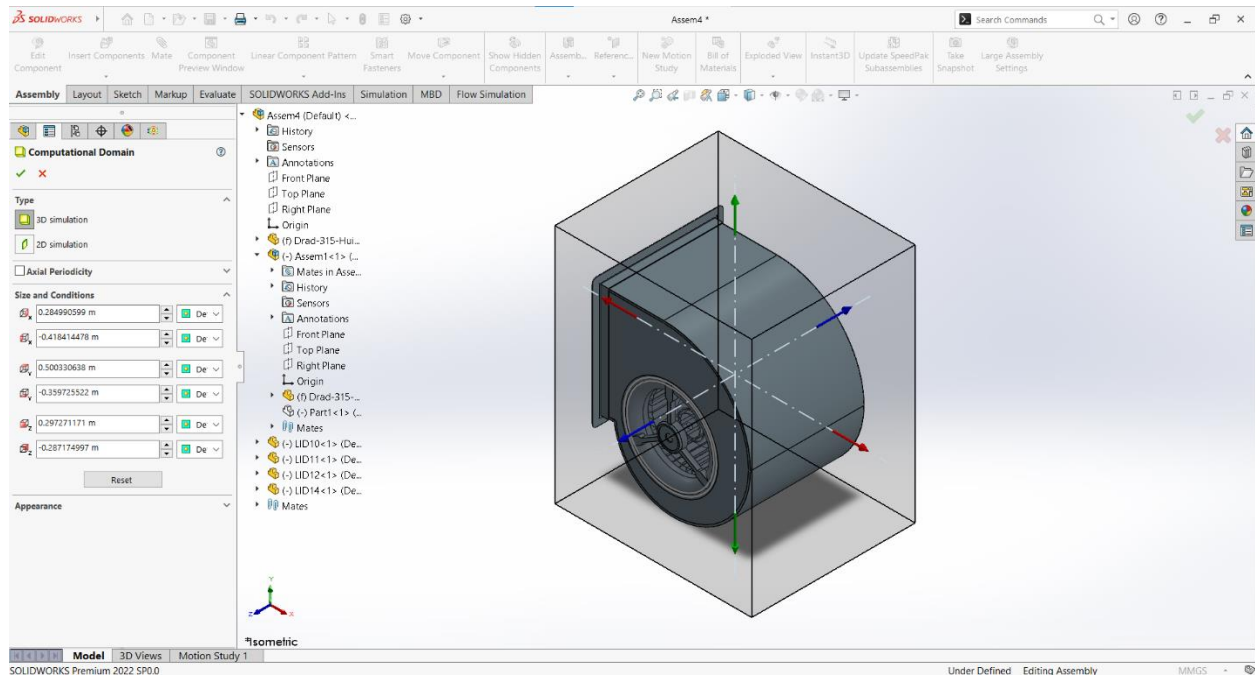
Ngày 7 tháng 6 năm 2023

Buổi sáng

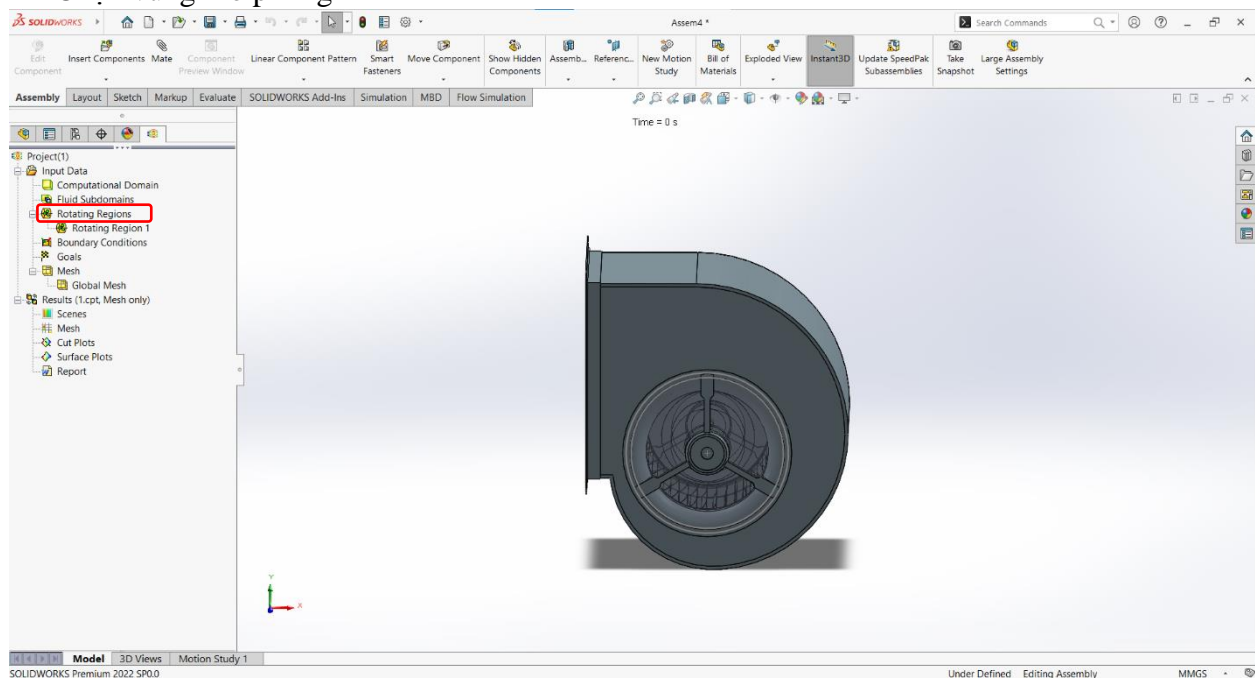
Làm mô phỏng quạt ốc sên (Hoàn thành)

