

UNIVERSITY OF MUMBAI
DEPARTMENT OF COMPUTER SCIENCE



M.Sc. Computer Science – Semester IV
Robotics
JOURNAL
2023-2024

Seat No: _____



UNIVERSITY OF MUMBAI
DEPARTMENT OF COMPUTER SCIENCE

CERTIFICATE

This is to certify that the work entered in this journal was done in the University Department of Computer Science laboratory by Mr/Mrs. _____ Seat No. _____ for the course of M.Sc. Computer Science - Semester IV (CBCS) (Revised) during the academic year 2023- 2024 in a satisfactory manner.

Subject In-charge

Head of Department

External Examiner

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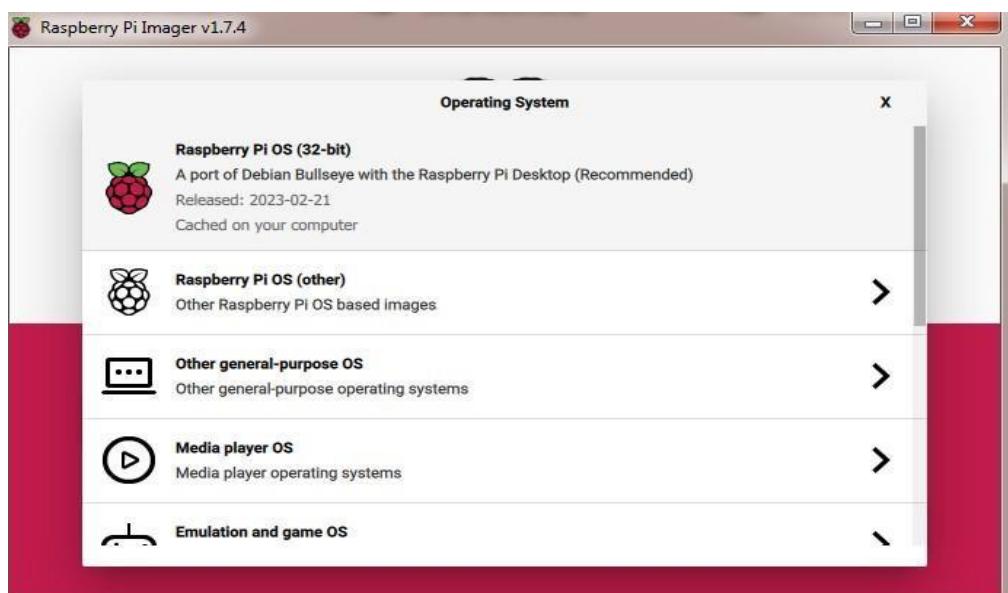
Practical No. 01

Aim: Making Raspberry pi headless, and reaching it from the network using wifi and SSH.

STEP I : Download raspberry pi imager for windows. And connect sd card to laptop.



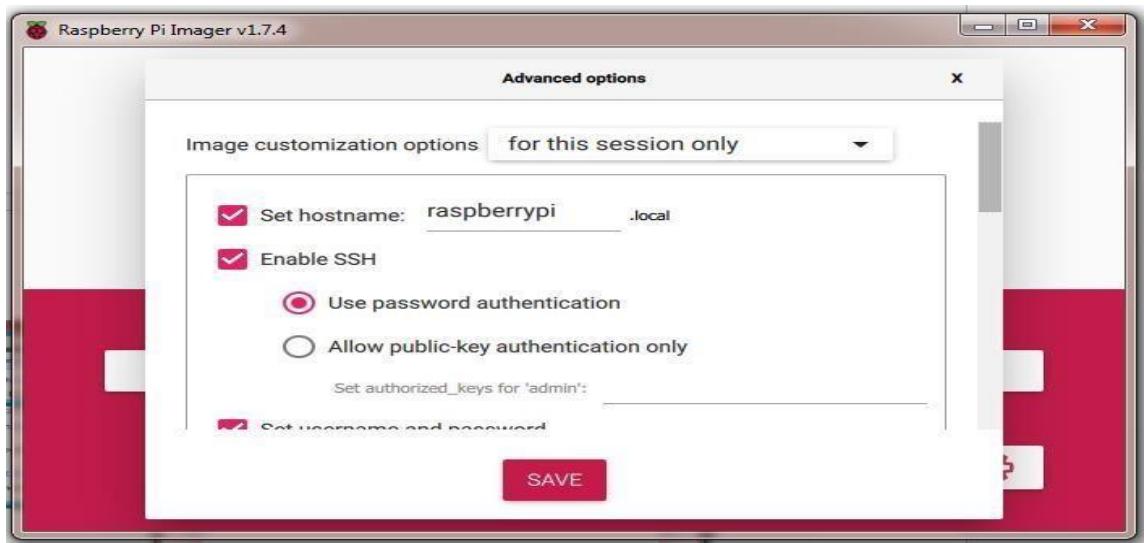
STEP II : Select operating sysyem (raspberry pi OS 32-bit)



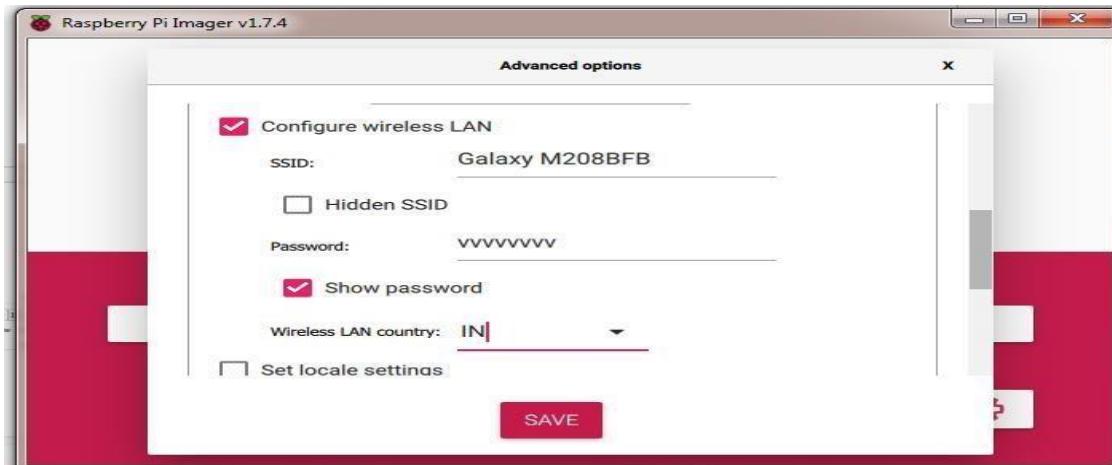
STEP III : Select Storage.



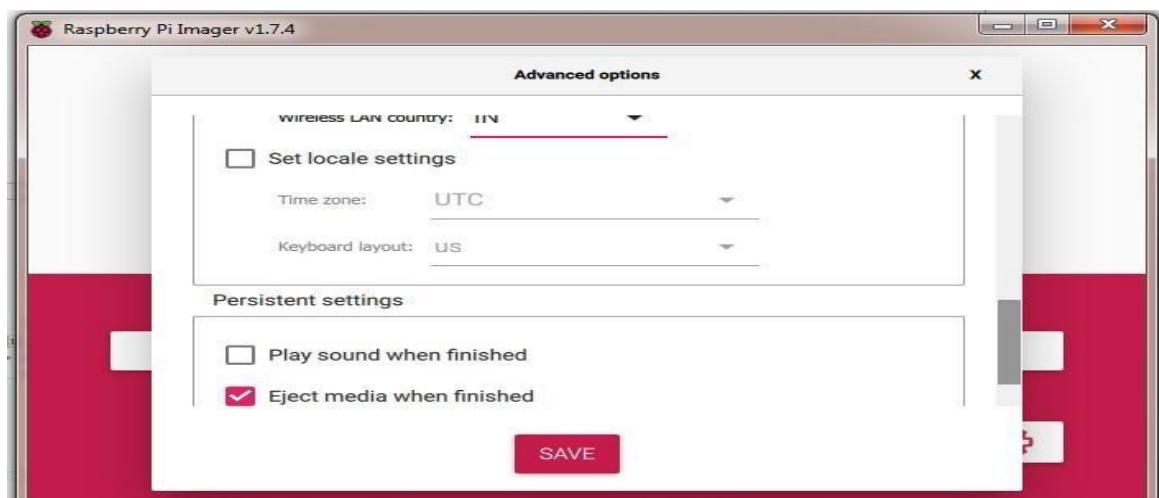
STEP IV : Click on Setting Icon . and set hostname. Click to enable SSH.



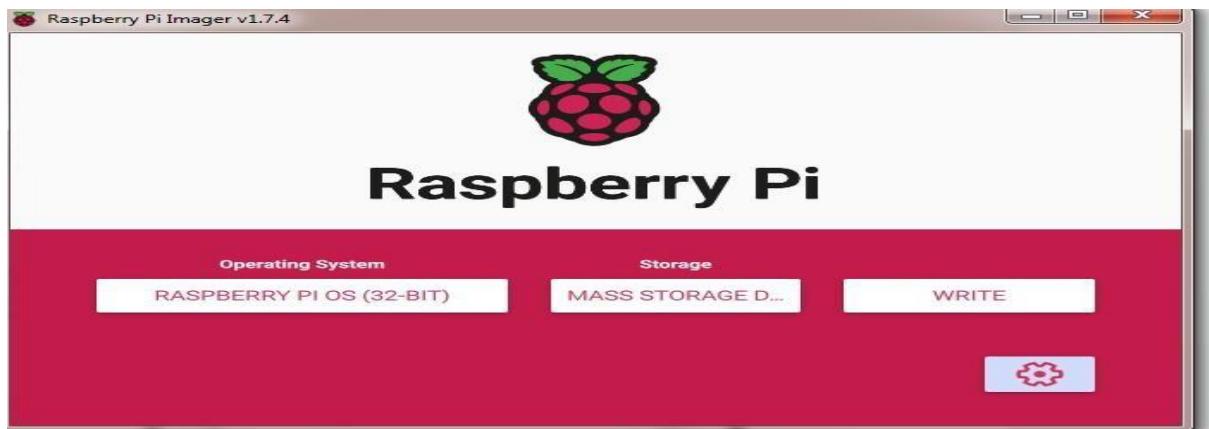
STEP V : Click to configure wireless LAN. And select country.



STEP VI : Click to save.



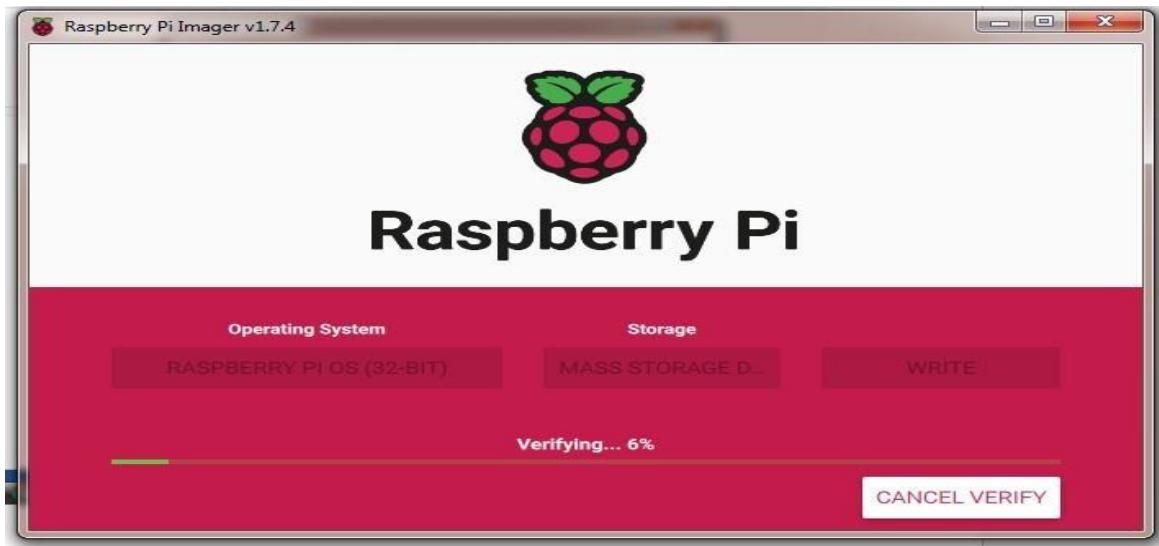
STEP VII : Click on write.



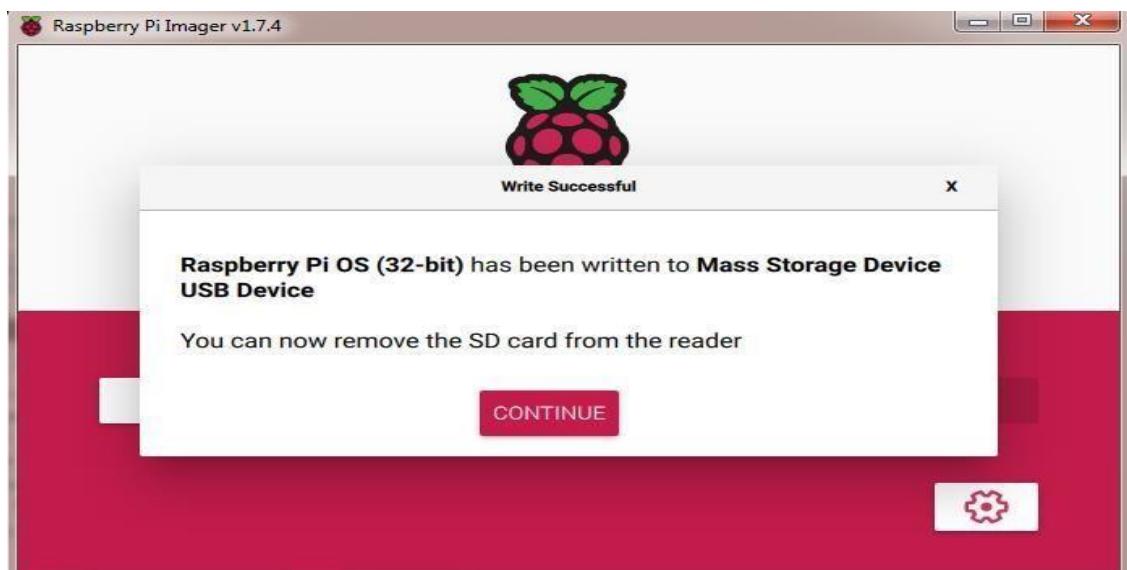
STEP VIII : Click on yes.



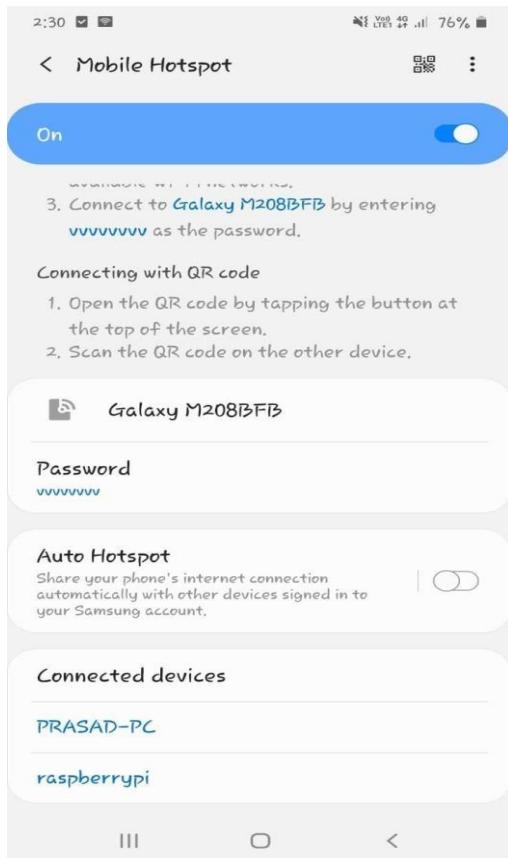
STEP IX : Verifying raspberry pi .



STEP X : Click on continue .



