Robot Find Home

Proposal Report

ELEC 299 Mechatronics Project

Team 03, Section 03

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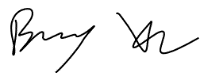
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March 4th, 2020

Our signatures below attest that this submission is our original work.

Following professional engineering practice, we bear the burden of proof for original work. We have read the Policy on Academic Integrity posted on the Faculty of Engineering and Applied Science web site (<http://engineering.queensu.ca/policy/Honesty.html>) and confirm that this work is in accordance with the Policy.

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**Individual 3:**

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# Executive Summary

The project goal is to get three robots to find a “home base” in the playing field provided. The robots will use sensors and motors in order to navigate the playing field and locate the objective. The problem will be broken down in 4 different categories which will be: the movement of the robots, find the home base, determining location, and communicating with other robots. Movement will be determined by position the robot strategically and ensuring that they drive straight. Moreover, ISM transceivers will be used to send the determined location of the home plate from one robot to another.

The robot will use a combination of different sensors and motors to determine where it is in the playing field, the direction it is going in, how far it has gone from its starting location, and when it is on the home base. This can be seen in the schematic provided in the body of the report.

A detailed flowchart and pseudocode are developed by the team shown in Figure 2 and Figure 3 to indicate and explain the key function of the robot which can be used as a reference for the team during the design process. After discussion among the three teams, a general project plan has been made which is to show in a detailed Gantt Chart shown in Figure 4. The teams have agreed to communicate weekly and have meetings weekly to ensure the completion of the tasks and deliverables. After every deliverable, the teams will meet and discuss the progress of the project. The teams will update the Gantt Chart accordingly as a reference to ensure the completion time of the project.

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# Section 1: Functional Requirements

## 1.1 Problem Definition

The main task of the project involves three teams working together for three robots to find a “home base” within a giving 180cm x 240cm playing field. This will be done using Arduino coding of different sensors and motors in order to complete the task at hand. Breaking down the problem into different subsections, they would be how the robots will move inside the playing field, detecting home base, position of the robots, and communicating with the other two robots.

## 1.2 Potential Solution

The teams came up with several potential solutions for the different subsystems based on the functional requirements after discussion and the final solution will be decided by the teams based on the pros and cons of each system.

### 1.2.1 Movement

By using a sweep scanning method, for the movement of each robot, they would go up and down in different lines looking for home base. The robots they will need to be strategically positioned and orientated at the starting points in order to ensure that they will cover as much ground as possible, so they find home base in a timely manner. Next, they would also have to turn 180 degrees perfectly each time they hit a wall. This could be done by using the IR distance sensor in the front of each of the robots or alternatively it could be done using the bumpers of the robot.

### 1.2.2 Detecting Home Base

One method that is possible for detecting the home base is to use the AMU in the WIFI enabled Arduino to measure the acceleration in the z-direction. When this happens, the robot should know that it has hit the home base. However, the IMU values can be unreliable and that could lead to false positives and false negatives which would very negatively impact our results. Another option would be to use the IR distance sensor and move it face towards the floor. Theoretically the sensor would give out a constant distance on the flat plate and would change when the distance is changed to a smaller number. The robot would then hit home base and would stop on the plate. Both of these methods would need further testing to ensure that they are both viable and reliable for the purposes of this challenge.

### 1.2.3 Tracking Robots Location

There are many possible ways to track the robot’s current positions; however, one way is to create a co-ordinate system for the entire grid with (0,0) being at one of the four corners. The robots would have an initial starting position which will be indicated in the code. Then the robots will keep track of all their movements using the encoders and update their position on the plane. Once one of the robots hit the home base, they would send the other two robots’ the location of the home base which can be used by the other robots as the destination. Another method for figuring out the location of the home base would be to use the beacons that are set up on the edges of the playing field. The robot that hits home base first can receive the frequency and to figure out which beacon it is looking at and the distance it is away from it. It would then turn 90 degrees and find the distance from the next beacon. Using these two distances the exact position of the robot can be found and that would be set to the other two robots.

# Section 2: Schematic of Hardware Connections

Figure - A detailed schematics outlining the components needed for the robot to function.