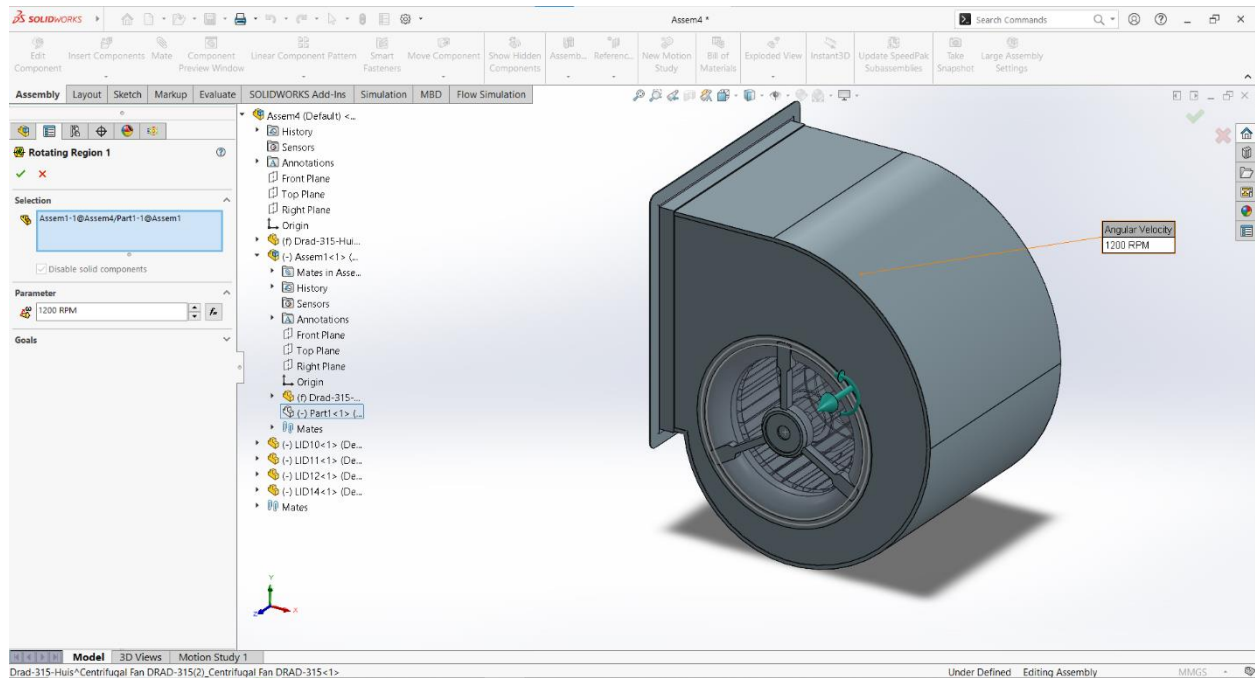
B1 Chọn vùng mô phỏng



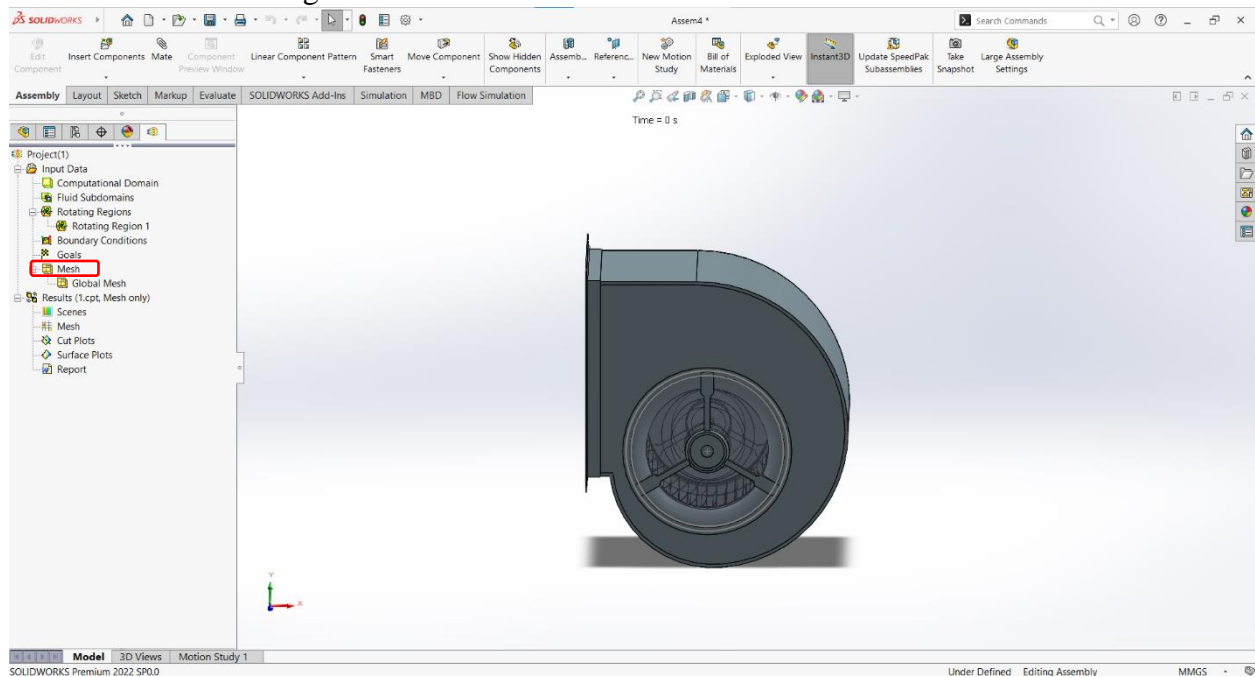


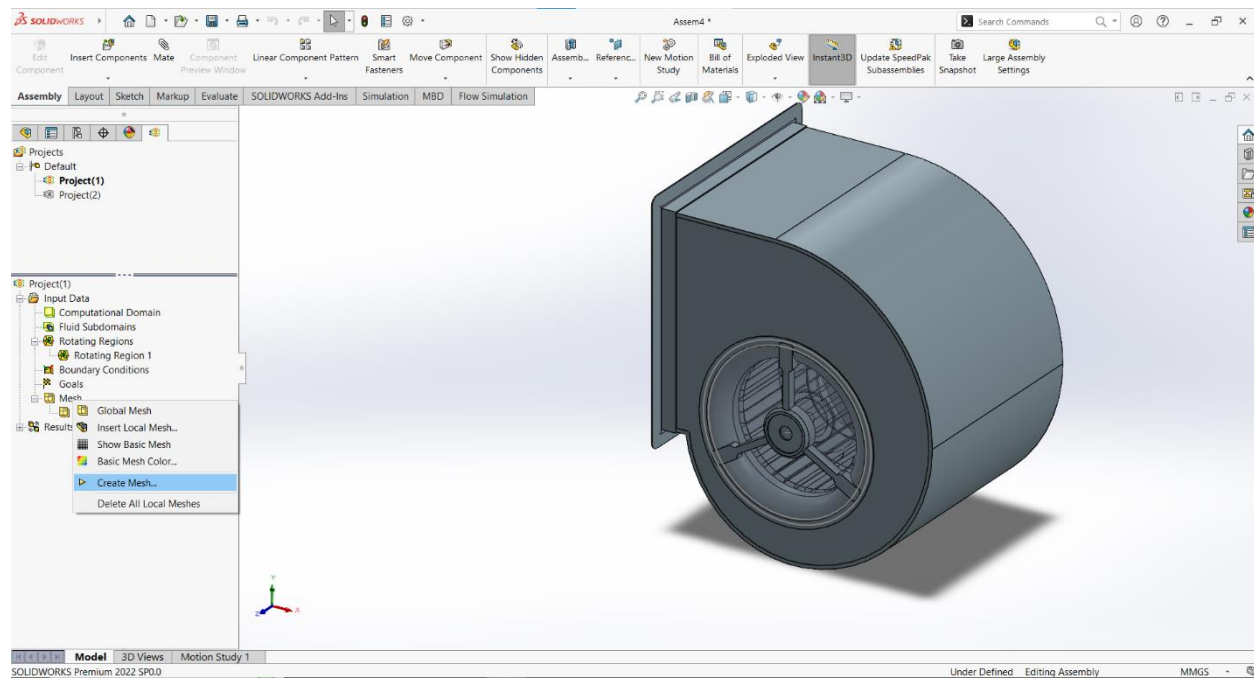
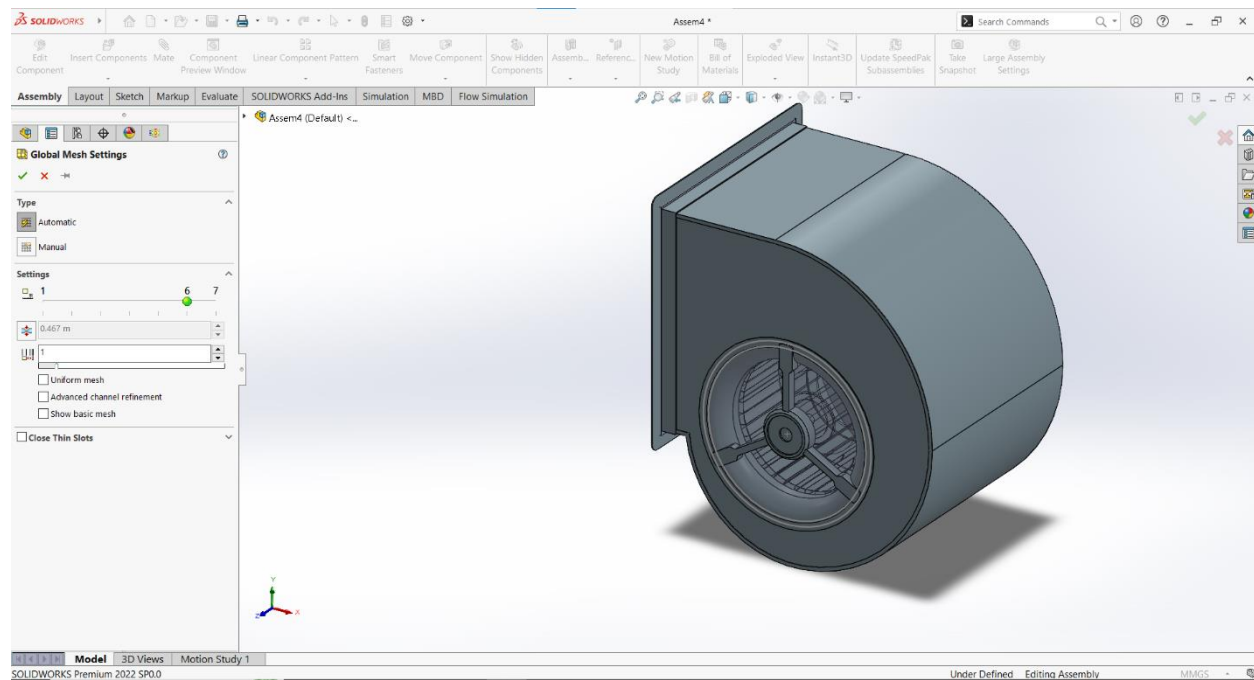
B2 Chọn vùng mô phỏng