Step XI : check the connection in your mobile hotspot of raspberrypi



STEP X: On cmdprompt execute these command :

1.ping raspberrypi

2.ssh admin@raspberrypi

```
admin@raspberrypi: ~
Microsoft Windows [Version 10.0.19044.1889]
(c) Microsoft Corporation. All rights reserved.

C:\Users\Admin>ping raspberrypi

Pinging raspberrypi.local [2409:40c2:2a:1473:e49d:39f2:eea5:8b9d] with 32 bytes of data:
Reply from 2409:40c2:2a:1473:e49d:39f2:eea5:8b9d: time=15ms
Reply from 2409:40c2:2a:1473:e49d:39f2:eea5:8b9d: time=4ms
Reply from 2409:40c2:2a:1473:e49d:39f2:eea5:8b9d: time=4ms
Reply from 2409:40c2:2a:1473:e49d:39f2:eea5:8b9d: time=11ms

Ping statistics for 2409:40c2:2a:1473:e49d:39f2:eea5:8b9d:
    Packets: Sent = 4, Received = 4, Lost = 0 (0% loss),
    Approximate round trip times in milli-seconds:
        Minimum = 4ms, Maximum = 15ms, Average = 8ms

C:\Users\Admin>ssh admin@raspberrypi
admin@raspberrypi's password:
Linux raspberrypi 5.15.84-v7+ #1613 SMP Thu Jan 5 11:59:48 GMT 2023 armv7l

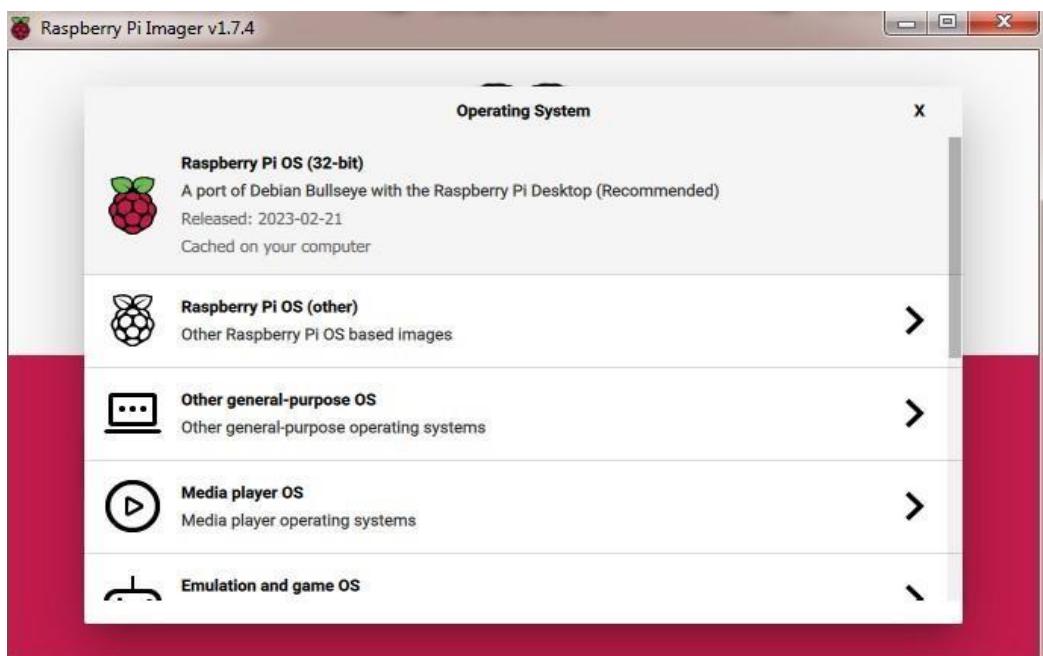
The programs included with the Debian GNU/Linux system are free software;
the exact distribution terms for each program are described in the
individual files in /usr/share/doc/*copyright.

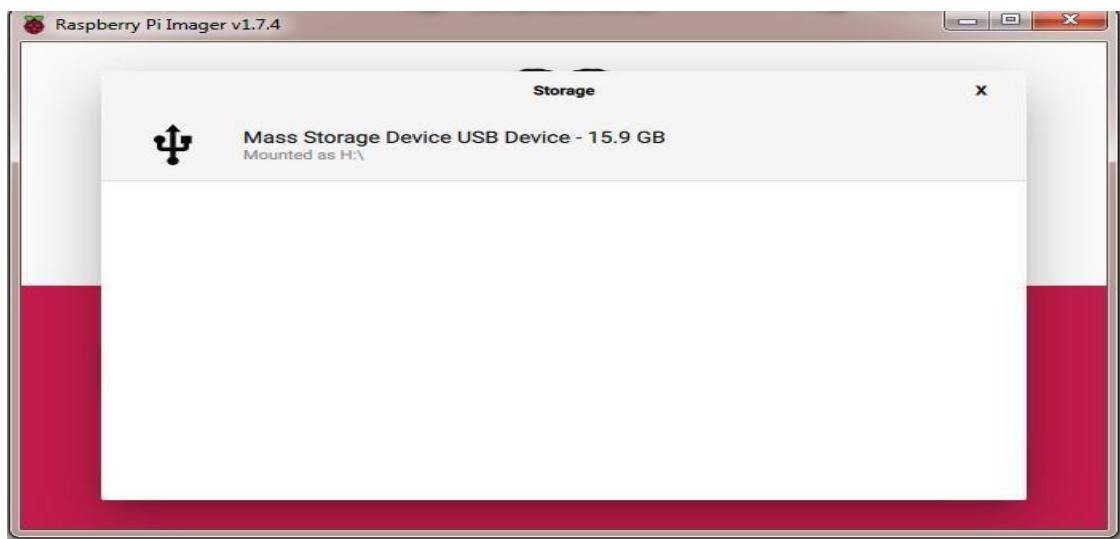
Debian GNU/Linux comes with ABSOLUTELY NO WARRANTY, to the extent
permitted by applicable law.
Last login: Tue Apr 18 09:40:59 2023
admin@raspberrypi:~ $
```

Practical No 2

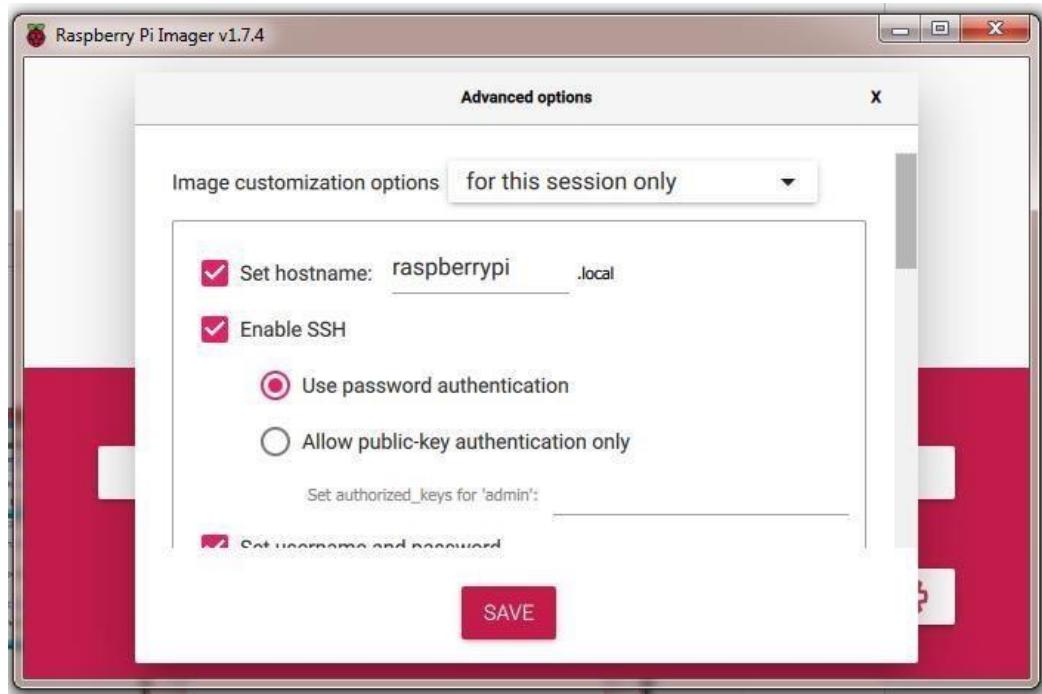
Aim: Using sftp upload files from PC.

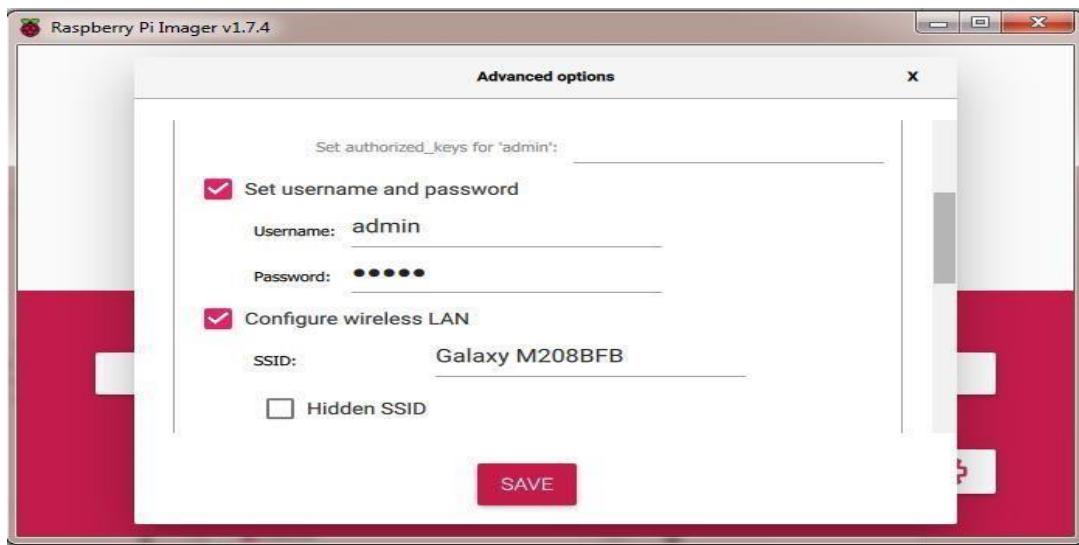
Step 1: Intsall the Raspberry Pi Imager



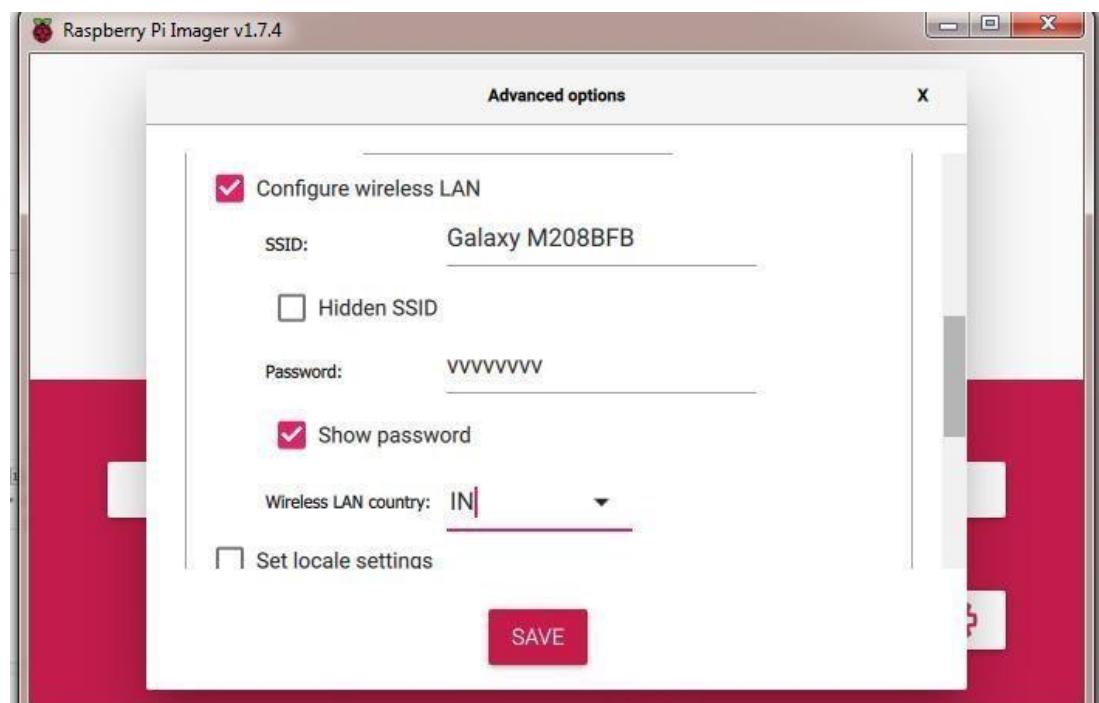


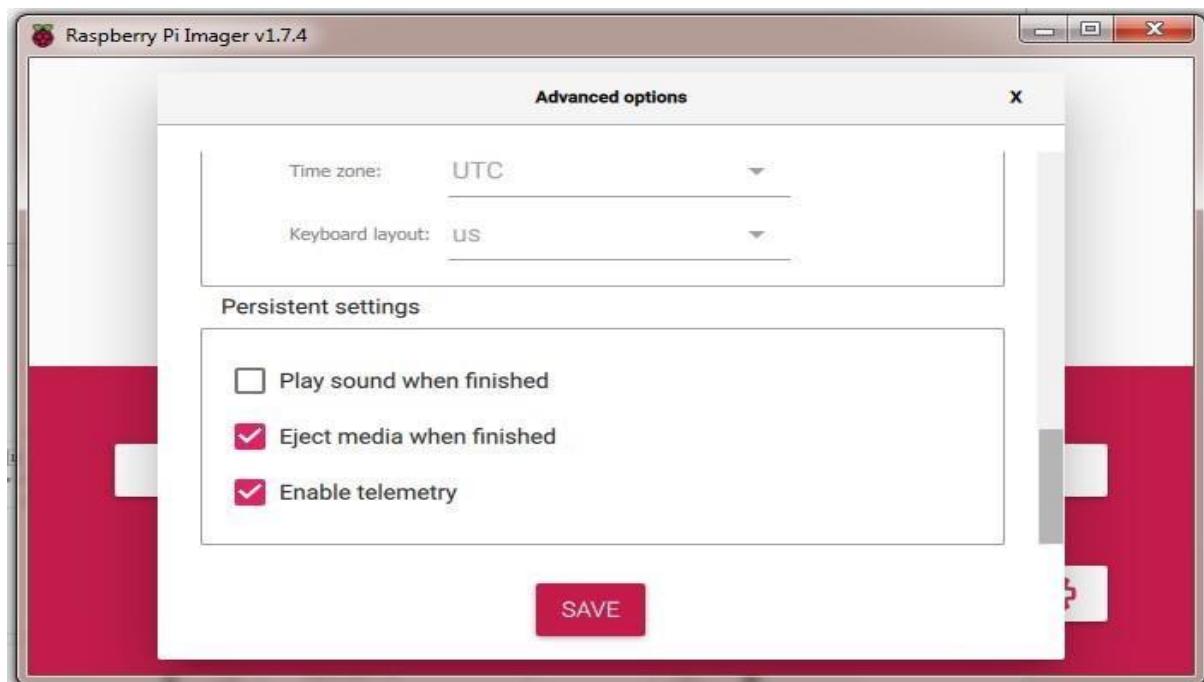
Step 2: Set Host Name , enable SSH, Set Username and Password.