The main board on the left side of the diagram shown in Figure 1 is the Arduino Uno WIFI that we will be using with our robots. Connected to this Arduino through the digital pins 4-7 are the left and right motor. These are used to control the speed and direction of each of the motors on the robot. A push button circuit is also set up on the robot in order to control when and how the robot will start to execute its instructions. Encoders will also be used in this project to count how far the robot is moving within the playing field. Both left and right encoders can be seen connected to 5V, Ground, and a digital Arduino pin. Lastly, two different IR sensors are used in this schematic for the robot. One is the proximity sensor which will allow the robot to be able to turn before hitting any walls. The one as seen furthest on the right is the IR Receiver. This will be used to detect signals from one of the beacons on the playing field in order for the robot to know its location.

# Section 3: Role Description

Each team member should participate in developing the code and testing the robot to ensure that they understand the code and the hardware connections. Team members will communicate daily on the progress made to the project as well as having scheduled meetings throughout the week to work on the content as a group. A detailed table of general role of each member is shown in Table 1. Three team members will be assigned to work on software, hardware, and research separately. The individual who works on essential parts of the software will provide the pseudocode as well as a flowchart based on the decision-making process of individual robots. The team member who is responsible for the main parts of the hardware will accomplish a schematic of hardware connection based on the sensors and connections between Arduino and circuits. There will be another individual team member who is responsible for conducting background research on the project as well as booking meeting times according to individual schedule and ensure that deliverables are completed on time.

|  |  |
| --- | --- |
| Name | Roles of each person |
| Barry Xu | Arduino programming & Pseudocode |
|  | Demonstration (flowchart) |
|  | Hardware (research on sensors) |
|  | Project plan (Gannt chart & collaborate with other teams) |
|  | Proofreading |
| Noah Marra | Software (modify code based on functional requirements) |
|  | Collect data from analogue and digital interface |
|  | Schematic of hardware connections |
|  | Functional requirements (do research & check updated information) |
|  | Proofreading |
| Amanda Yu | Software (modify code based on research and requirements) |
|  | Do research on the functions of sensors and motors |
|  | Decomposition into key requirements |
|  | Role description |
|  | Proofreading |

Table 1: A description of the role of each person on the team

# Section 4: Flowchart and Pseudocode

The pseudocode and flowchart for the key functions of each robot is shown in Appendix in Figure 1 and in Figure 2. Each robot will include similar functionality with a difference in searching strategy where they will search in different routes. A detailed explanation of the function of the robots is shown in Section 5: Function of robots.

# Section 5: Function of robots

Sensors and motors are required to accomplish the detection and movement of robots. Analog and digital interfacing will display the data which will help to determine the position of robots on the playing field and avoid hitting hazards such as walls and other robots.

## 5.1 Navigation System

The navigation part will focus on the solutions of ensuring that the robot can drive in an intended direction and determining the position of the home base, and this will be controlled by the encoder interrupted count. Each robot will be able to search, locate, and direct independently to the home base. In order to determine the home base, the IMU sensor is required to measure a difference in the z-axis acceleration. The z-axis acceleration and distance will change by robot moving onto the home base from a flat surface. There will be a x-y coordinate set up as indicated in the Figure 1 and Figure 2 for the main searching area which can provide an specific location of the home base once a robot detects it.

## 5.2 Communication System

The ISM serial transceiver allows the robot that detects the home base to communicate to the other robot and send an exact location based on the coordinate system. Once the location is detected, each robot will run through a separate function for them to move accordingly based on the given location. After all robots are located near the home base, a message will be sent to the web server via WIFI to notice the user that the home base has been found.

# Section 6: Project Plan

The teams have created a general plan to be used to follow and keep the team on track during the competition project and to ensure the system can be completed on time while meeting all the requirements.

## 6.1 General Project Management

The list of key tasks with due dates are shown in Figure 4. As shown in the Gantt Chart, three teams will work closely for each stage of the project and different research tasks will shared between individual teams to ensure that the final task can be completed on time. During week 8 of the term, teams will meet together to discuss on the research conducted and decide on the final solution for the system. Each team will communicate constantly to ensure that every team is on the same stage of the project. While any difficulties occur during the design process, all teams will meet together to make decisions for the solution of the issue and ensure that all team members are updated with the progress on the robots.

Teams will meet twice a week for updating progress of the design and creating plans accordingly based on individual’s time schedule. Each team will develop the code for the subsystems of the whole design and all teams will discuss the individual code during each meeting to ensure that the robots work together within a system. Flowchart will be updated accordingly to help guide the team towards the final design. Gantt Chart will also be updated due to the progress of the project to ensure the completion time. During week 9 and week 10, the teams will work together to implement the code on all three robots and test on them in the field. Later on, each team will conduct research to optimize the system based on its functionality to ensure it meets all the requirements. All teams will decide and implement on the final optimized solution as a whole.