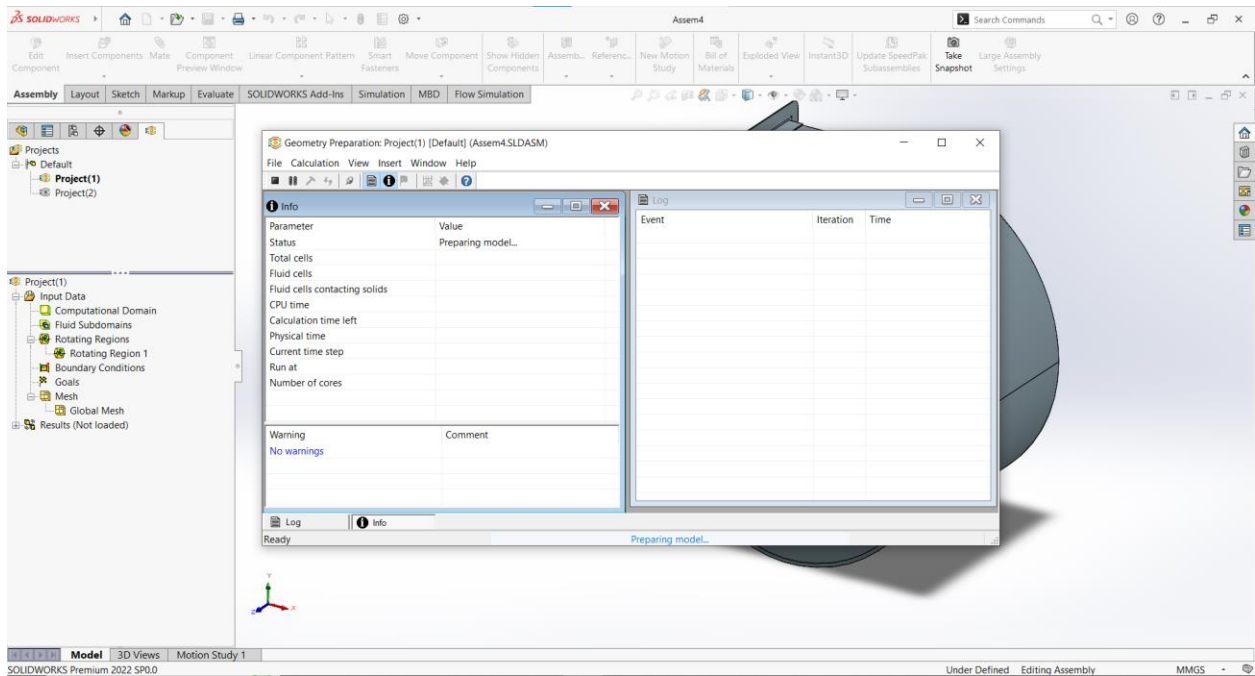
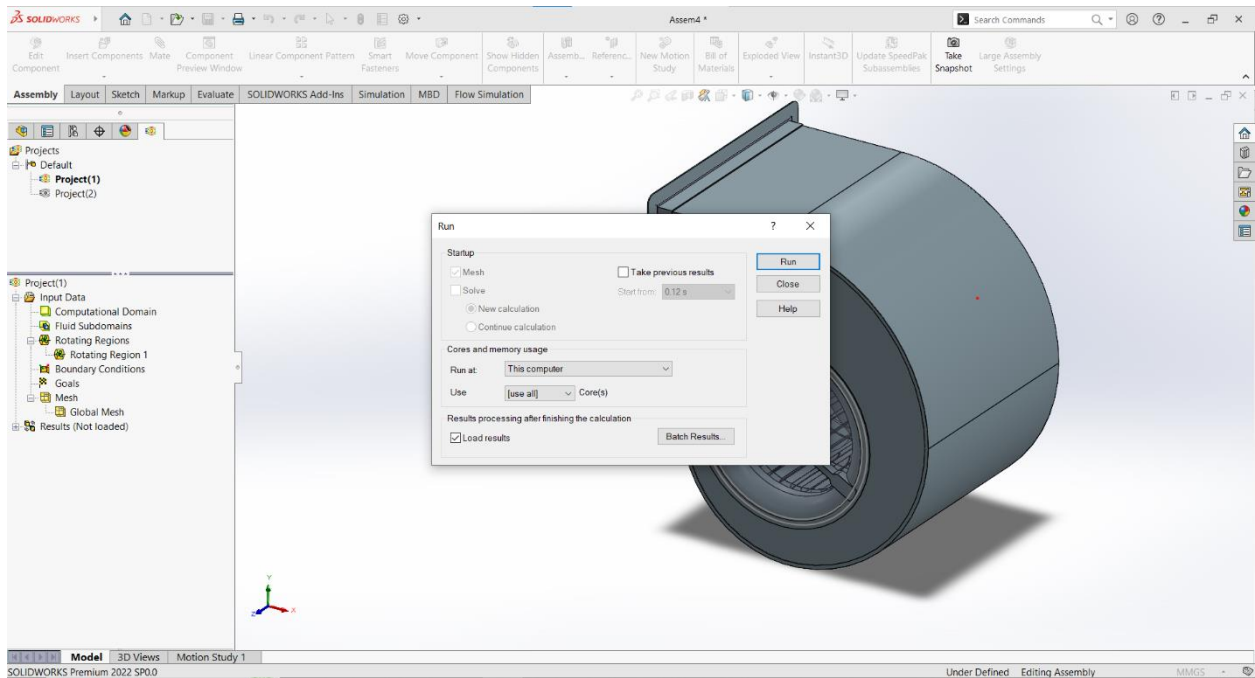