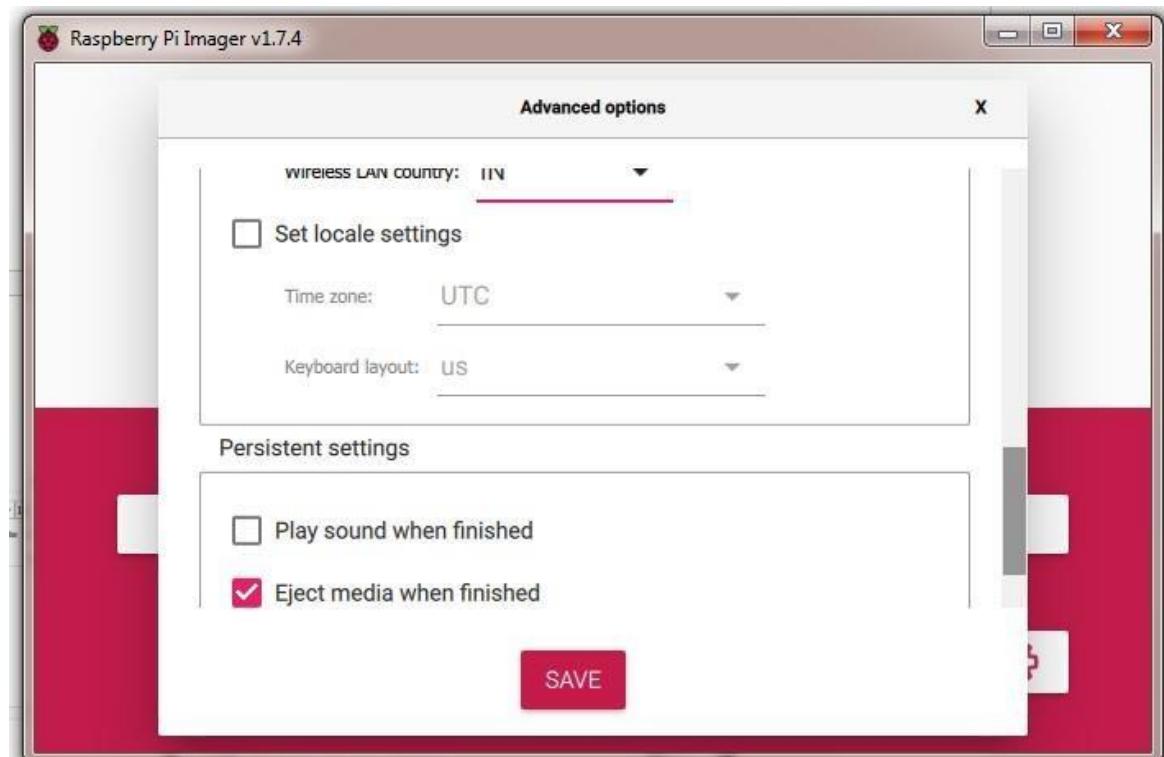


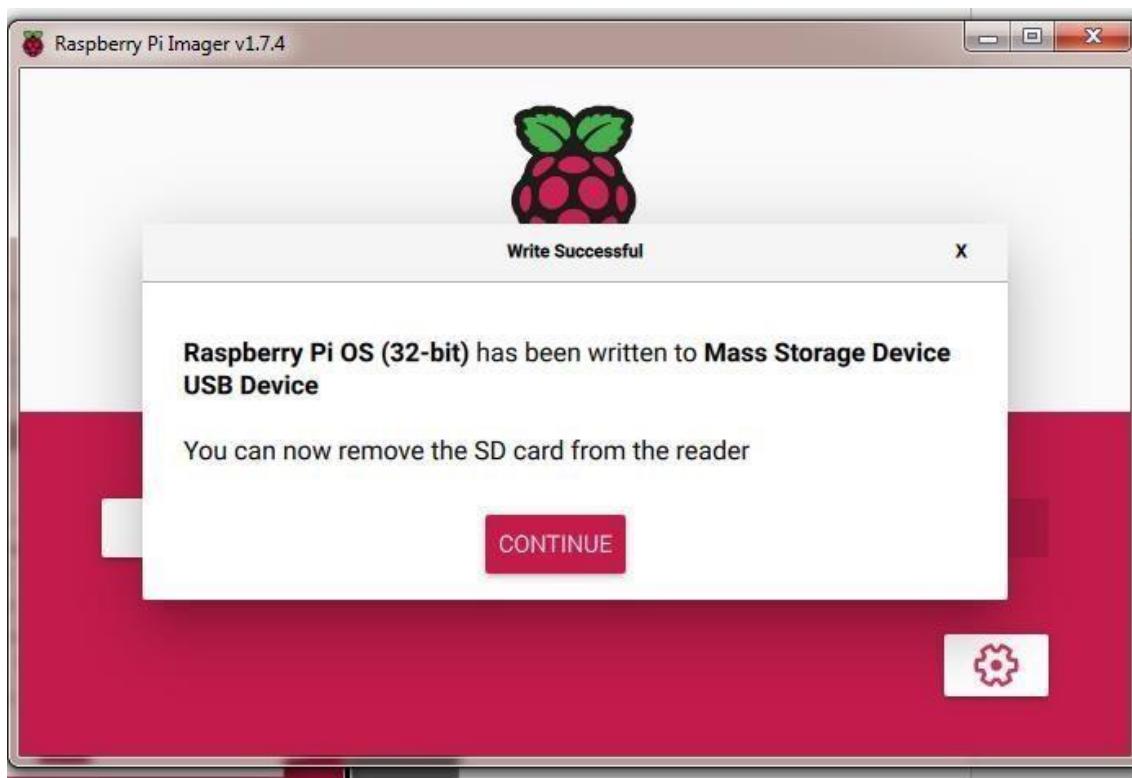


Step 3: Set SSID and Password of hotspot which is used .

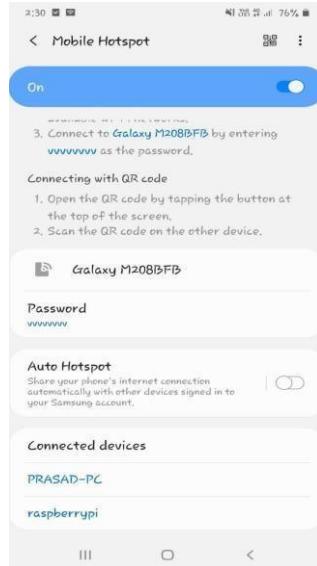








Step 4: Connect Raspberry Pi WIFI and Laptop WIFI to Mobile Device.



Step 5: Open CMD and type following command
ping raspberrypi or ping 162.168.207.244
ssh admin@ raspberrypi or ssh admin@
162.168.207.244 And type password of Admin

```

admin@raspberrypi: ~
Request timed out.

Ping statistics for 192.168.207.244:
  Packets: Sent = 4, Received = 0, Lost = 4 (100% loss),
C:\Users\Admin>ping 192.168.207.244

Pinging 192.168.207.244 with 32 bytes of data:
Reply from 192.168.207.244: bytes=32 time=21ms TTL=64
Reply from 192.168.207.244: bytes=32 time=11ms TTL=64
Reply from 192.168.207.244: bytes=32 time=9ms TTL=64
Reply from 192.168.207.244: bytes=32 time=10ms TTL=64

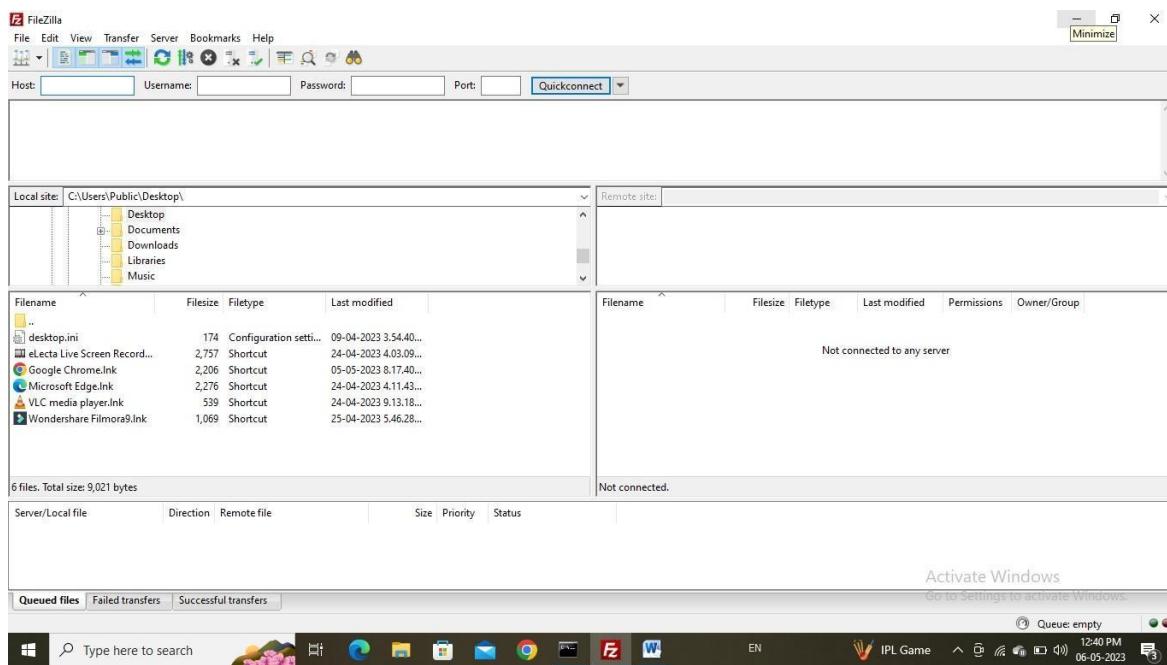
Ping statistics for 192.168.207.244:
  Packets: Sent = 4, Received = 4, Lost = 0 (0% loss),
Approximate round trip times in milli-seconds:
  Minimum = 9ms, Maximum = 21ms, Average = 12ms

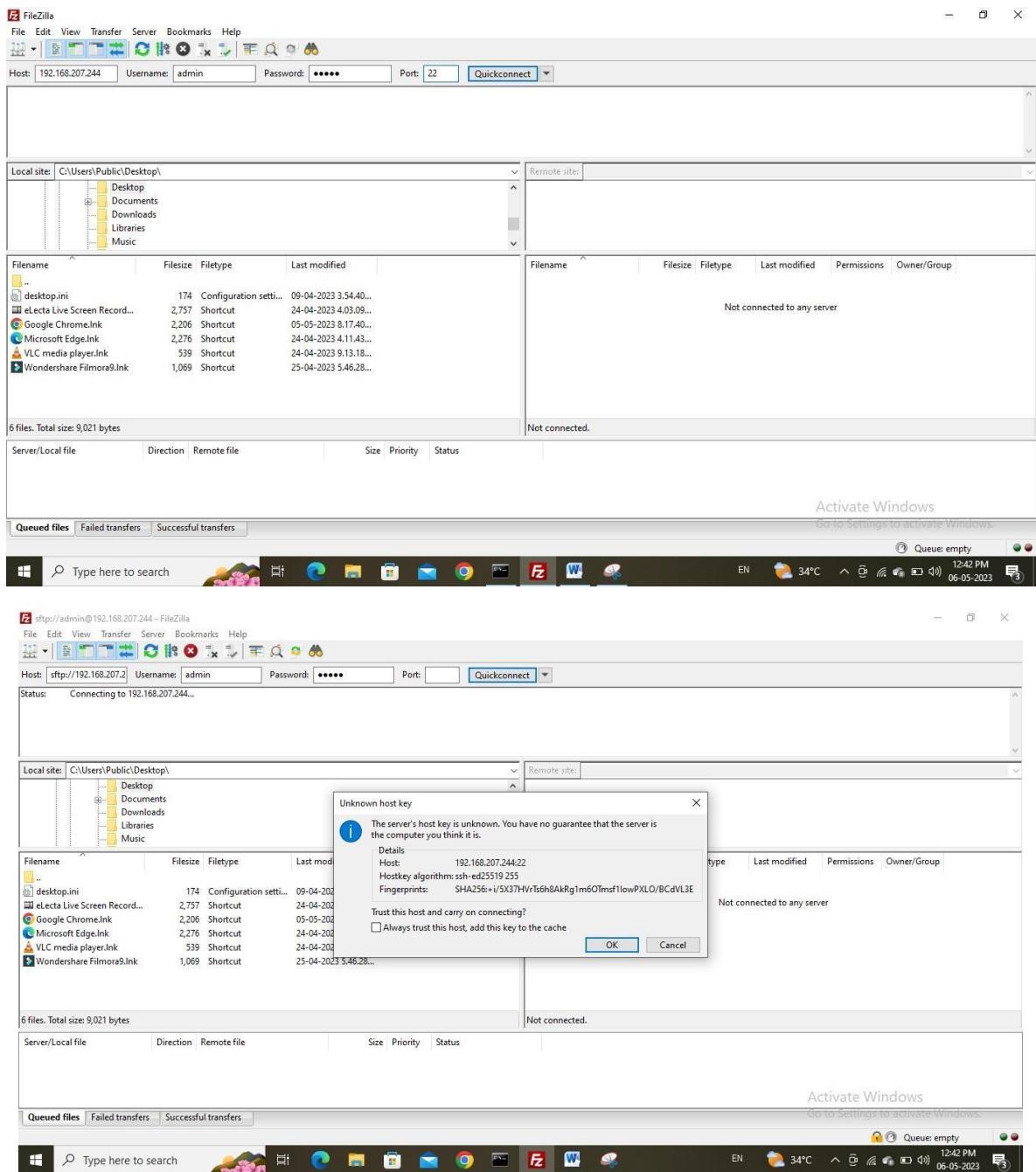
C:\Users\Admin>ssh admin@192.168.207.244
The authenticity of host '192.168.207.244 (192.168.207.244)' can't be established.
ECDSA key fingerprint is SHA256:qLw2aLXcb81PnFDfJMhtKANxs5KbGF1/X9PLVq5/Hb0.
Are you sure you want to continue connecting (yes/no/[fingerprint])? yes
Warning: Permanently added '192.168.207.244' (ECDSA) to the list of known hosts.
admin@192.168.207.244's password:
Linux raspberrypi 6.1.21-v7+ #1642 SMP Mon Apr 3 17:20:52 BST 2023 armv7l

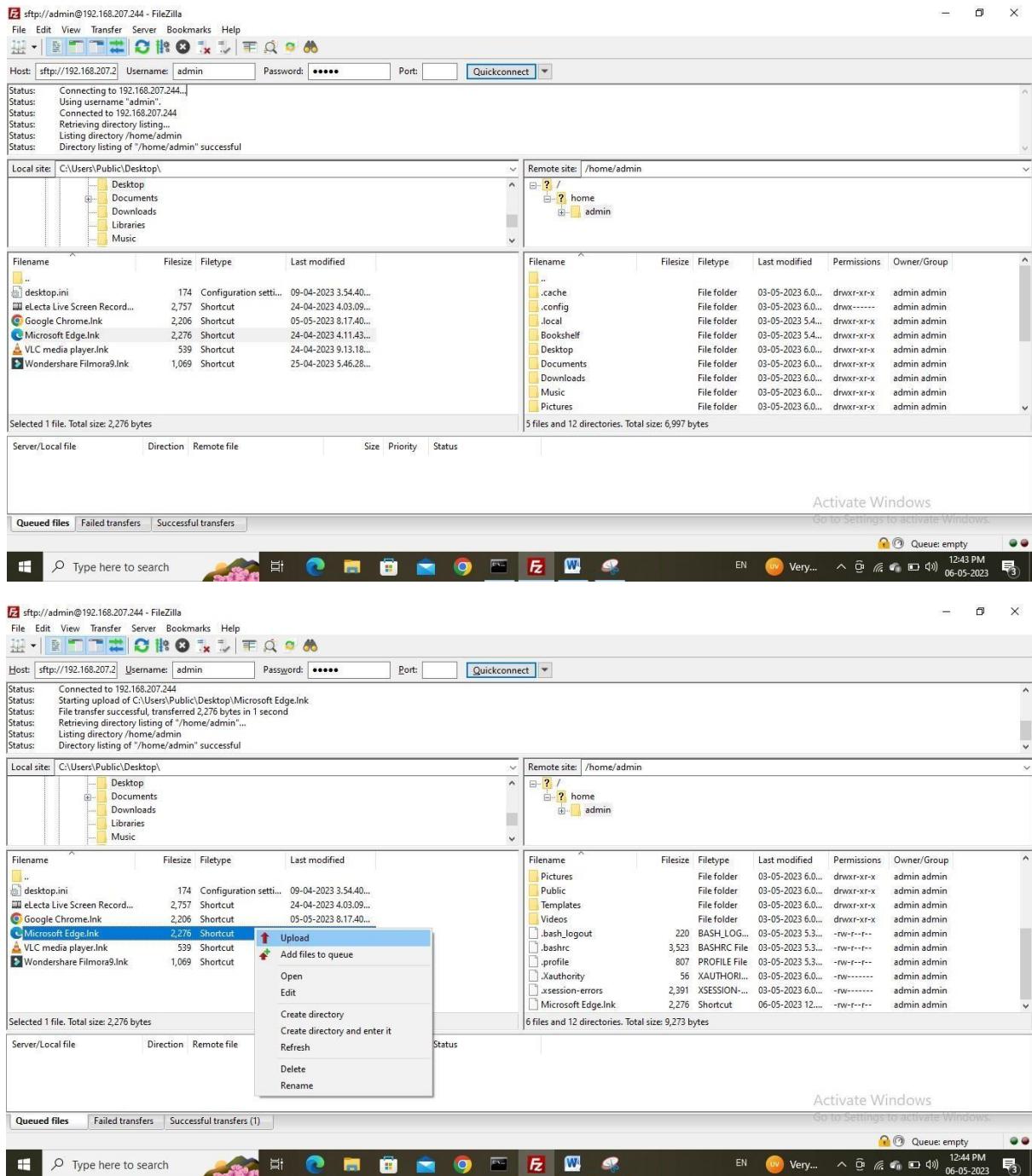
The programs included with the Debian GNU/Linux system are free software;
the exact distribution terms for each program are described in the
individual files in /usr/share/doc/*copyright.

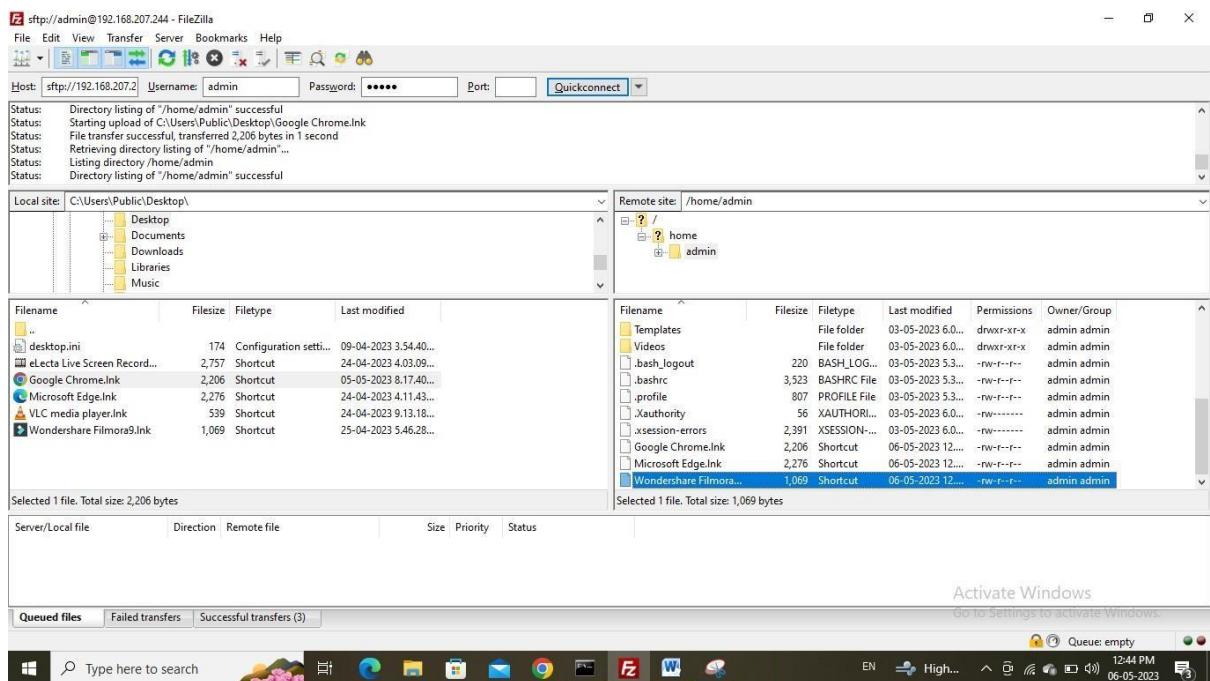
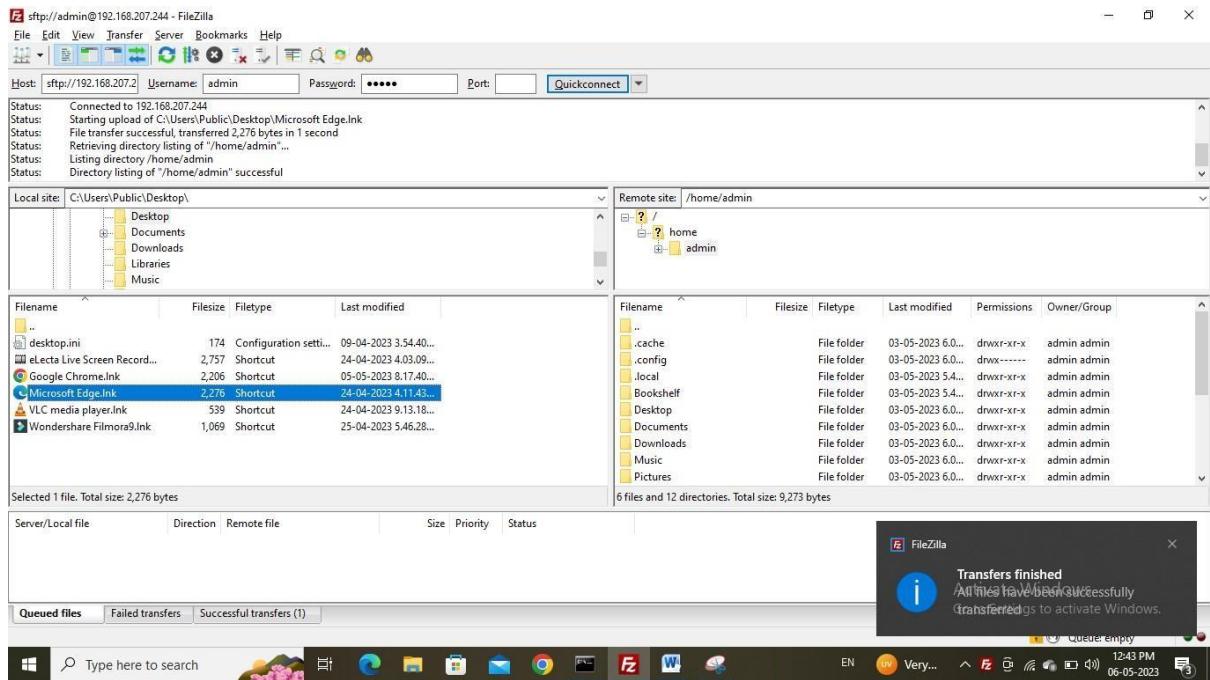
Debian GNU/Linux comes with ABSOLUTELY NO WARRANTY, to the extent
permitted by applicable law.
Last login: Wed May 3 06:07:06 2023
admin@raspberrypi:~ $
```