## 6.1 Individual Team Plan

In terms of individual team, a role for each team member within this team has been shown Table 1. All three members will develop the code and testing together for the robot to ensure that everyone understands and can continue developing the code with an absence of a team member due to various reasons sometime. The report will be divided between all three members. The team will ensure to complete the reports at least one day before the due date and the whole team will meet during the day of the due date to proofread the report together. One team member is responsible for submitting the report and it is everyone’s responsibility to ensure that reports are submitted before the deadline.

# 

# Appendix

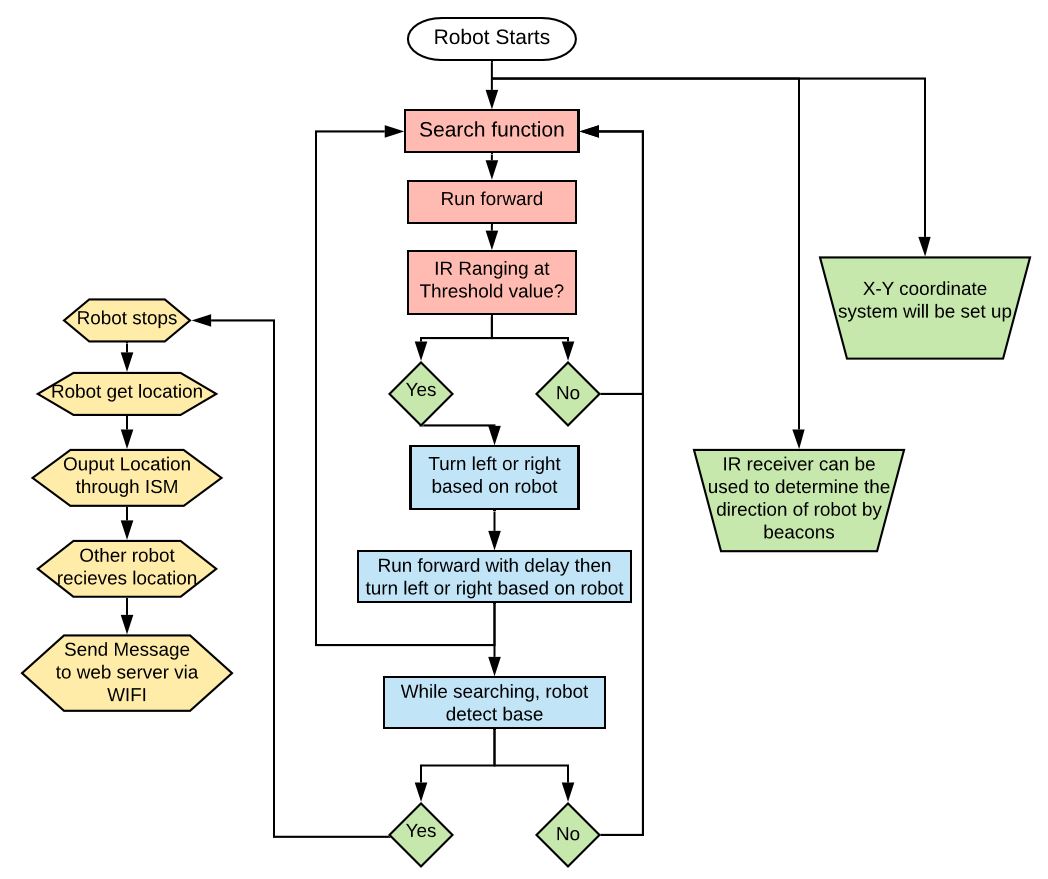


Figure 2 - Flowchart explains the basic function and decision-making process of individual robots.

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Figure 3 - Detailed decision-making process for individual robots during the competition.

![A screenshot of a cell phone

Description automatically generated](data:image/jpeg;base64,/9j/4AAQSkZJRgABAQEAeAB4AAD/4RDcRXhpZgAATU0AKgAAAAgABAE7AAIAAAAGAAAISodpAAQAAAABAAAIUJydAAEAAAAMAAAQyOocAAcAAAgMAAAAPgAAAAAc6gAAAAgAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAEJhcnJ5AAAFkAMAAgAAABQAABCekAQAAgAAABQAABCykpEAAgAAAAMxNgAAkpIAAgAAAAMxNgAA6hwABwAACAwAAAiSAAAAABzqAAAACAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAA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Figure - A detailed Gantt chart for the project.