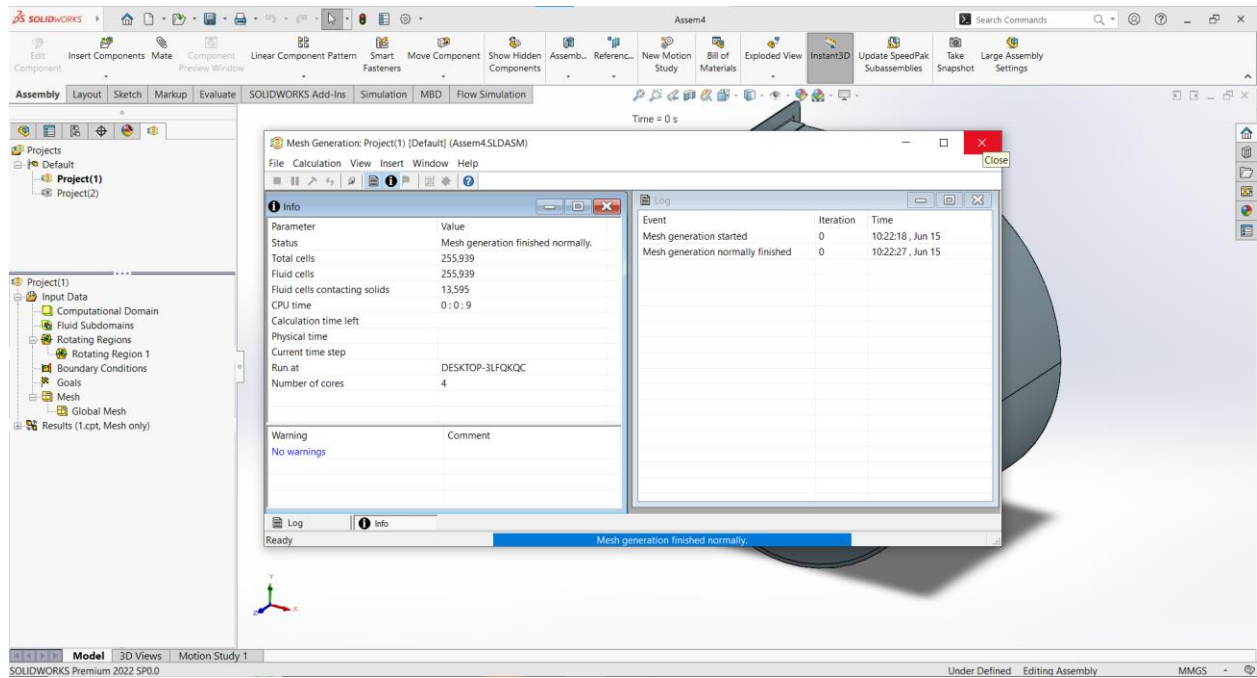


B3 Global Mesh Settings

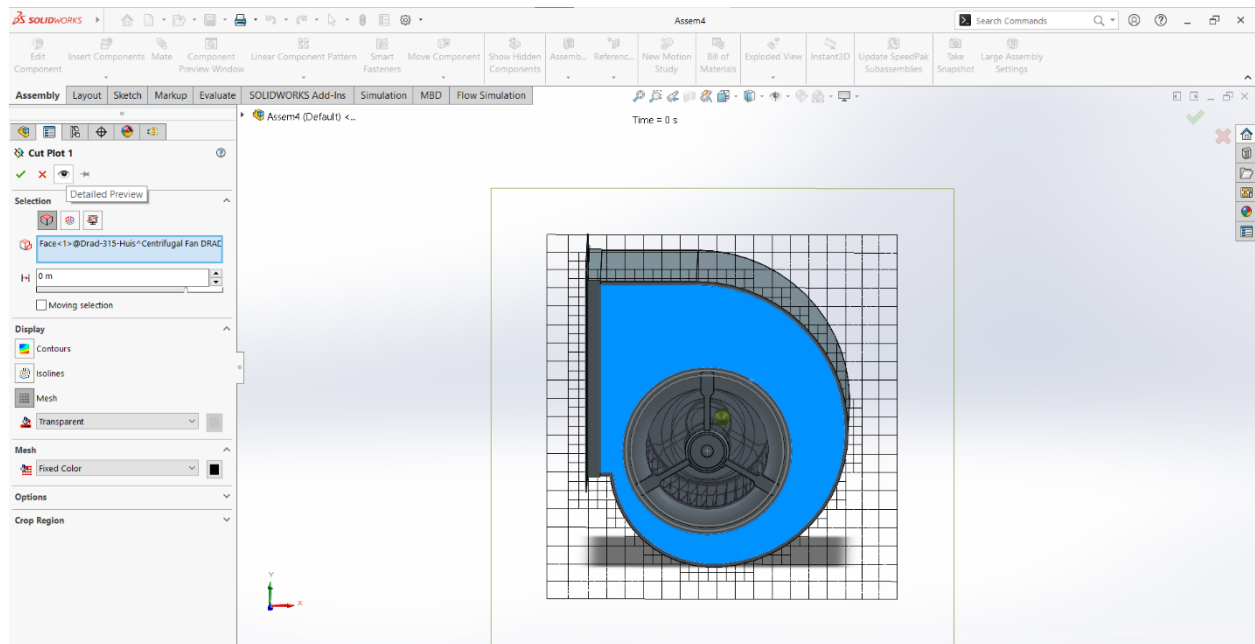
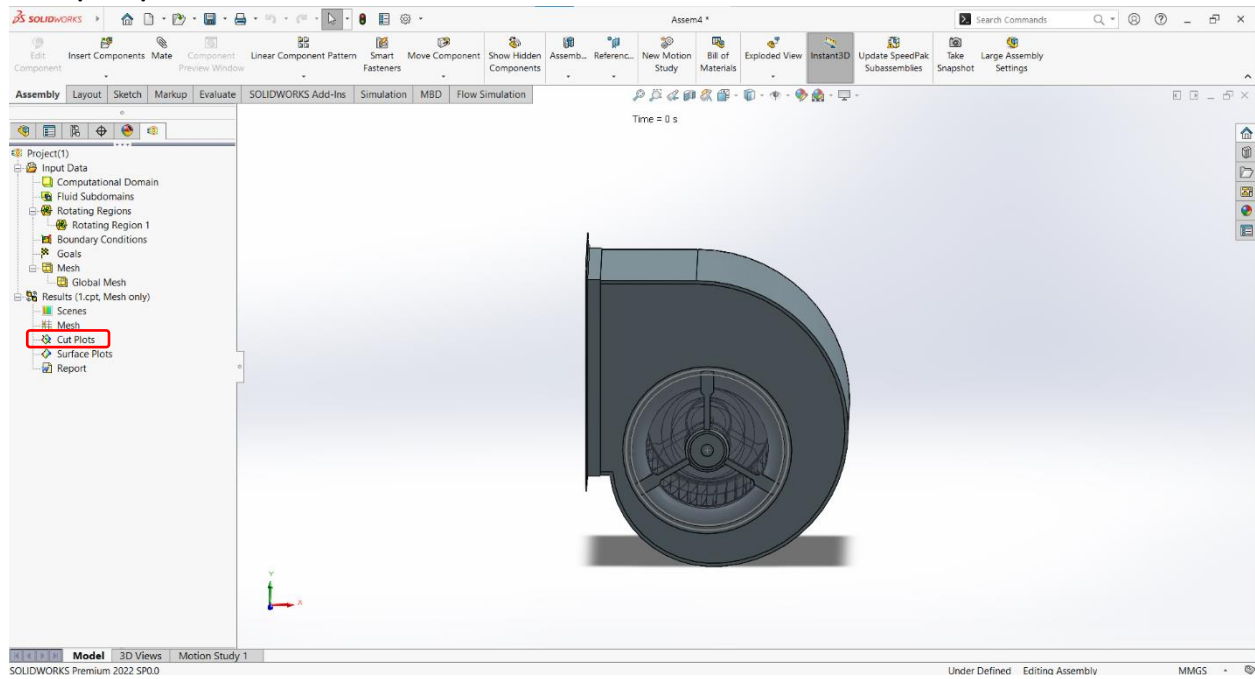




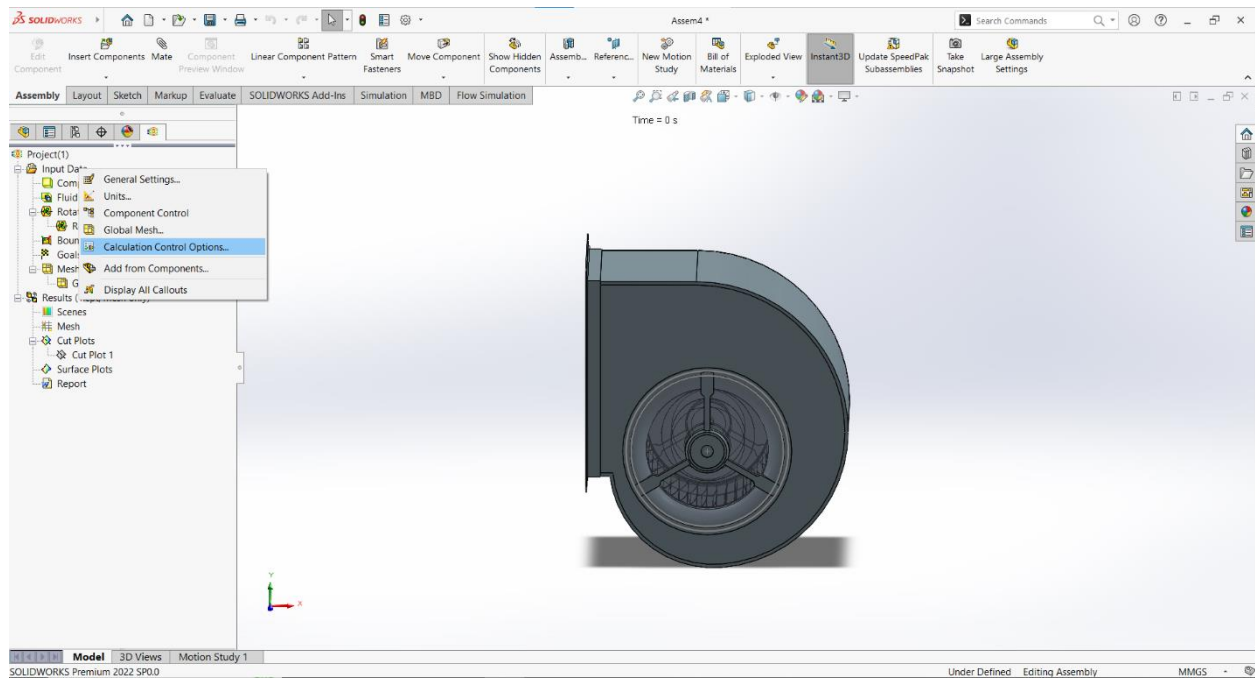
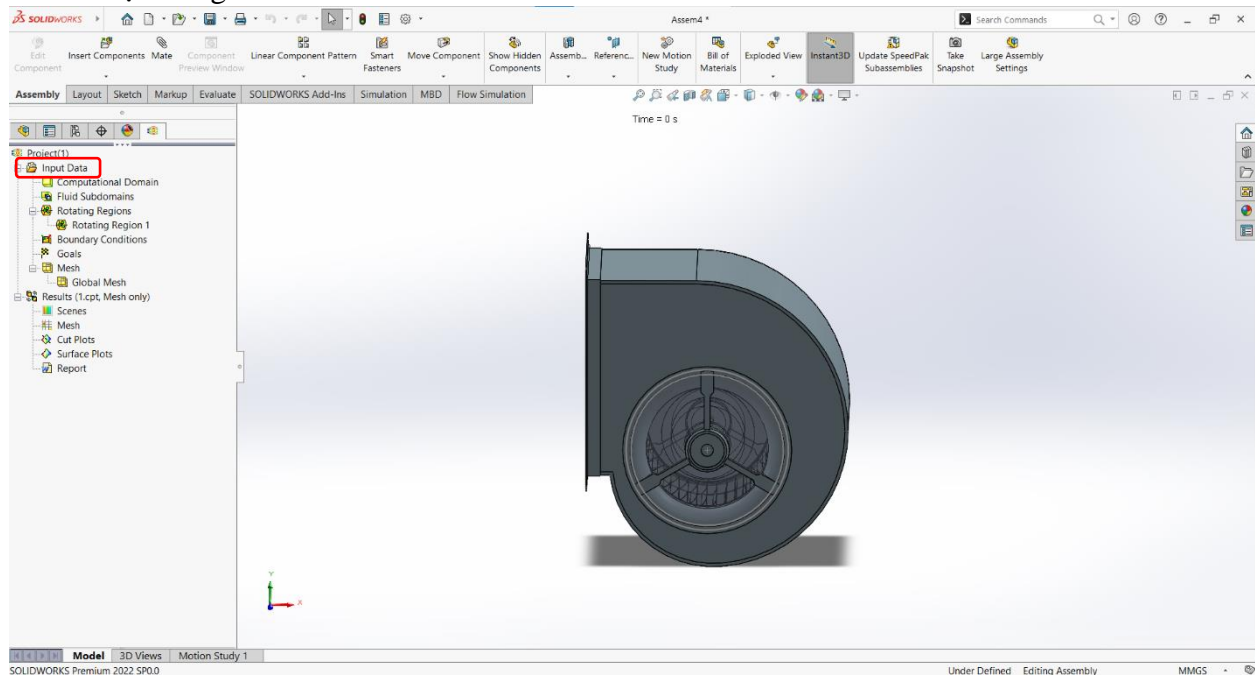