Step:6 Download the FileZilla (Client)







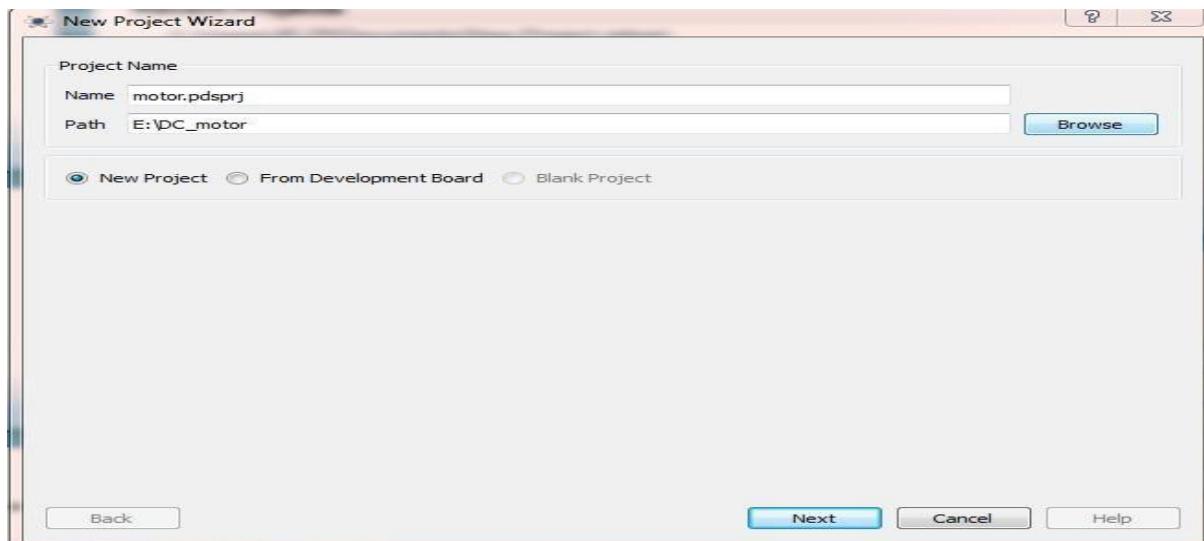


Practical No: 03

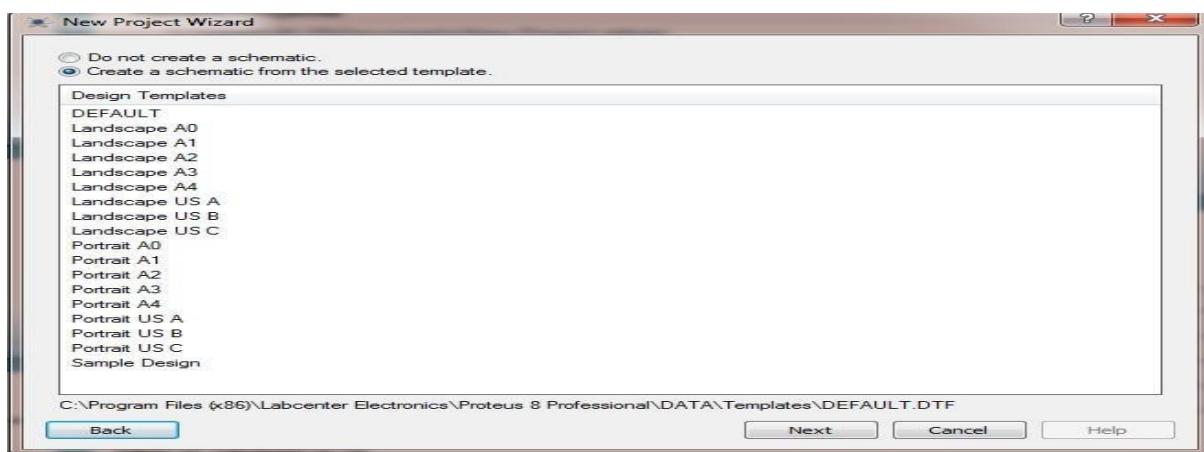
Aim: Write python code to test Motors.

OUTPUT:

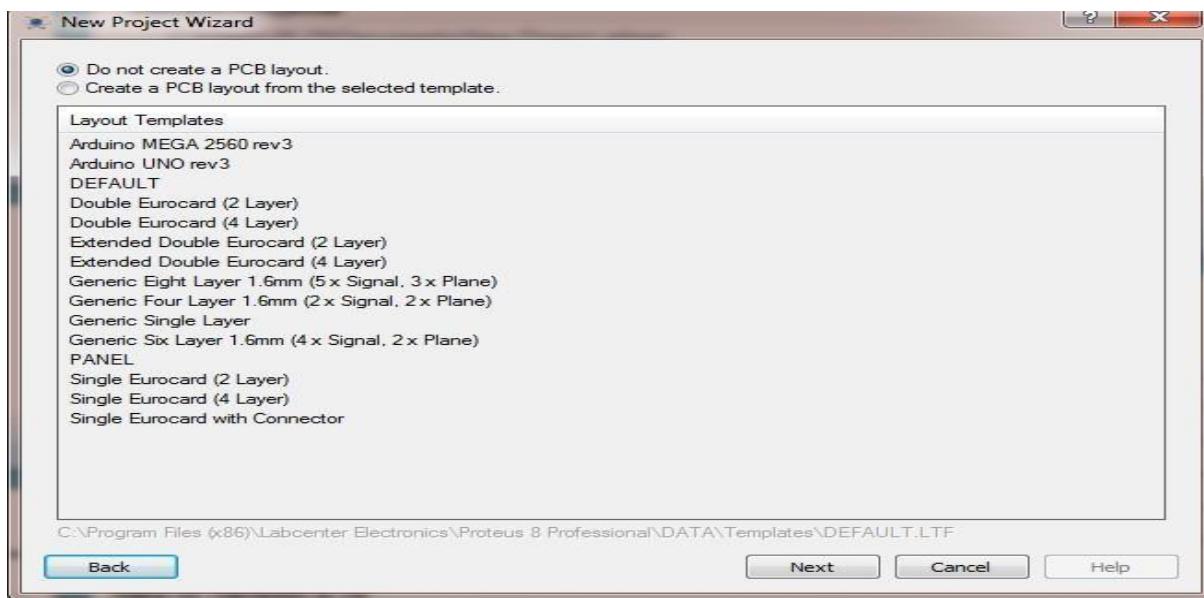
Give project name.



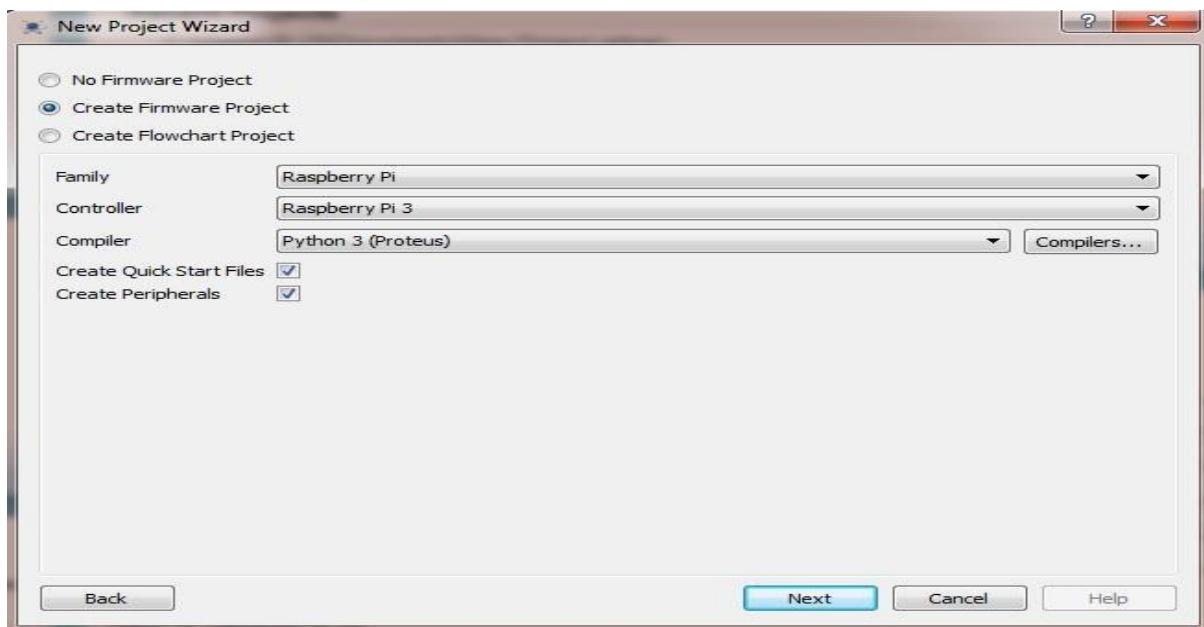
Select “create a schematic from the selected template”.



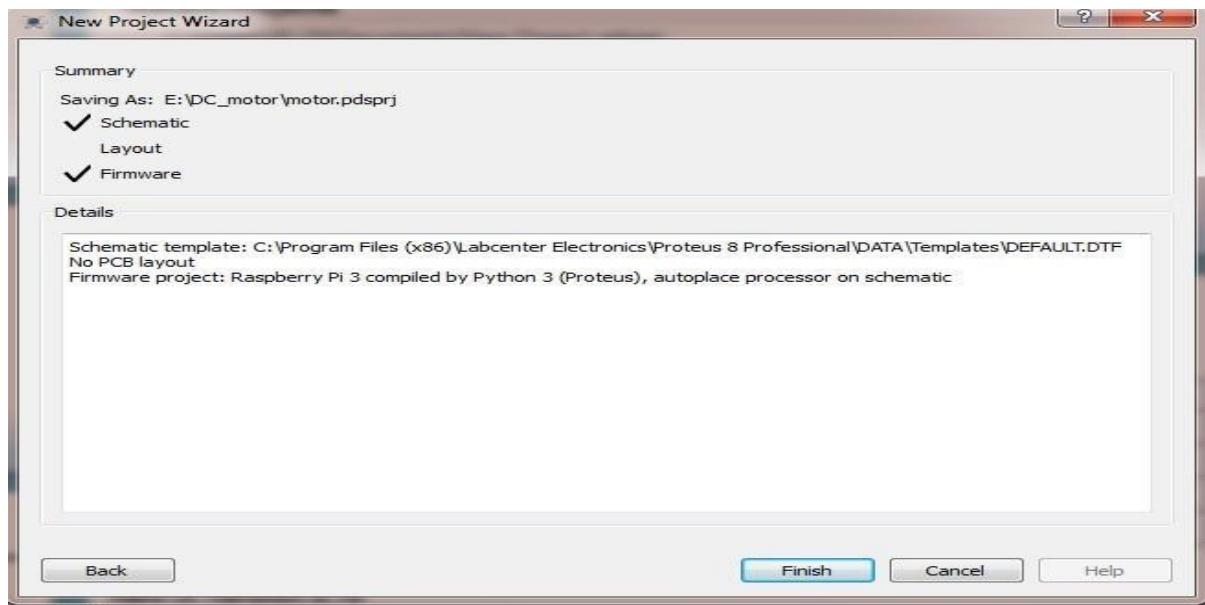
Select “Do not create a PCB layout”



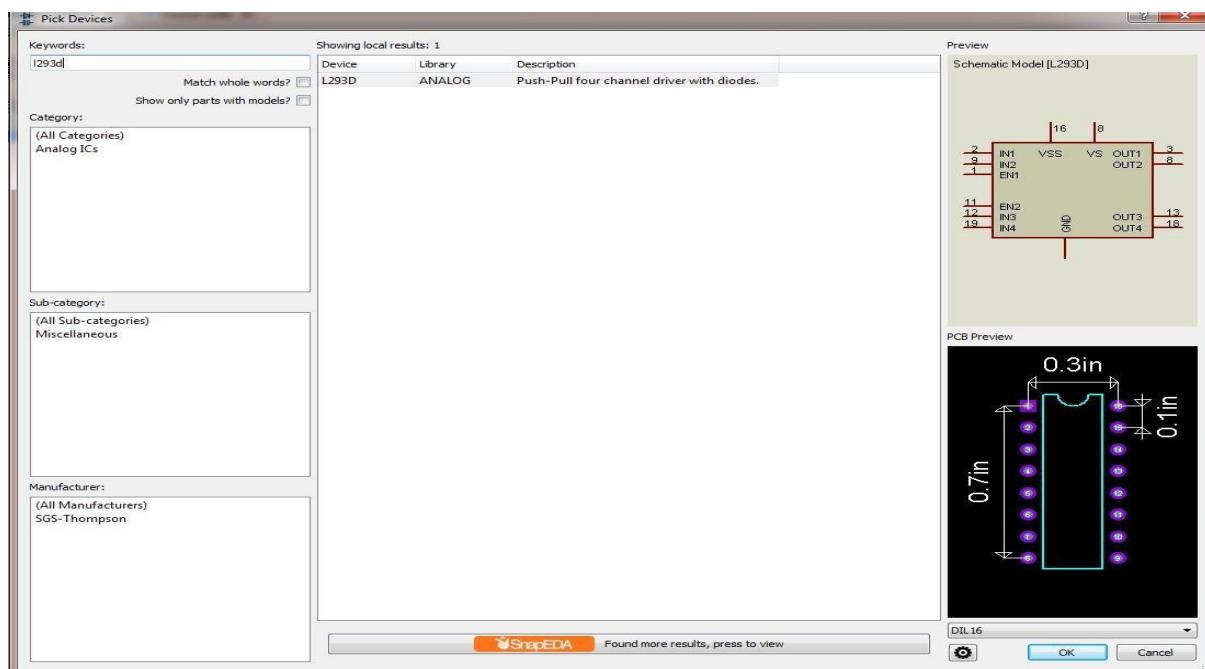
Select “Create firmware project”. and create firmware project in proteus and select Raspberry pi Family.



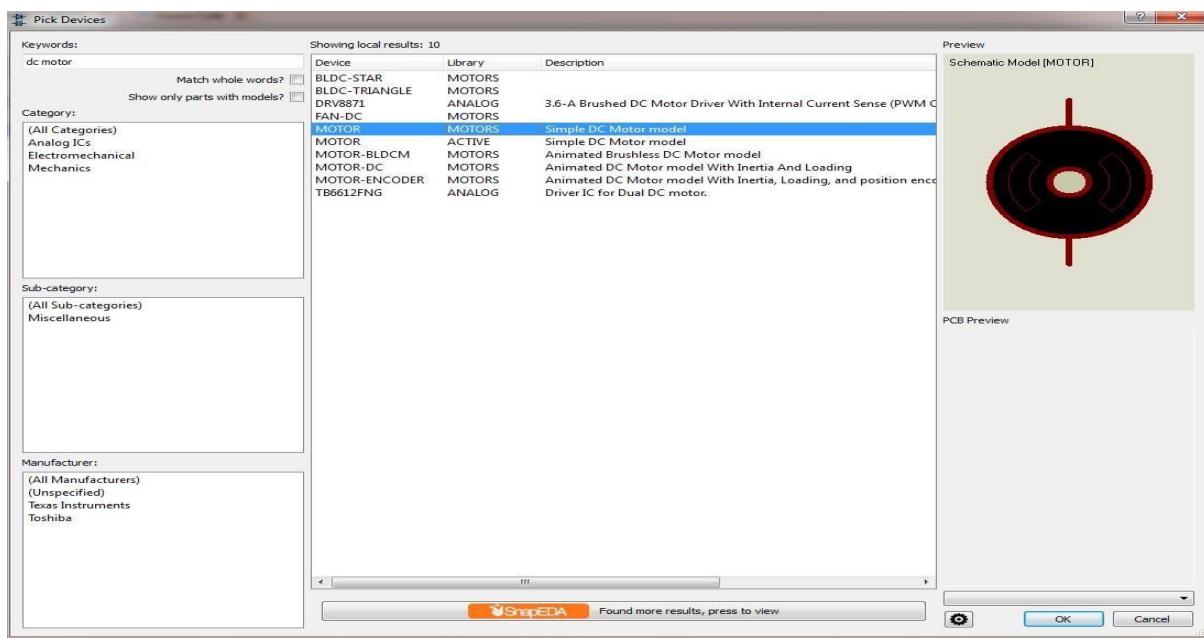
Click on Finish.