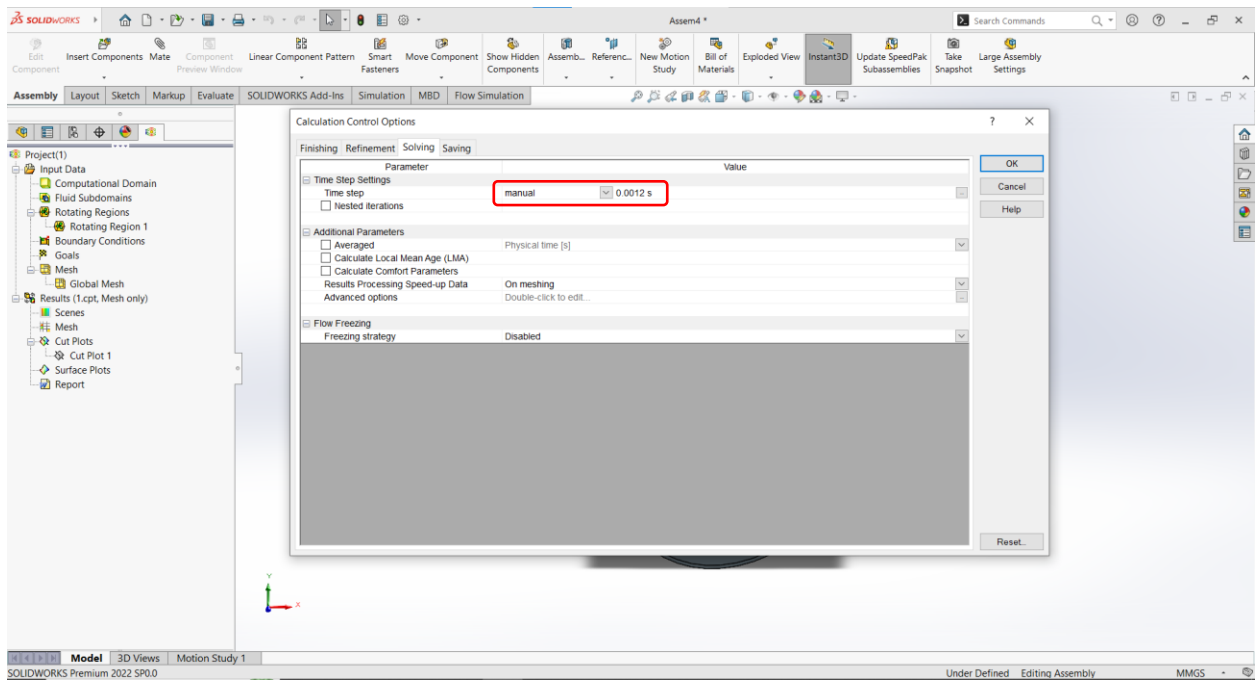
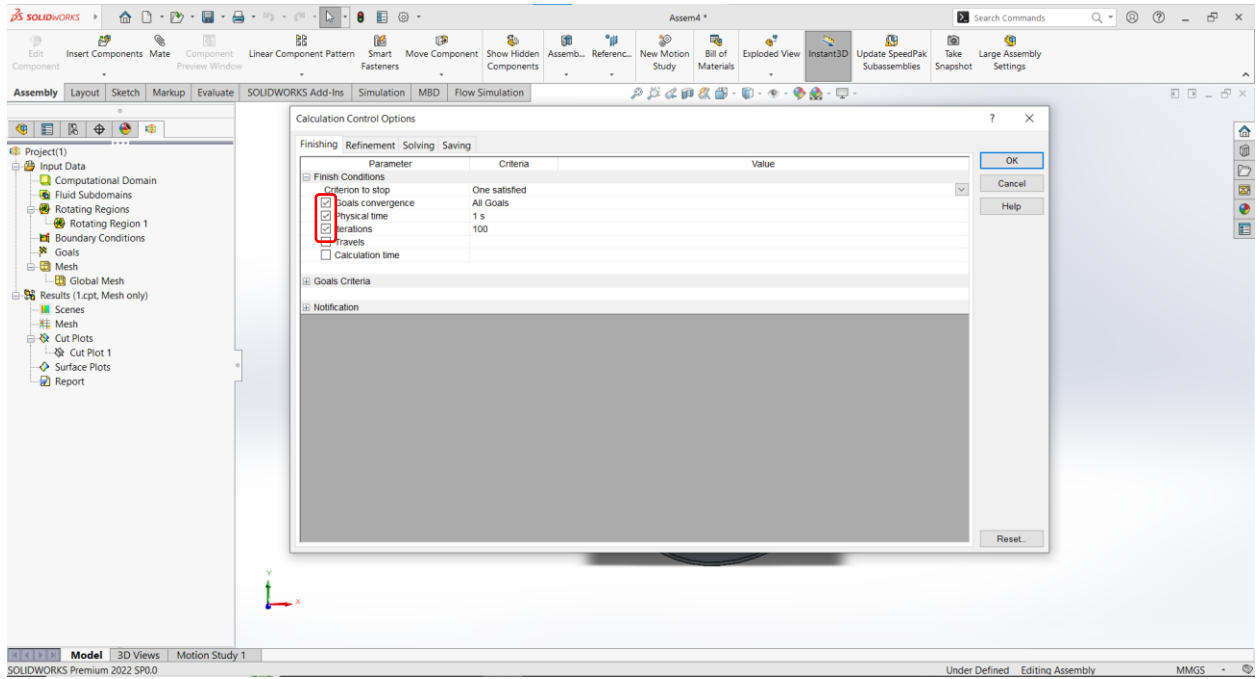


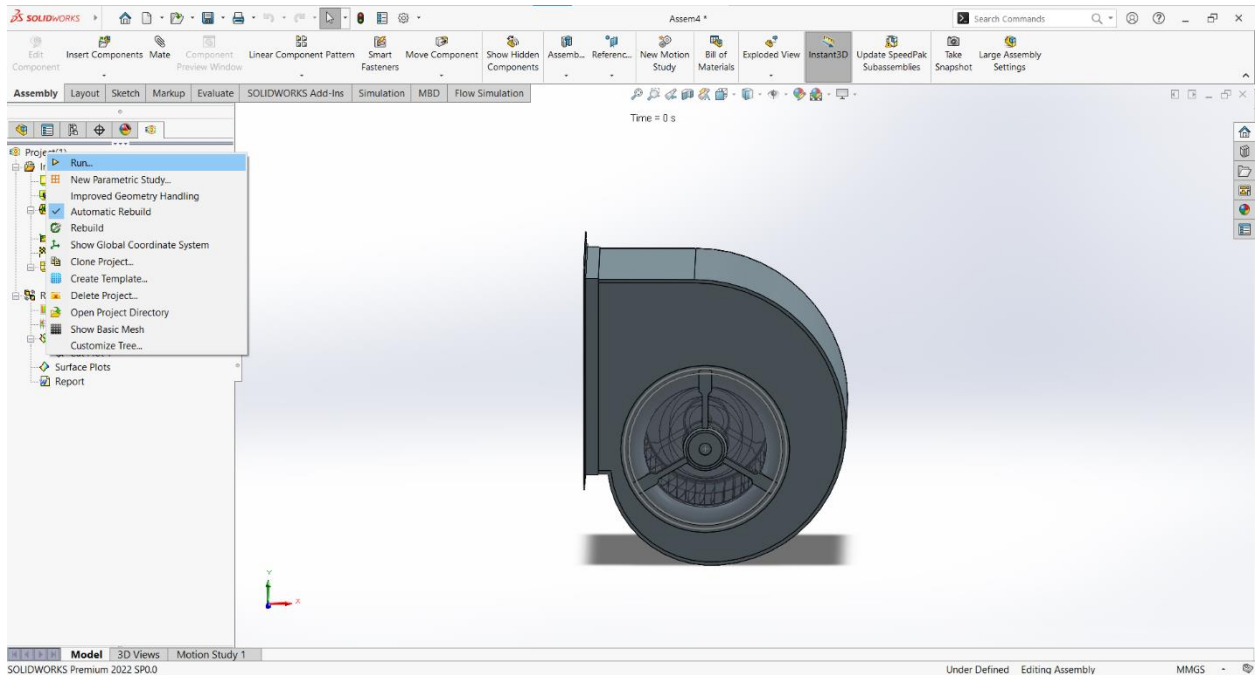
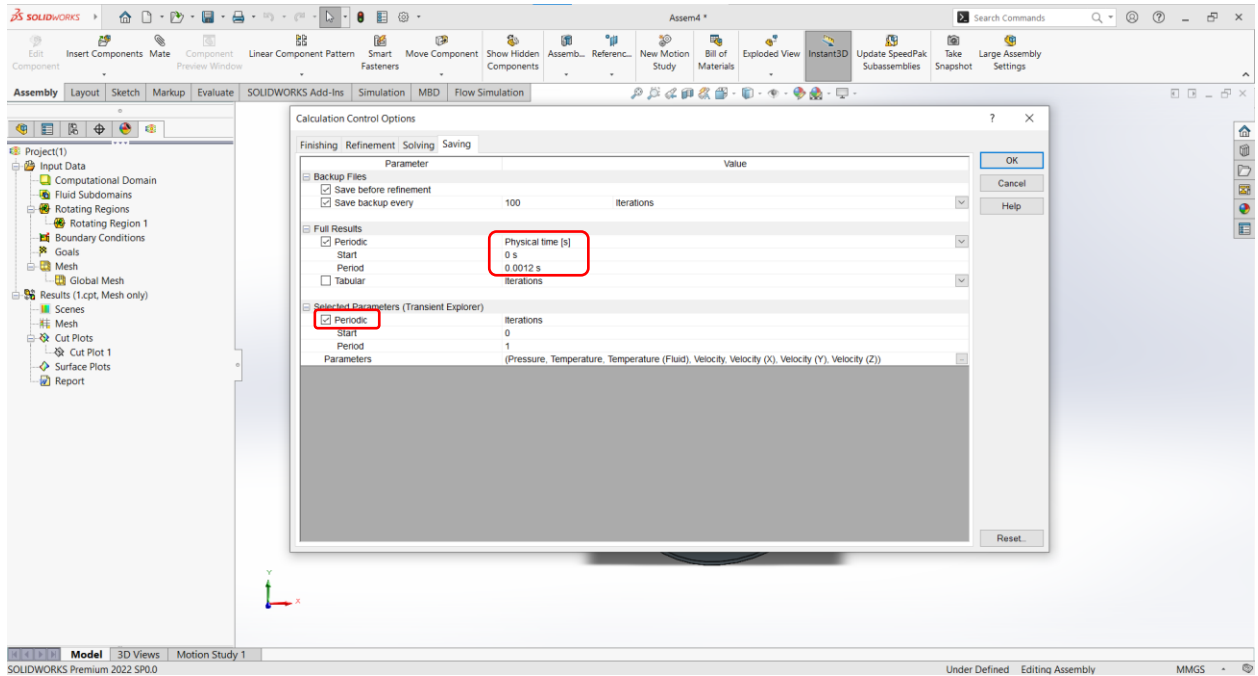
B4 Tạo mặt cắt Cut Plot