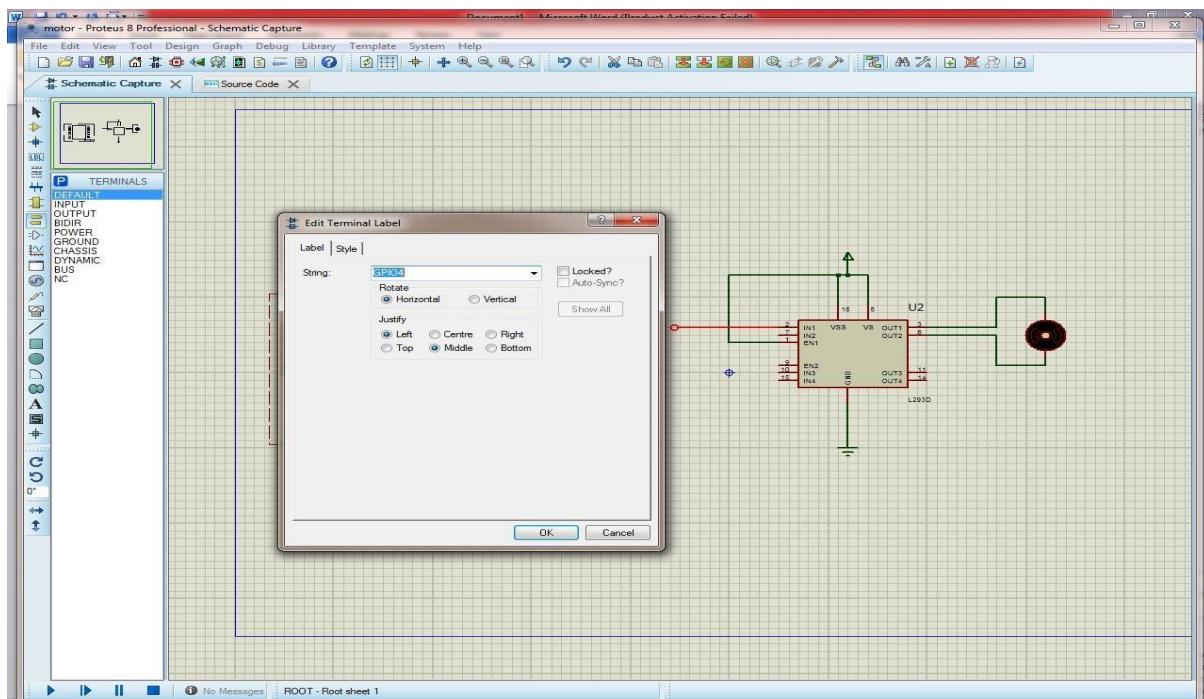
Go to the library>pick devices>L293D



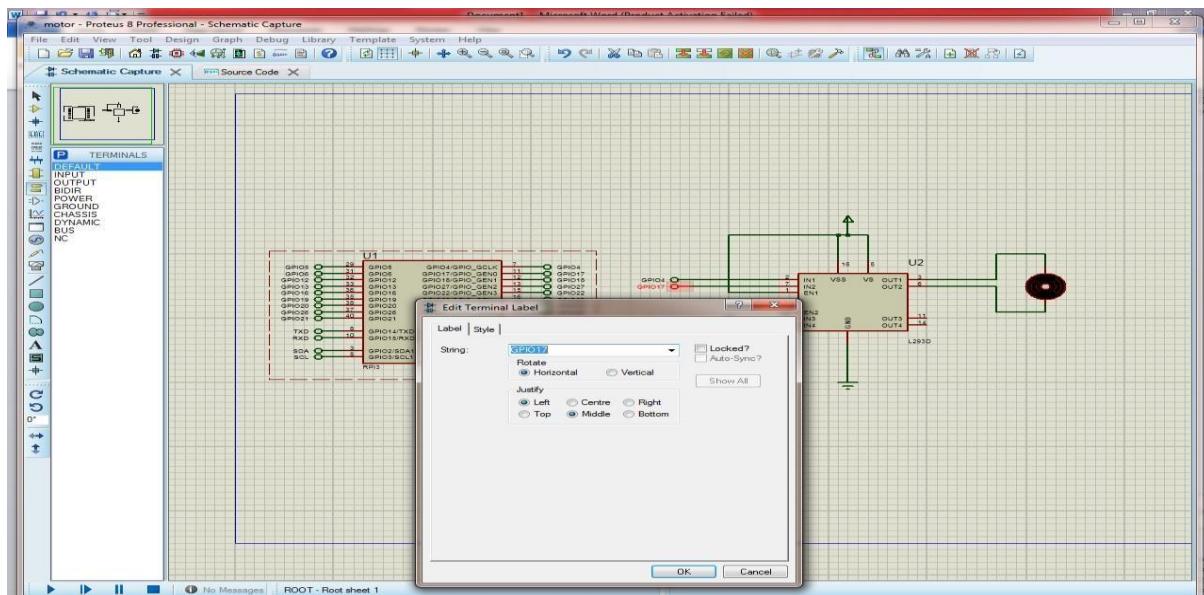
Select MOTOR



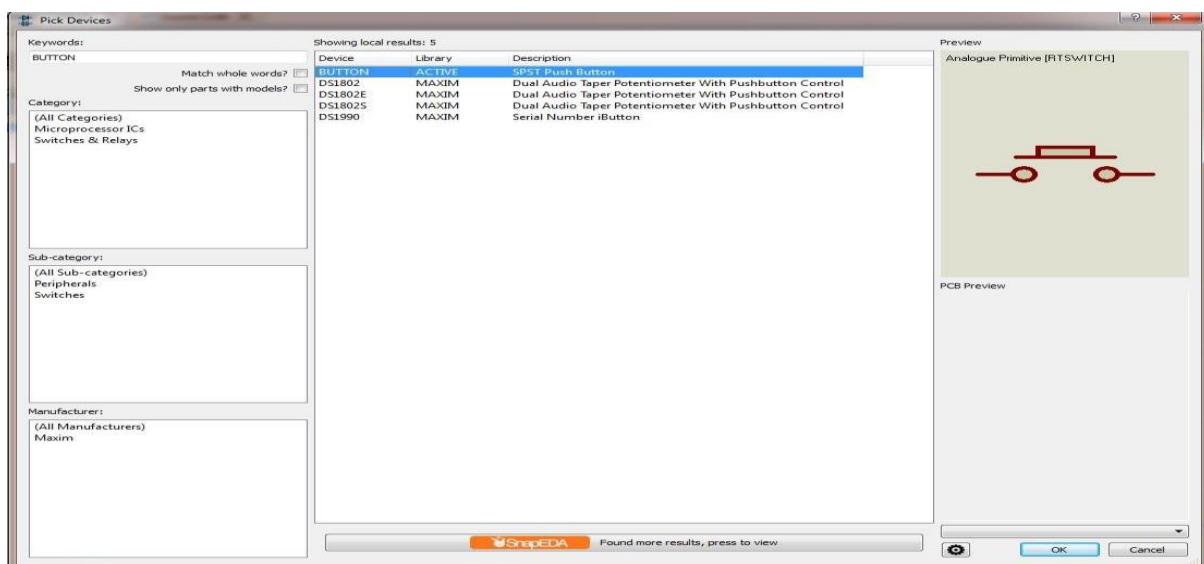
Edit terminal label as GPIO4



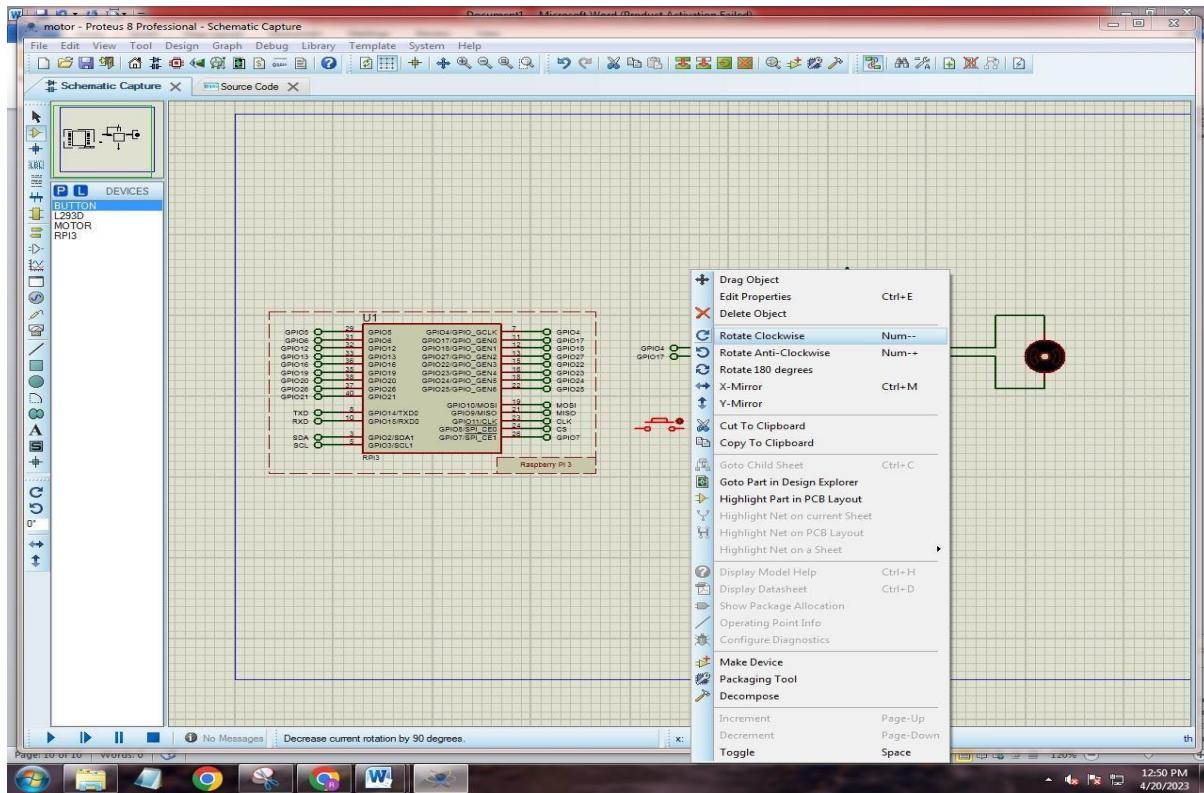
Edit terminal label as GPIO17



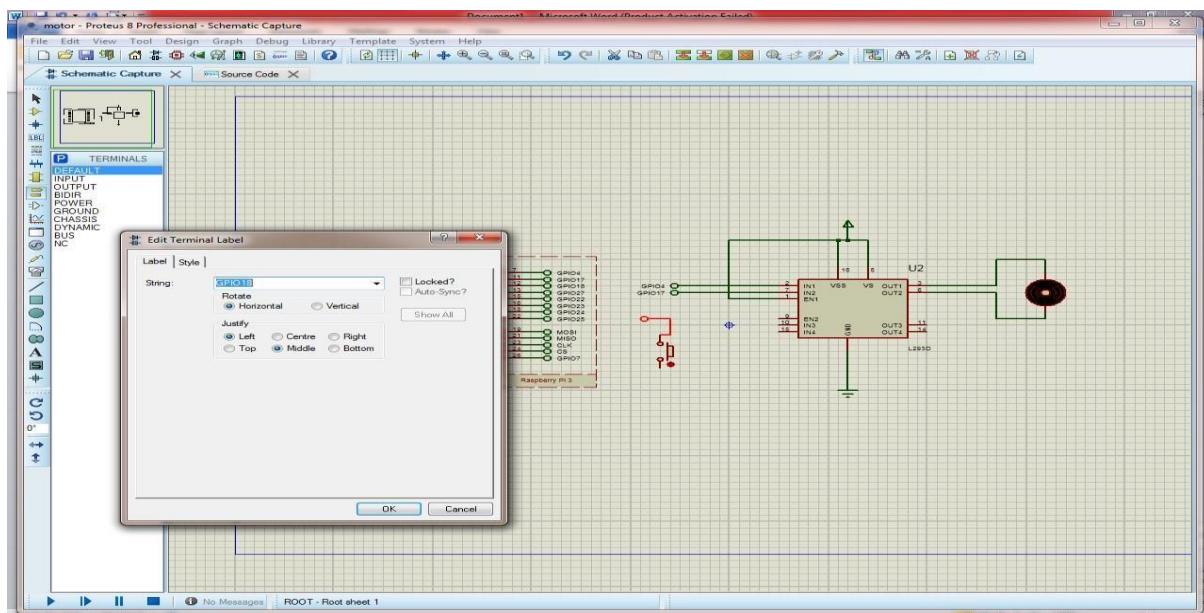
Select BUTTON



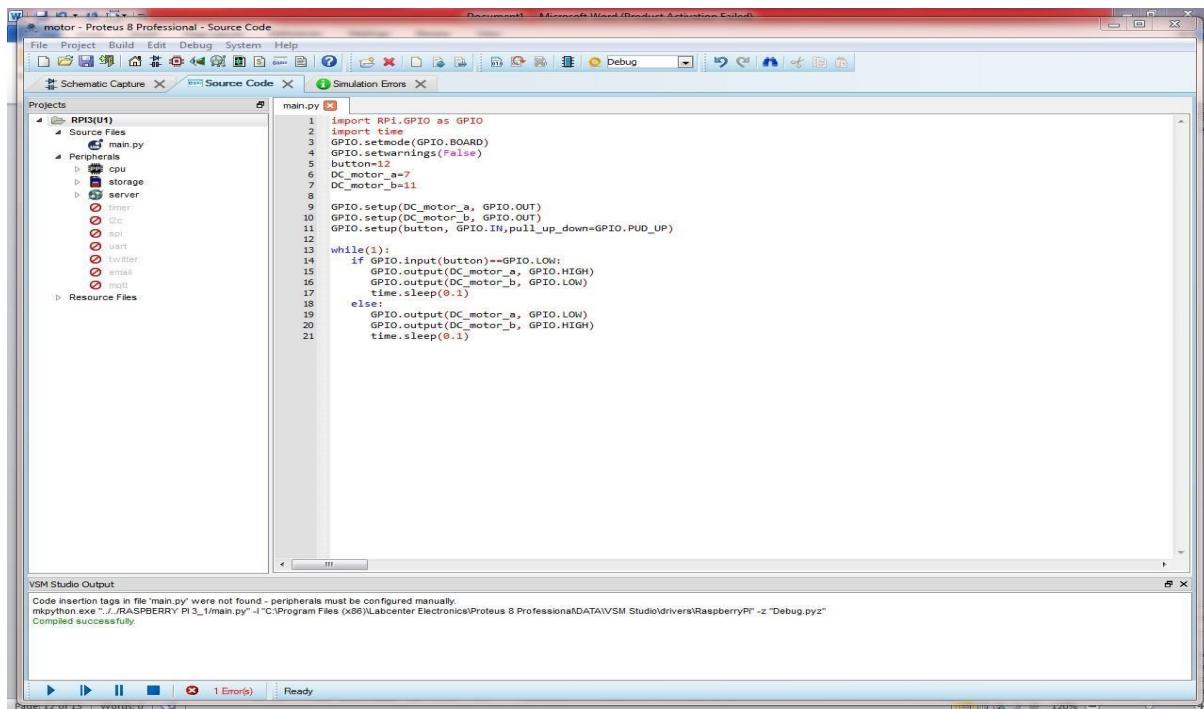
Rotate button in clockwise



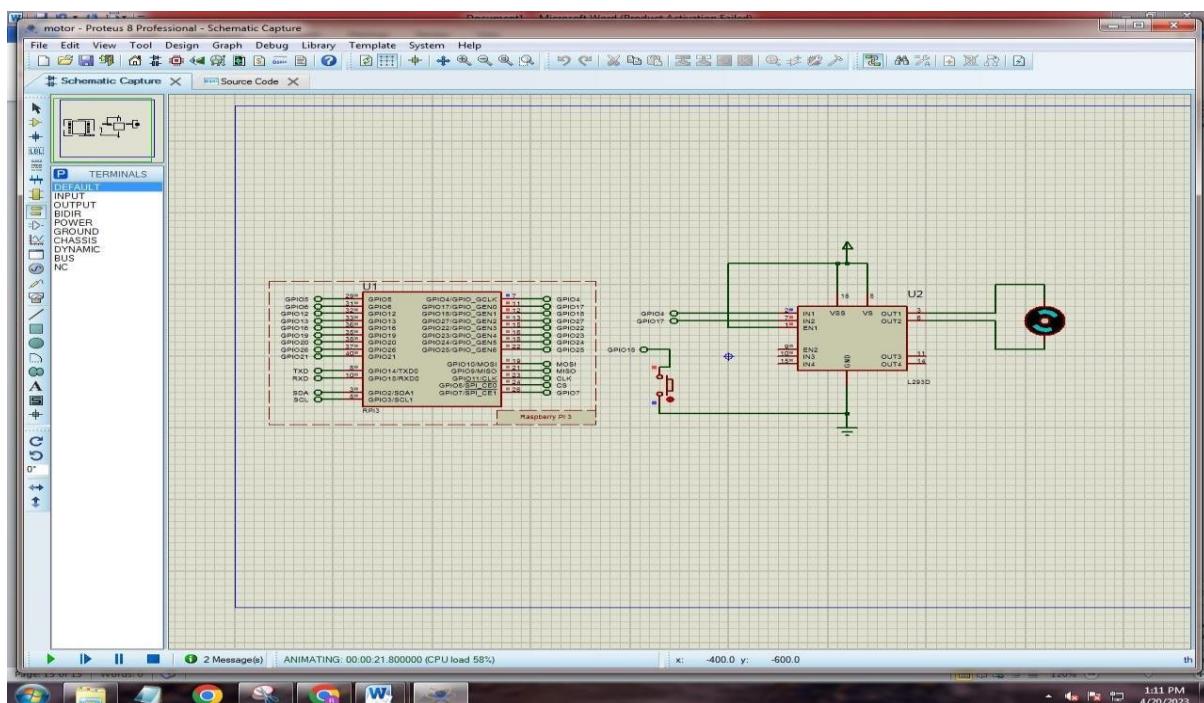
Edit terminal label as GPIO18

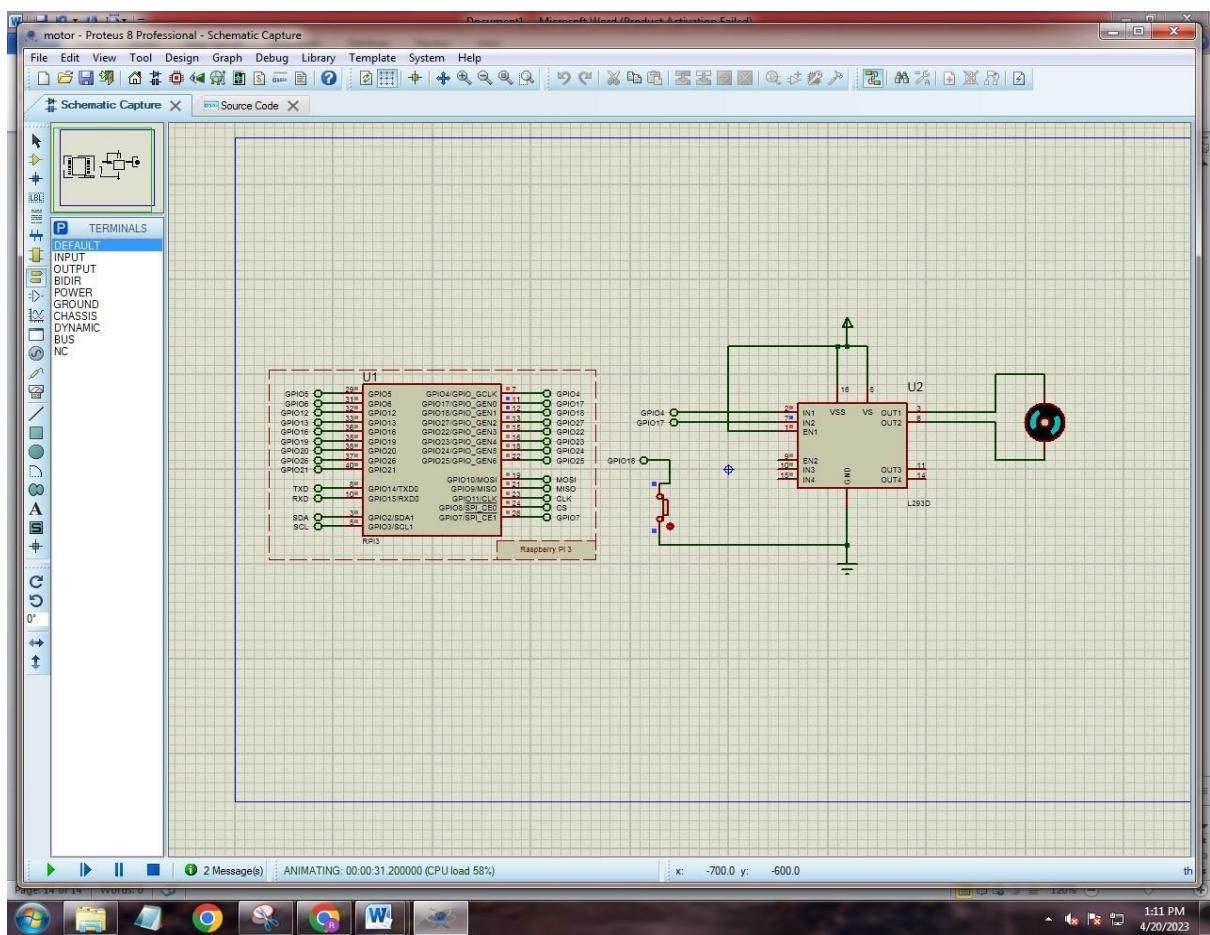


Type code in proteus source code page



Start Simulation.





Practical No.4

Aim: Develop Python code for testing the sensors.

Step 1: Place the following component in TinkerCard.

Components:

- PIR Sensor
- Resistor
- Piezo
- Arduino Uno R3
- LED RGB

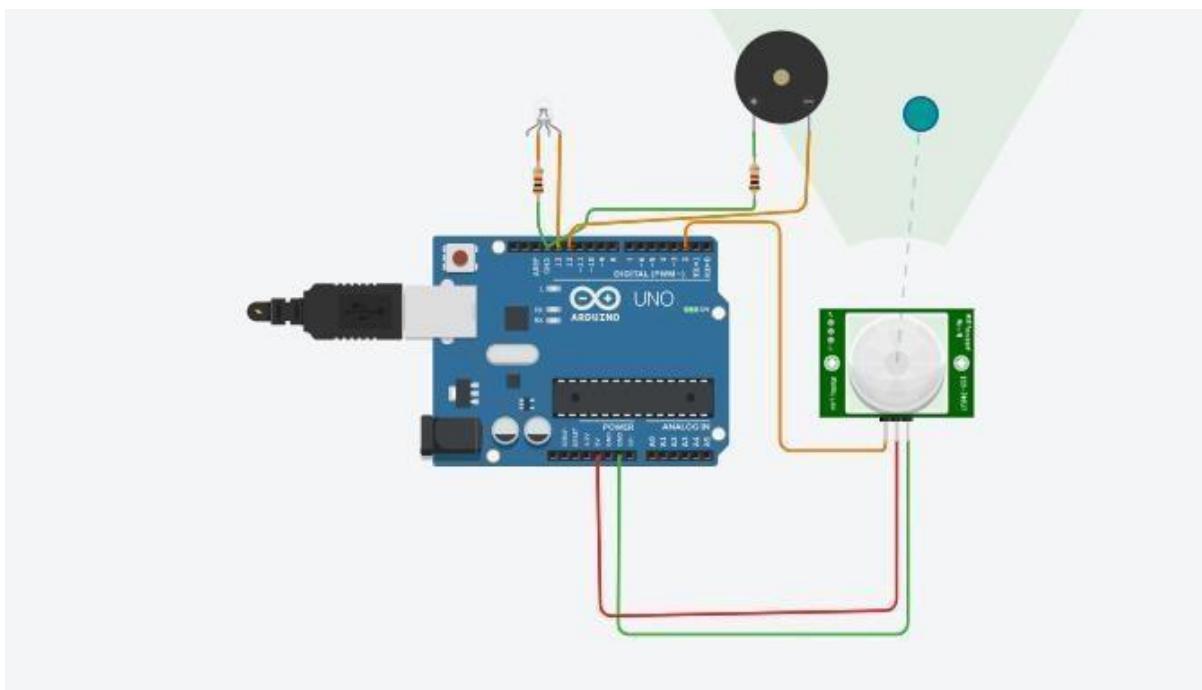
Step 2: Type the following code int pirsensor = 0; void setup()

```

    {
        pinMode(2, INPUT);  pinMode(12,
        OUTPUT);  pinMode(13, OUTPUT);
    }  void loop() {  pirsensor = digitalRead(2);  if (pirsensor
        == HIGH)
    {
        digitalWrite(13,HIGH);  tone(12,500,500);
    }
    digitalWrite(13,LOW)
}

```

OUTPUT:



Practical No: 5

Aim:- Add the sensors to the Robot object and develop the line-following behavior code.

Step 1: Download the following libraries

L298 Motor Driver Library for Proteus

Arduino UNO Library for Proteus V2.0

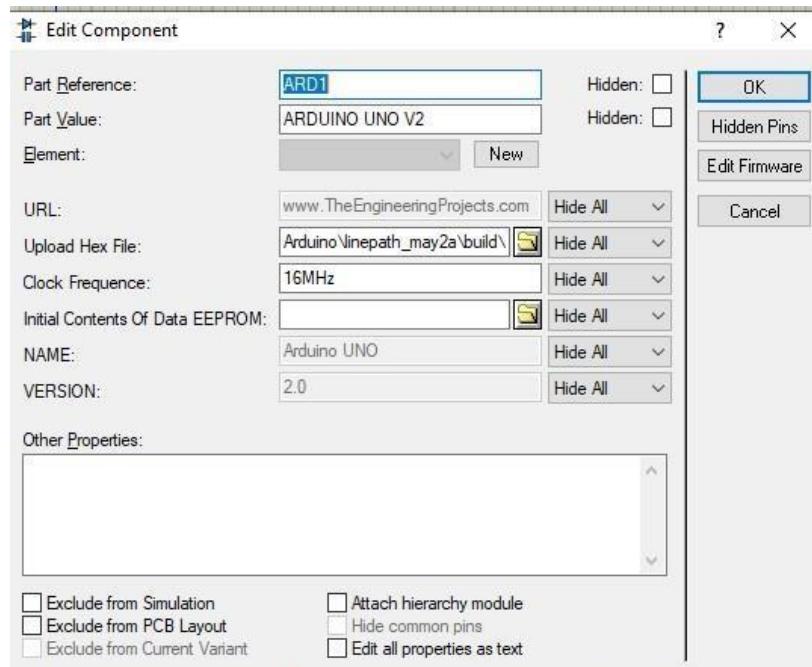
Infrared Sensor Library for Proteus

Step 2: Extract this files and pest it in Proteus libraries folder and restart the Proteus .

Step 3: Download the Proteus IDE and type the following code after that save it and Export Complied

Library

Step 4: Upload this HEX file in Arduino



```

Code: void setup()
{
pinMode(2,INPUT); pinMode(3,INPUT);
pinMode(10,OUTPUT); pinMode(11,OUTPUT);

pinMode(12,OUTPUT); pinMode(13,OUTPUT);

}

void loop(){
int v=digitalRead(2); int
s=digitalRead(3);

if(v==1 and s==1){

digitalWrite(13,1); digitalWrite(12,0); digitalWrite(11,1);
digitalWrite(10,0);

}

if(v==1 and s==0){

digitalWrite(13,0); digitalWrite(12,1);
digitalWrite(11,0); digitalWrite(10,1); }

if(v==0 and s==1){

digitalWrite(13,1); digitalWrite(12,0); digitalWrite(11,0);
digitalWrite(10,1);

}

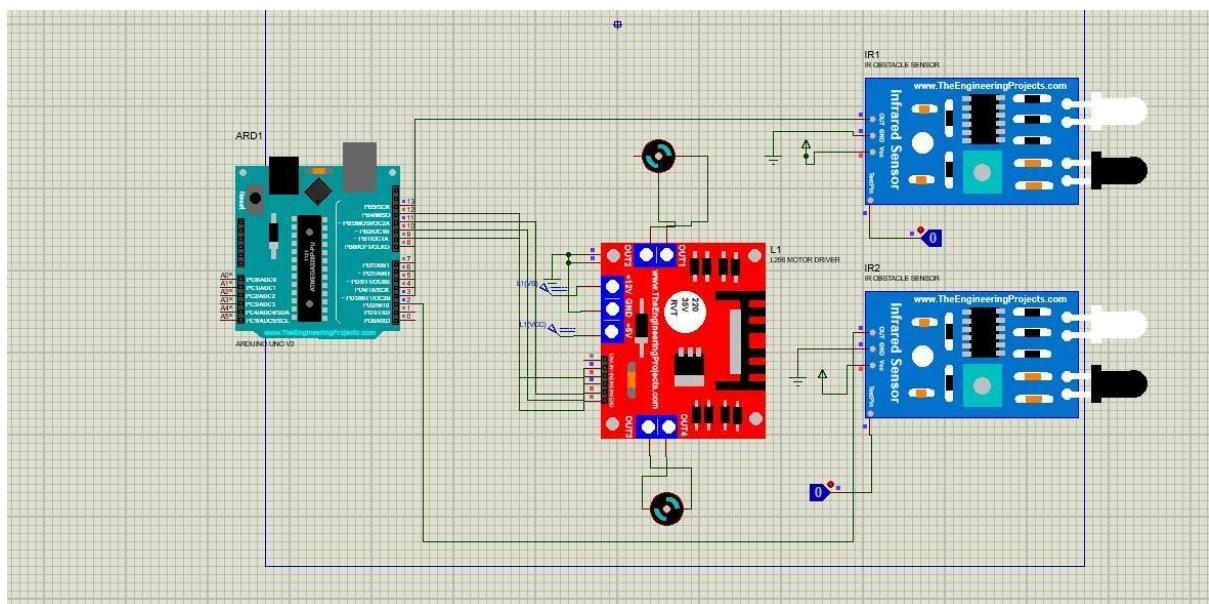
if(v==0 and s==0){

digitalWrite(13,0); digitalWrite(12,1);

```

```
digitalWrite(11,0); digitalWrite(10,1);  
}  
}
```

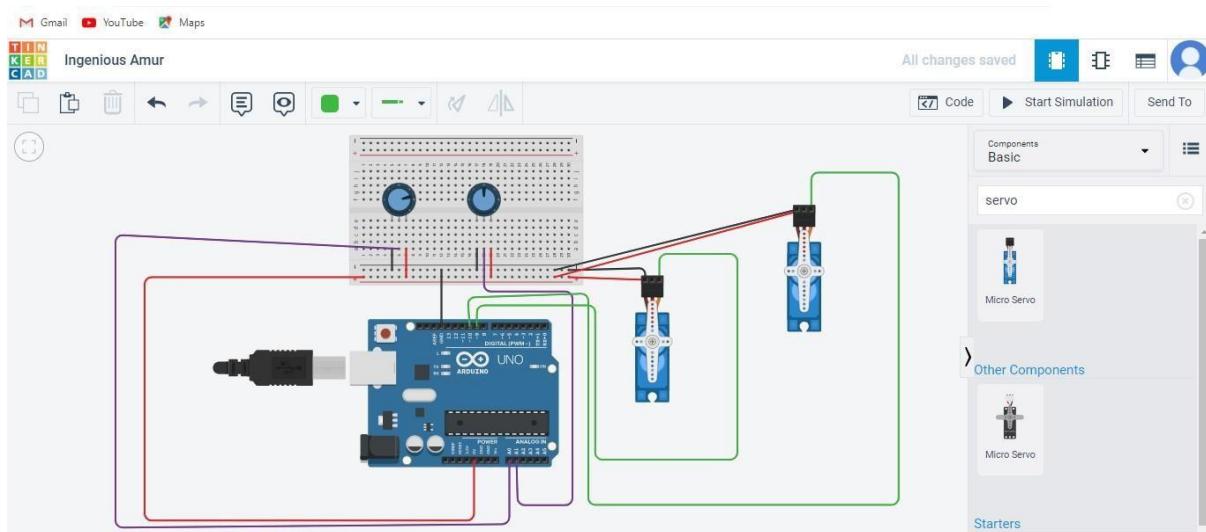
OUTPUT:



Practical No. 6

Aim: Add pan and tilt service to the robot object and test it.

Take Arduino Uno R3 , Breadboard, two Servo motor and make connections: Take two potentiometer and change resistance to 10: Join wires:



Code:

```
#include <Servo.h>
int sensorValue = 0; int outputValue = 0;
int sensorValue1 = 0; int outputValue1 = 0;
Servo servo_9;
Servo
servo_10;
void setup()
{
    pinMode(A0, INPUT); servo_9.attach(9, 500,
2500); pinMode(A1, INPUT); servo_10.attach(10, 500,
2500); }
void loop()
{
```

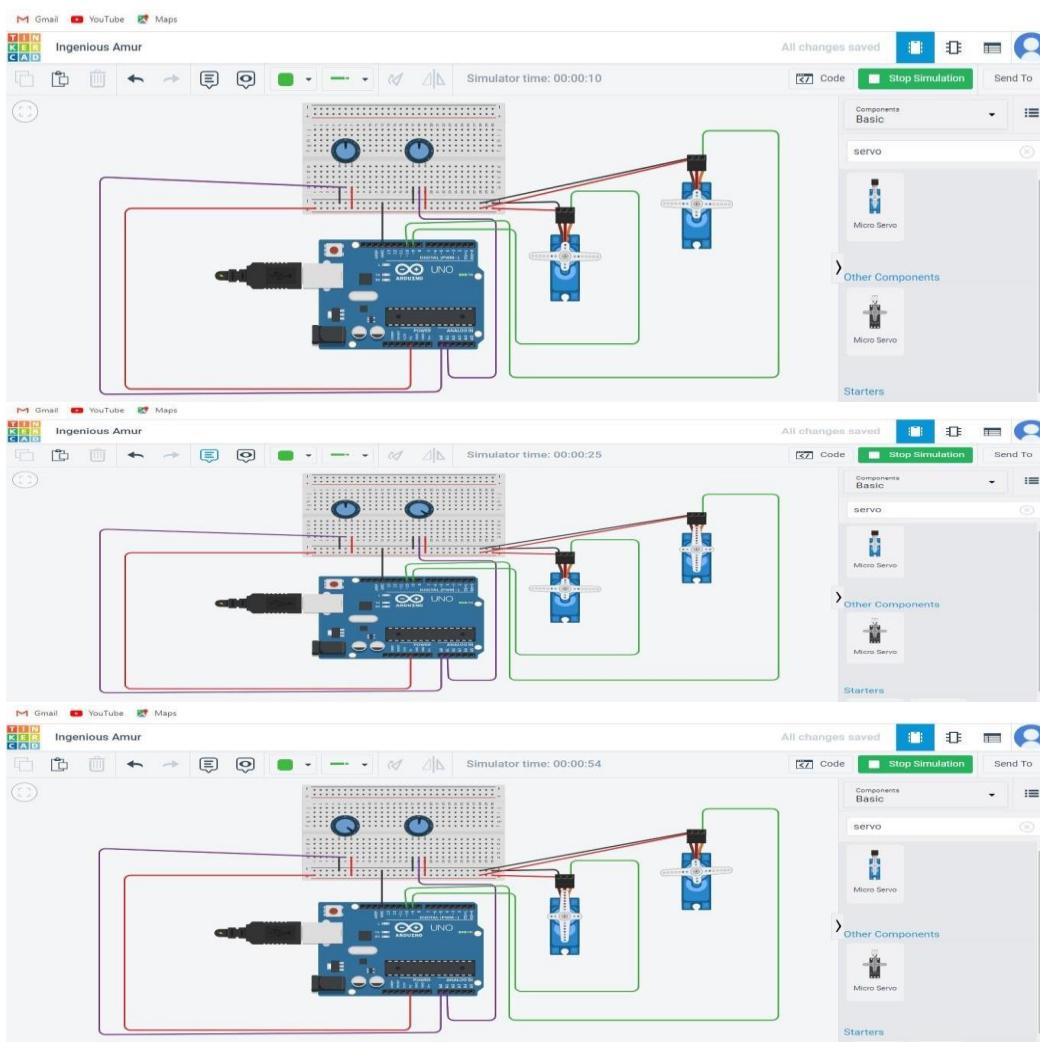
```
sensorValue = analogRead(A0); outputValue =
map(sensorValue, 0, 1023, 0, 180);
```

```

servo_9.write(outputValue); delay(10); // Delay a little bit to
    improve simulation performance sensorValue1 =
analogRead(A1); outputValue1 = map(sensorValue1, 0,
1023, 0, 180); servo_10.write(outputValue1); delay(10); //
Delay a little bit to improve simulation performance
}

```

OUTPUT:

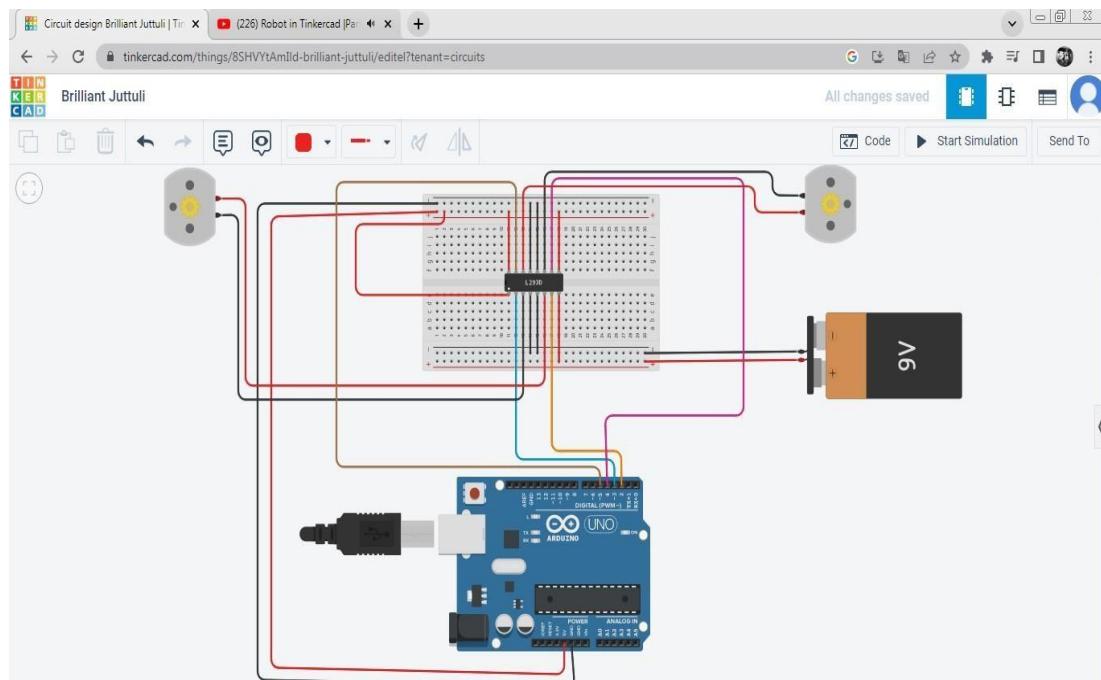


Practical No. 7

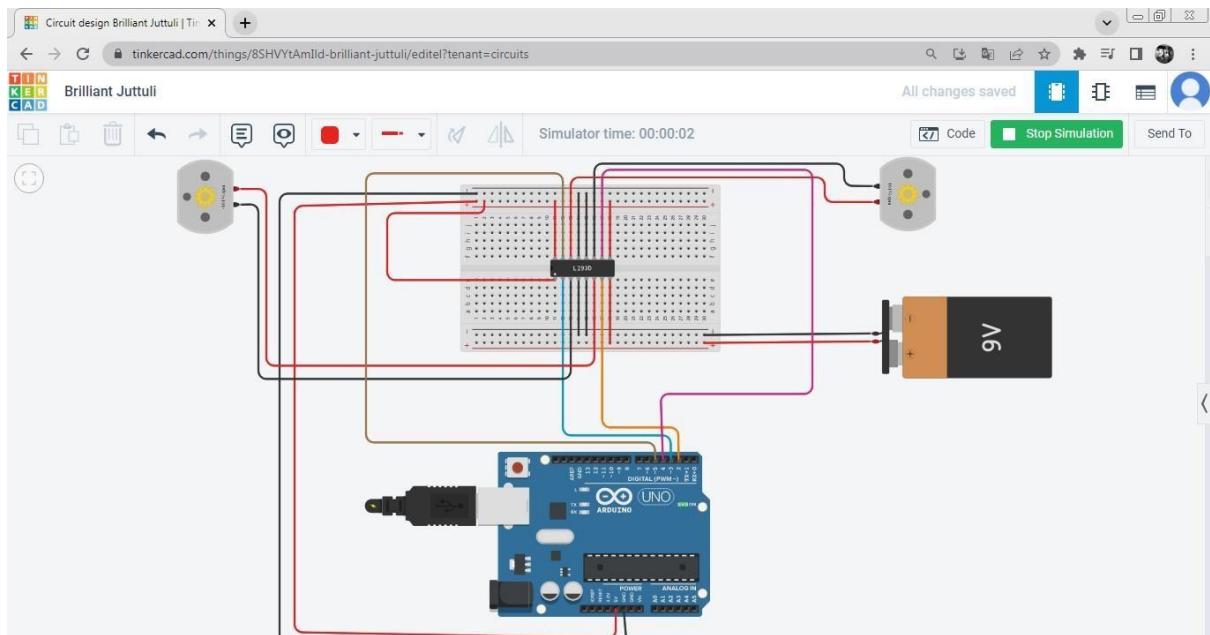
Aim: Create an obstacle avoidance behavior for robot and test it.