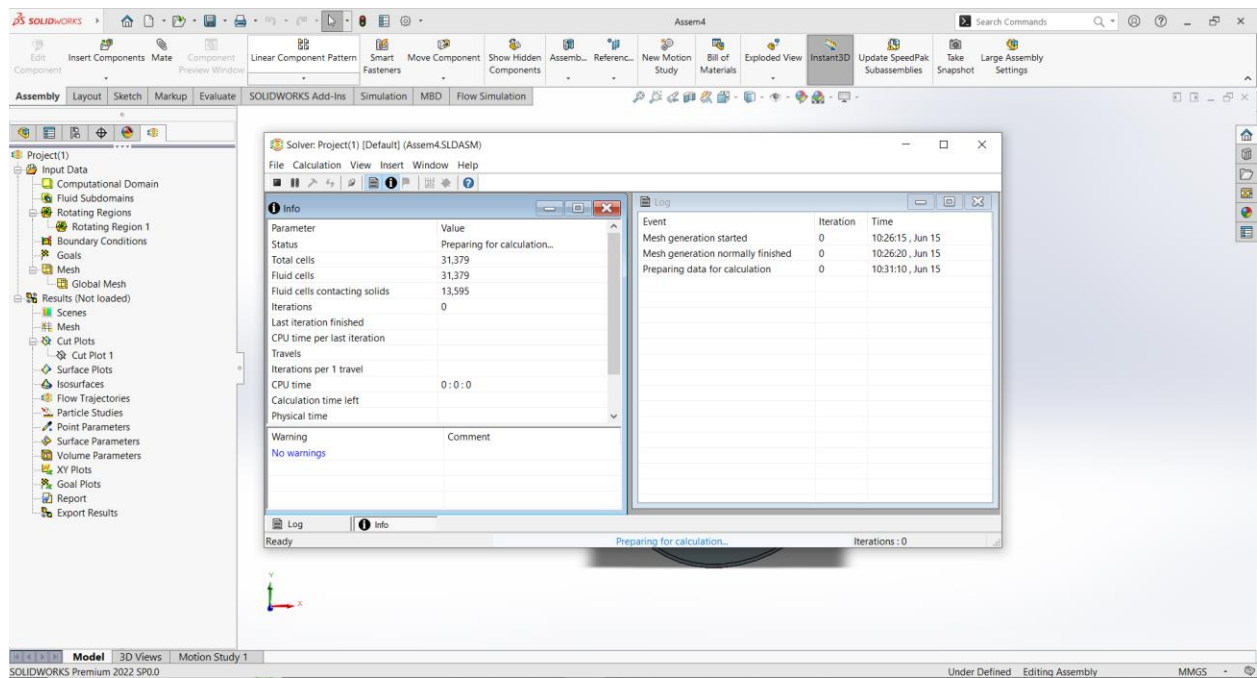
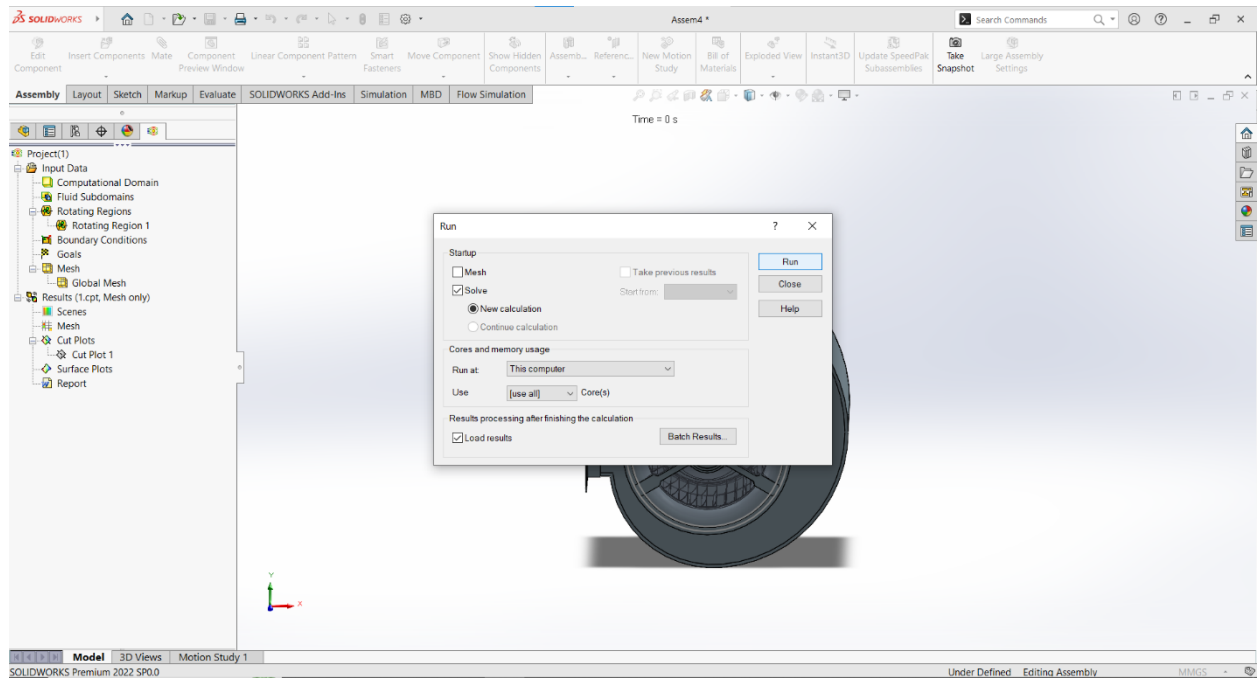


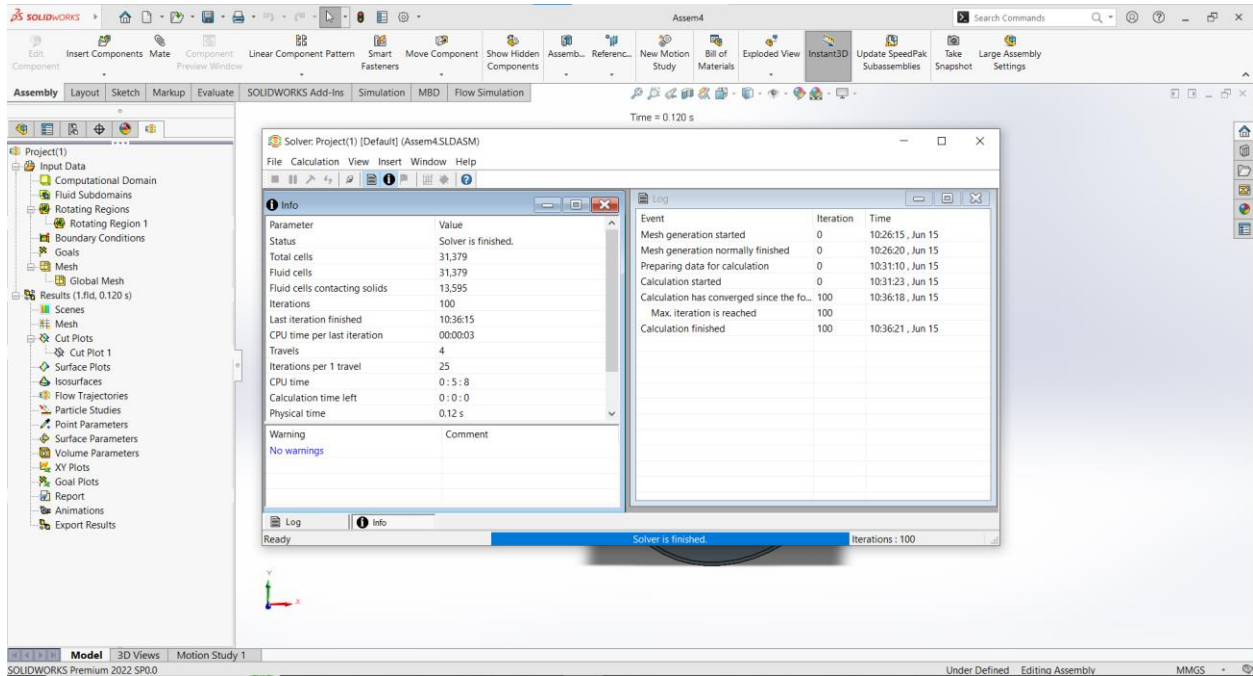
B5 Cài đặt thông số tính toán điều khiển



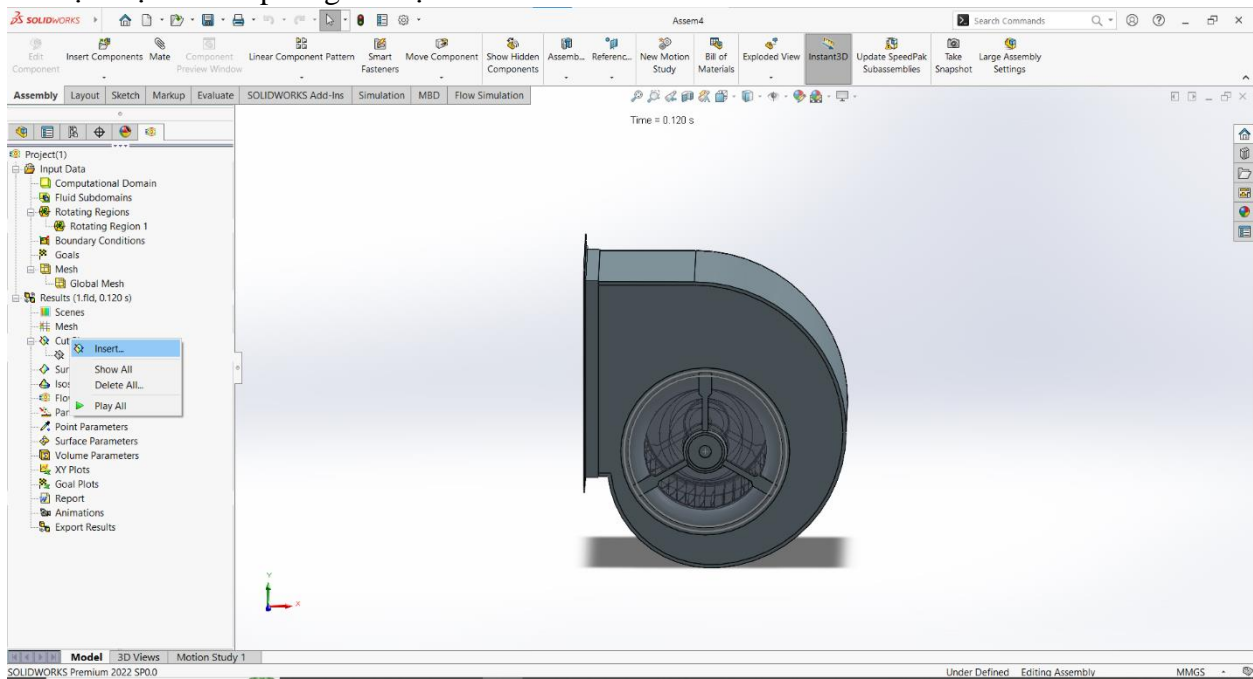


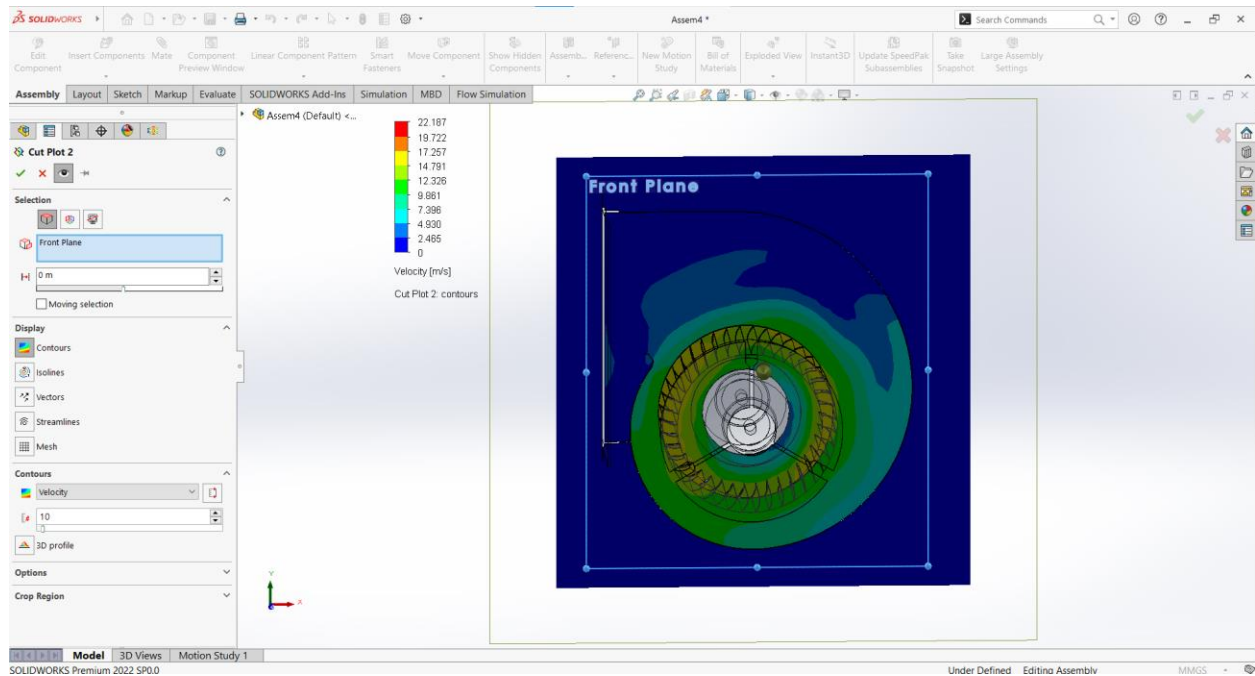
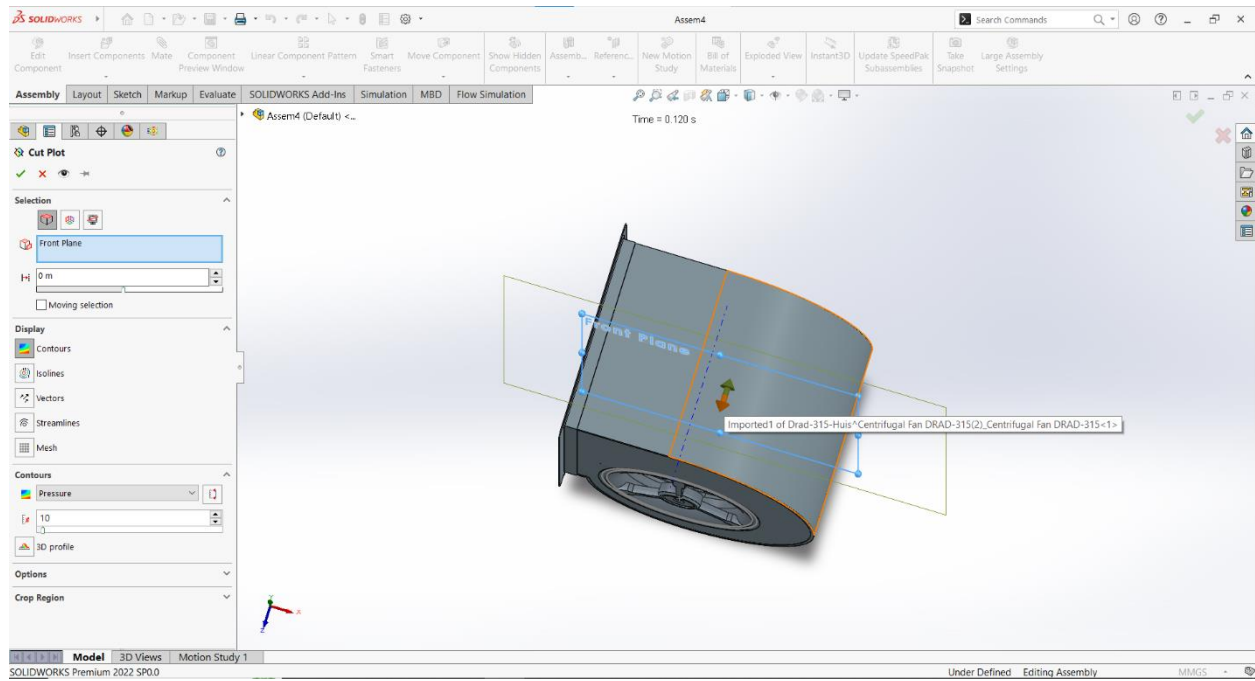


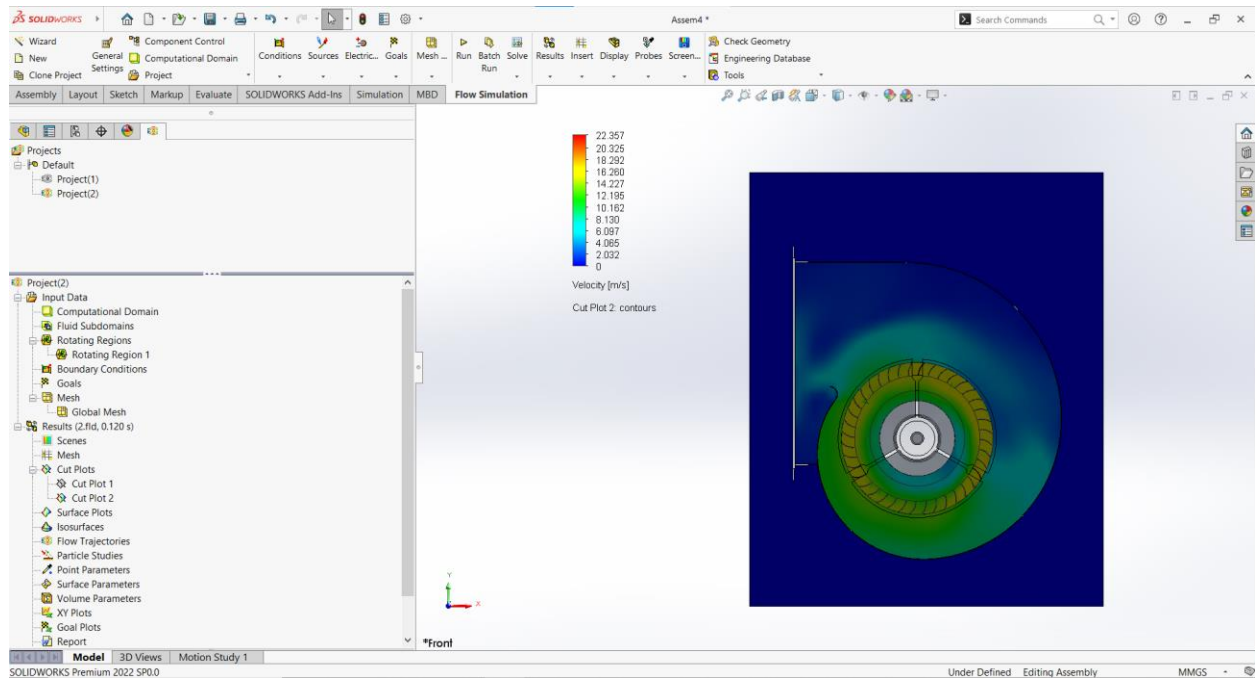




B6 Tạo mặt cắt mô phỏng tốc độ







Buổi chiều

Làm báo cáo và mô phỏng video



video mô phỏng
quạt ốc sên.mp4

Ngày 8 tháng 6 năm 2023

Buổi sáng

Kiểm tra lại code xe dò line

Code

1. float pTerm, iTerm, dTerm;
2. int error, previousError;
3. float kp = 18, ki = 0, kd = 18; // 15
4. float output;
5. int integral, derivative;
6. int motor1newSpeed;
7. int motor2newSpeed;

8. int sensorPins[5] = {A1, A2, A3, A4, A5};
9. int motorPins[6] = {12, 6, 13, 11, 3, 5};
10. int s = 125; // max 120
11. int motor1Speed = s; //Default r
12. int motor2Speed = s; //Default l


```

13.
14. void setup() {
15.   for (int i = 0; i < 5; i++) {
16.     pinMode(sensorPins[i], INPUT_PULLUP);
17.   }
18.
19.   for (int i = 0; i < 6; i++) {
20.     pinMode(motorPins[i], OUTPUT);
21.   }

22.   Serial.begin(9600);
23. }
24. void calculateError() {
25.   int sensorValues[5];
26.   sensorValues[0] = digitalRead(A1);
27.   sensorValues[1] = digitalRead(A2);
28.   sensorValues[2] = digitalRead(A3);
29.   sensorValues[3] = digitalRead(A4);
30.   sensorValues[4] = digitalRead(A5);

31.   int errorValues[13][5] = {
32.     {0, 1, 1, 1, 1}, // 6
33.     {0, 0, 1, 1, 1}, // 5
34.     {0, 0, 0, 1, 1}, // 4
35.     {0, 0, 0, 0, 1}, // 3
36.     {1, 0, 1, 1, 1}, // 2
37.     {1, 0, 0, 1, 1}, // 1
38.     {1, 1, 0, 1, 1}, // 0
39.     {1, 1, 0, 0, 1}, // -1
40.     {1, 1, 1, 0, 1}, // -2
41.     {1, 0, 0, 0, 0}, // -3
42.     {1, 1, 0, 0, 0}, // -4
43.     {1, 1, 1, 0, 0}, // -5
44.     {1, 1, 1, 1, 0}, // -6 100 30
45.   };

46.   for (int i = 0; i < 13; i++) {
47.     bool match = true;
48.     for (int j = 0; j < 5; j++) {
49.       if (sensorValues[j] != errorValues[i][j]) {
50.         match = false;
51.         break;
52.       }
53.     }
54.     if (match) {
55.       error = i - 6;
56.       break;

```

```

57.     }
58. }
59. }
60. void pidCalculations() {
61.     pTerm = kp * error;
62.     integral += error;
63.     iTerm = ki * integral;
64.     derivative = error - previousError;
65.     dTerm = kd * derivative;
66.     output = pTerm + iTerm + dTerm;
67.     previousError = error;
68. }

69. void changeMotorSpeed() {
70.     // Check if all IR readings are 0
71.     if ((digitalRead(A1) == 0) && (digitalRead(A2) == 0) && (digitalRead(A3) == 0) &&
        (digitalRead(A4) == 0) && (digitalRead(A5) == 0)) {

72.         analogWrite(3, 0);
73.         analogWrite(5, 0);
74.         digitalWrite(12, 0);
75.         digitalWrite(6, 0);
76.         digitalWrite(13, 0);
77.         digitalWrite(11, 0);
78.     } else {

79.         // Change motor speed of both motors accordingly
80.         motor2newSpeed = motor2Speed + output;
81.         motor1newSpeed = motor1Speed - output;
82.         int speedThresholds[] = {233, 215, 197, 179, 143};

83.         for (int i = 0; i < sizeof(speedThresholds) / sizeof(speedThresholds[0]); i++) {
84.             if (motor1newSpeed == speedThresholds[i]) {
85.                 motor1newSpeed = s;
86.             }
87.             if (motor2newSpeed == speedThresholds[i]) {
88.                 motor2newSpeed = s;
89.             }
90.         }

91.         // Constrain the new speed of motors to be between the range 0-255
92.         motor2newSpeed = constrain(motor2newSpeed, 0, 255);
93.         motor1newSpeed = constrain(motor1newSpeed, 0, 255);
94.         // Set new speed and run motors in the forward direction
95.         analogWrite(5, motor2newSpeed);
96.         analogWrite(3, motor1newSpeed);
97.         digitalWrite(12, 1);

```

```
98.   digitalWrite(6, 1);
99.   digitalWrite(13, 0);
100.      digitalWrite(11, 0);
101.      }
102.      }
103.   void loop() {
104.       calculateError();
105.       pidCalculations();
106.       changeMotorSpeed();
107.       Serial.println(output);
108.       Serial.print("motor1newSpeed: ");
109.       Serial.println(motor1newSpeed);
110.       Serial.print("motor2newSpeed: ");
111.       Serial.println(motor2newSpeed);
112.       //delay(100);
113.   }
```

Buổi chiều

Ngày 9 tháng 6 năm 2023

Buổi sáng

Buổi chiều