Part A

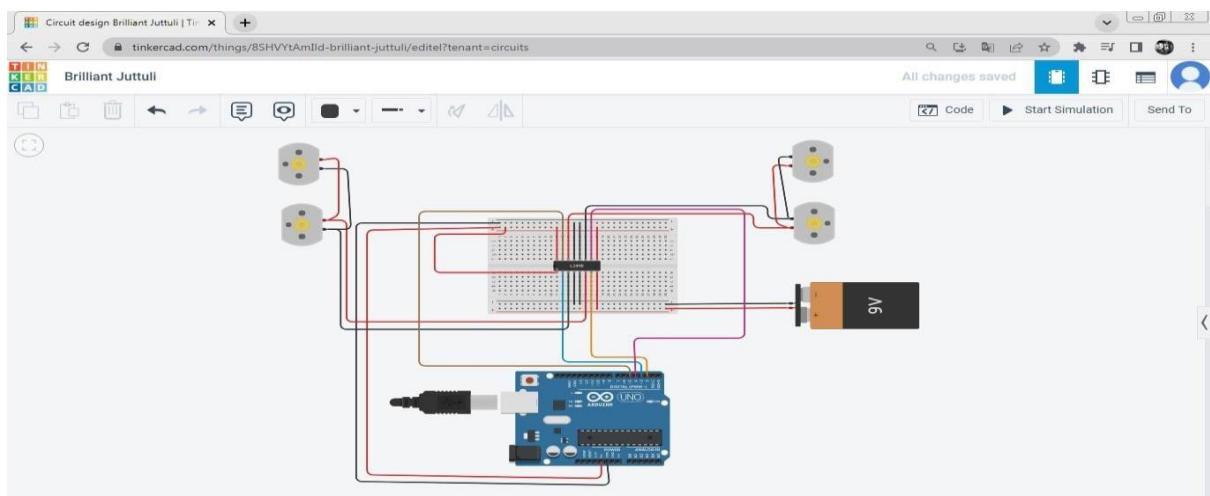
Take DC Motor and 9 Volt Battery, 2 Dc motors, Arduino UNO R3, 9V Battery and Breadboard small: Connect wires:



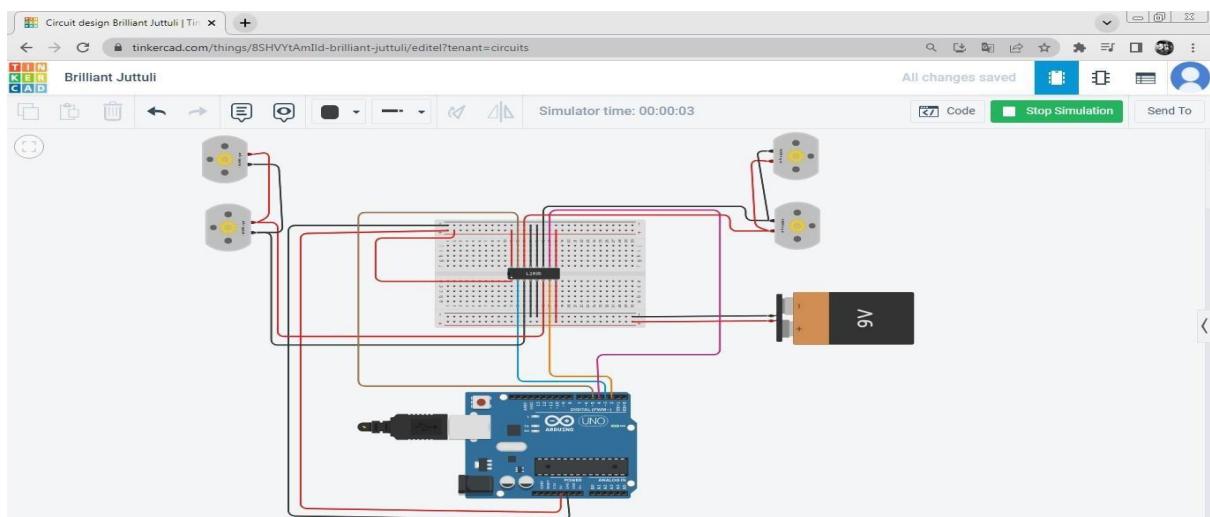
OUTPUT:



Take 2 more motors & connect wires:

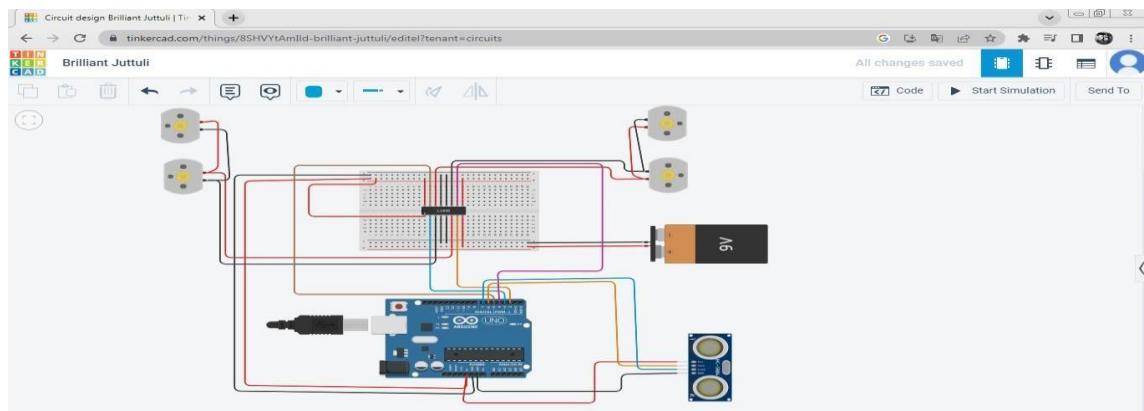


OUTPUT:

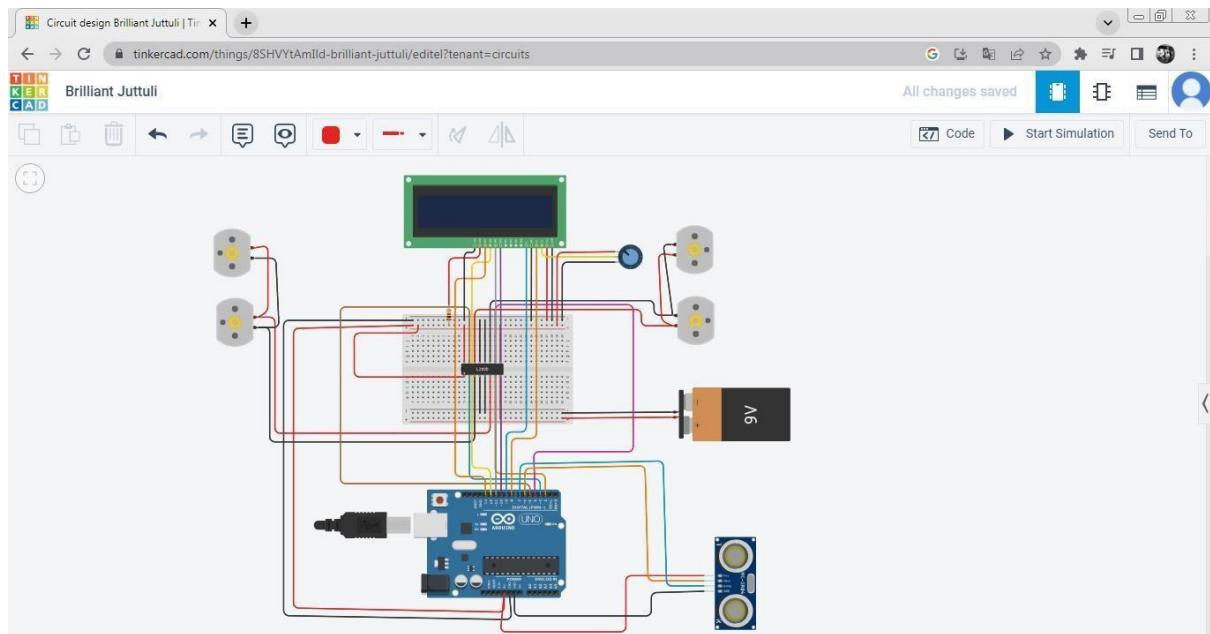


Part B

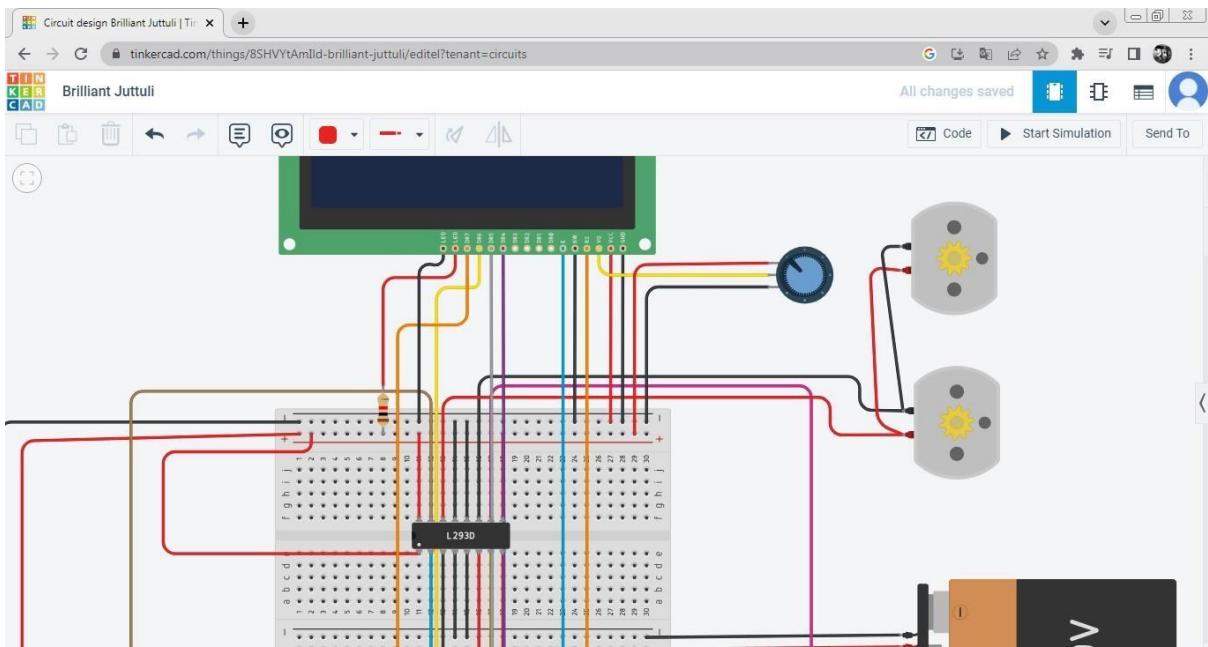
Take ultrasonic distance and connect :



Take LCD, Potentiometer and connect devices:



Take resistor and connect:



Write code:

```
//code for obstacle avoiding robot #include
<LiquidCrystal.h>LiquidCrystal lcd(8,9,10,11,12,13); long
cm, duration; const int echoPin = 7; const int trigPin = 6;
const int lm1 = 2; const int lm2 = 3; const int rm3 = 4; const
int rm4 = 5; void setup()
{
    pinMode(lm1, OUTPUT); pinMode(lm2, OUTPUT);
    pinMode(rm1, OUTPUT); pinMode(rm2, OUTPUT);
    pinMode(trigPin, OUTPUT); pinMode(echoPin, INPUT);
    Serial.begin(9600); lcd.begin(16,2);

} void loop()
{
    digitalWrite(trigPin, LOW); delayMicroseconds(2);
    digitalWrite(trigPin, HIGH); delayMicroseconds(5);
    digitalWrite(trigPin, LOW); duration =
}
```

```

pulseIn(echoPin,HIGH); //converting time into distance in
centimetre cm = duration*0.034/2; if(cm < 20)
{
  stop_bot(); delay(2000); go_back(); delay(2000);
  stop_again(); delay(1000); go_left(); delay(1000);
} else { go_straight(); delay(1000);
}

Serial.print("Distance:CM");
Serial.println(cm);
}

void go_straight()
{
  lcd.setCursor(0,0); lcd.print("NOTHING AHEAD");
  lcd.setCursor(0,1); lcd.print("MOVING FORWARD");
  digitalWrite(lm1,HIGH); digitalWrite(lm2,LOW);
  digitalWrite(rm1,HIGH);
  digitalWrite(rm2,LOW);
}

void go_back()
{
  lcd.clear(); lcd.setCursor(0,0);
  lcd.print("TAKING REVERSE"); lcd.setCursor(0,1);
  lcd.print(cm); digitalWrite(lm2,HIGH);
  digitalWrite(lm1,LOW); digitalWrite(rm2,HIGH);
  digitalWrite(rm1,LOW);
}

void stop_bot() { lcd.clear(); lcd.setCursor(0,0);
  lcd.print("SOMETHING AHEAD");
}

```

```

lcd.setCursor(0,1); lcd.print("STOP!");
digitalWrite(lm1,LOW); digitalWrite(lm2,LOW);
                    digitalWrite(rm1,LOW);
                    digitalWrite(rm2,LOW);

} voidstop_again() { lcd.clear(); lcd.setCursor(0,0);
lcd.print("BREAK FOR TURN"); digitalWrite(lm1,LOW);
digitalWrite(lm2,LOW); digitalWrite(rm1,LOW);
                    digitalWrite(rm2,LOW);

} voidgo_left()

{ lcd.clear(); lcd.setCursor(0,0); lcd.print("TURNING
LEFT"); lcd.setCursor(0,1); lcd.print(cm);
digitalWrite(lm1,LOW); digitalWrite(lm2,LOW);
                    digitalWrite(rm1,HIGH);
                    digitalWrite(rm2,LOW);

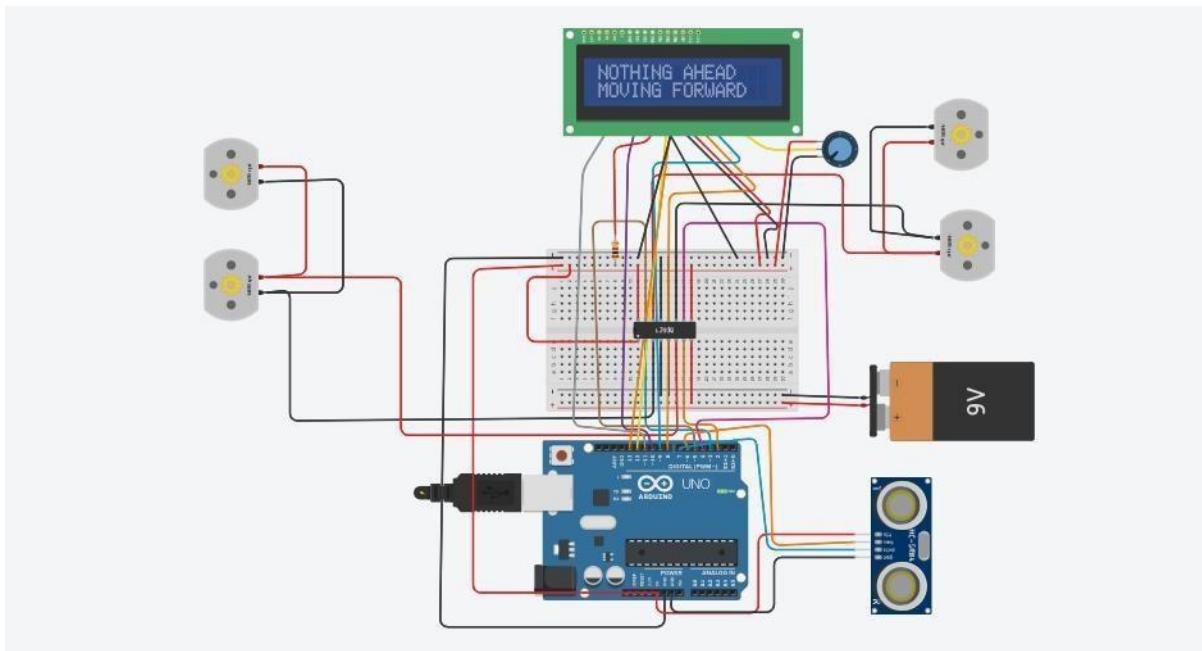
} voidgo_right()

{ lcd.clear(); lcd.setCursor(0,0); lcd.print("TURNING
RIGHT");
lcd.setCursor(0,1); lcd.print(cm);
digitalWrite(lm1,HIGH); digitalWrite(lm2,LOW);
                    digitalWrite(rm1,LOW);
                    digitalWrite(rm2,LOW);

}

```

OUTPUT:



Practical No: 8

Aim: Detect faces with haar cascades.

CODE:

```
# Importing OpenCV package import cv2

# Reading the image img = cv2.imread('test.jpg')

# Converting image to grayscale gray_img =
cv2.cvtColor(img, cv2.COLOR_BGR2GRAY)

# Loading the required haar-cascade xml classifier file
haar_cascade = cv2.CascadeClassifier(cv2.data.haarcascades
+ "haarcascade_frontalface_default.xml") eye_cascade =
cv2.CascadeClassifier(cv2.data.haarcascades +
'haarcascade_eye.xml')

# Applying the face detection method on the grayscale image
faces_rect = haar_cascade.detectMultiScale(gray_img, 1.3, 5)
eyes = eye_cascade.detectMultiScale(gray_img)

# Iterating through rectangles of detected faces for (x, y, w, h)
in faces_rect: cv2.rectangle(img, (x, y), (x+w, y+h), (0,
255, 0), 2) for (ex,ey,ew,eh) in eyes:
cv2.rectangle(img,(ex,ey),(ex+ew,ey+eh),(0,255,0),2)
```

```
cv2.imshow('Detected faces', img)
```

```
cv2.waitKey(0)
```

OUTPUT:

