



e-ISSN: 2278-8875  
p-ISSN: 2320-3765

# International Journal of Advanced Research

in Electrical, Electronics and Instrumentation Engineering

Volume 11, Issue 4, April 2022



Impact Factor: 8.18

9940 572 462

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# Obstacle Avoiding Robot

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**ABSTRACT:** The objective of our project is to make an independent robot which insightfully distinguishes the hindrance in his way and explore as per the activities we set for it. This undertaking is been planned and executed with AT mega 328P miniature regulator in inserted framework domain. Experimental work has been done carefully. Sensors result will be given to controller. According to the program written in the regulator it will give guidelines to all gadgets. The task gives a rule to the understudies who are new in the realm of Arduino and assist them with comprehension about installed framework, IR sensors, microcontroller and how to make a robot utilizing Arduino. The proposal will cause understudies to more deeply study essential information and abilities with respect to servo, program and math to compute program esteems. New understudies will figure out how to program the BOE-Bot to perform fundamental moves and slow speed increase and deceleration of the robot to get robot out of moves and furthermore understudies will figure out how to compose subroutines to perform essential moves.

**KEYWORDS:**DC Motor, Arduino Nano, Arduino Nano Shield, Ultrasonic Sensor arduino, Motor Driver IC.

## I.INTRODUCTION

Advanced mechanics is the part of innovation that arrangements with the plan, development, activity, and utilization of robots. A machine equipped for completing a perplexing series of activities consequently, esp. one programmable by a PCs is characterized as a robot. Furthermore, Obstacle evasion alludes to the capacity of a robot to identify snags in its manner assuming there are any and along these lines make its own hindrance freeway.

The proposition manages two stages; first making a deterrent staying away from robot and second, basic rule to the principal year designing understudies. The proposal will assist them with finding out concerning material science when managing terms like Infrared (IR), IR sensors, electromagnetic range, and furthermore with installed registering while at the same time making the robot. The Board of Education (BOE-Bot) is our functioning cellar of the undertaking. BOE-Bot is moderately straightforward programmable robot series, which does not need any profound information on mechanical technology, programming, or hardware. The task is to foster a robot that will move as indicated by the code allocated yet track down a free space, exploring from any deterrent coming. This sort of snag is extremely valuable in businesses where mechanized management is required, for instance, in places where it very well may be hazardous for people to be. This robot can likewise be made by putting different sensors like light sensors or line.

## II. PROPOSED SYSTEM DEVELOPMENT

### A. DC Motor

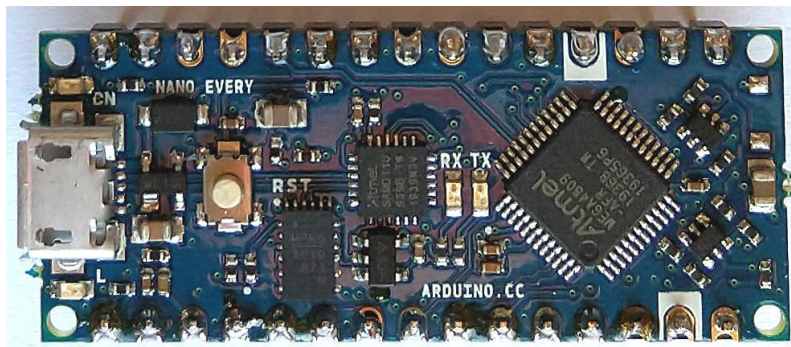
A DC motor is any of a class of rotary electrical motors that converts direct current (DC) electrical energy into mechanical energy. The most common types rely on the forces produced by magnetic fields. Nearly all types of DC motors have some internal mechanism, either electromechanical or electronic, to periodically change the direction of current in part of the motor.



### B. Arduino Nano

The Arduino Nano is a small, complete, and breadboard-friendly board based on the ATmega328P released in 2008. It offers the same connectivity and specs of the Arduino Uno board in a smaller form factor.

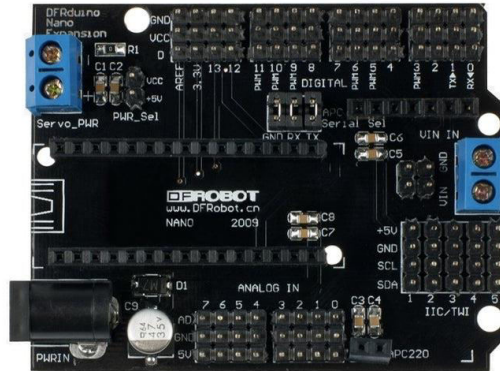
The Arduino Nano is equipped with 30 male I/O headers, in a DIP-30-like configuration, which can be programmed using the Arduino Software integrated development environment (IDE), which is common to all Arduino boards and running both online and offline. The board can be powered through a type-B mini-USB cable or from a 9 V battery. In 2019, Arduino released the Arduino Nano Every, a pin-equivalent evolution of the Nano. It features a more powerful ATmega4809 processor and twice the RAM.



### C. Arduino Nano Shield

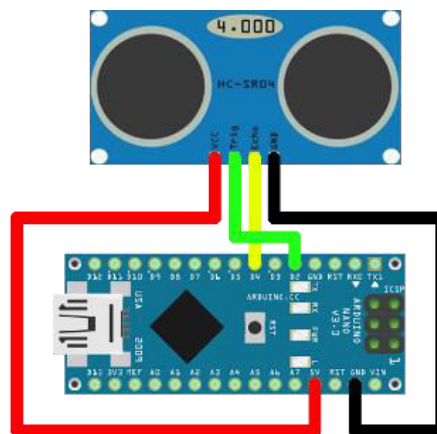
The Nano I/O Sensor Shield is an expansion board for the Arduino Nano boards. There are several different options for power input. The form factor of the Nano I/O Shield board is the same as the Arduino UNO/arduino Leonardo. In addition, the sensor shield adopts Gravity interface that each pinout includes 5V and GND pins for easy connection to Gravity sensors or servos. To the best compatibility, the shield supports jumper wires for rapid prototyping. This unit comes fully assembled. The board also has a space specifically for bluetooth module and ACP220. Several I2C pins are also expanded. The shield has independent power supply to provide extra power for servo and other sensors.





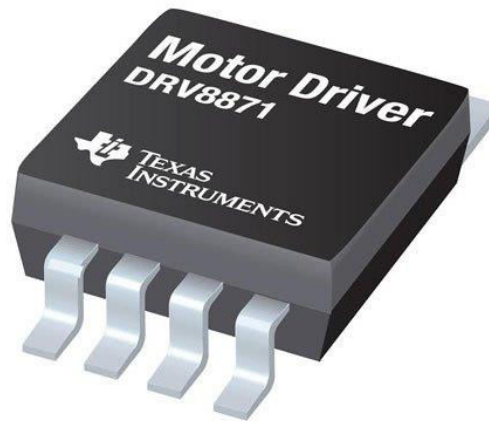
#### D. Ultrasonic Sensor arduino

Ultrasonic sensors measure distance with ultrasonic waves. It measures timeframe from emitting sound until receiving the rebounded soundwaves. By knowing the soundspeed (340.29m/s), the ultrasonic controller can calculate the distance in 0.01cm accuracy. You can always ask the current distance between any object and the sensor. This a perfect tool for building small robots.



#### E. Motor Driver IC.

A motor driver IC is an integrated circuit chip which is usually used to control motors in autonomous robots. Motor driver ICs act as an interface between microprocessors in robots and the motors in the robot. The most commonly used motor driver IC's are from the L293 series such as L293D, L293NE, etc. These ICs are designed to control 2 DC motors simultaneously. L293D consist of two H-bridge. H-bridge is the simplest circuit for controlling a low current rated motor. For this tutorial we will be referring the motor driver IC as L293D only. L293D has 16 pins.



### III. PRINCIPLE OF OPERATION

Deterrent evasion is one of the main parts of portable advanced mechanics. Without it, robot development would be exceptionally prohibitive and delicate. This undertaking proposes mechanical vehicle that has an insight underlying it with the end goal that it guides itself at whatever point an impediment comes in its way. Along these lines, to shield the robot from any actual harms. This can be configuration to fabricate a hindrance aversion mechanical vehicle utilizing ultrasonic sensors for its development. A miniature regulator (AT mega 328P) is utilized to accomplish the ideal activity. A ultrasonic sensor is utilized to identify any obstruction in front of it and sends an order to the miniature regulator. Contingent upon the info signal got, the miniature regulator diverts the robot to move a substitute way by activating the engines, which are interfaced to it through an engine driver.

The sonic waves transmitted by the transducer are reflected by an item and got back in the transducer. Subsequent to having discharged the sound waves, the ultrasonic sensor will change to get mode. The time passed among radiating and getting is relative to the distance of the article from the sensor.

Ultrasonic sensor are gadgets that utilization electrical– mechanical energy changes to quantify distance from the sensor to the objective article. Ultrasonic waves are longitudinal mechanical waves, which travel as a grouping of compressions and rarefaction along the course of wave spread through the medium. Distance is a worth between the item and the snag, which is answerable for the robots and mechanized hardware system, which can be set in a code that will be utilized in the impediment location. Allow us to take a right IR drove and a right servo as reference

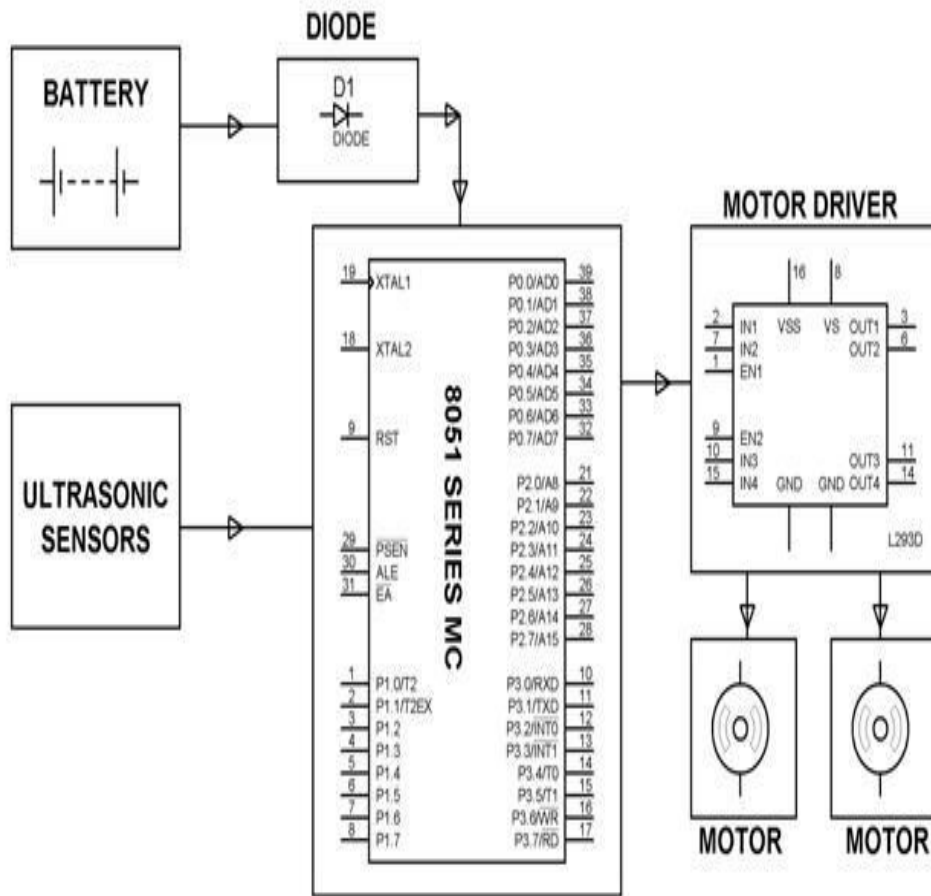


Fig 3 Actual circuit diagram

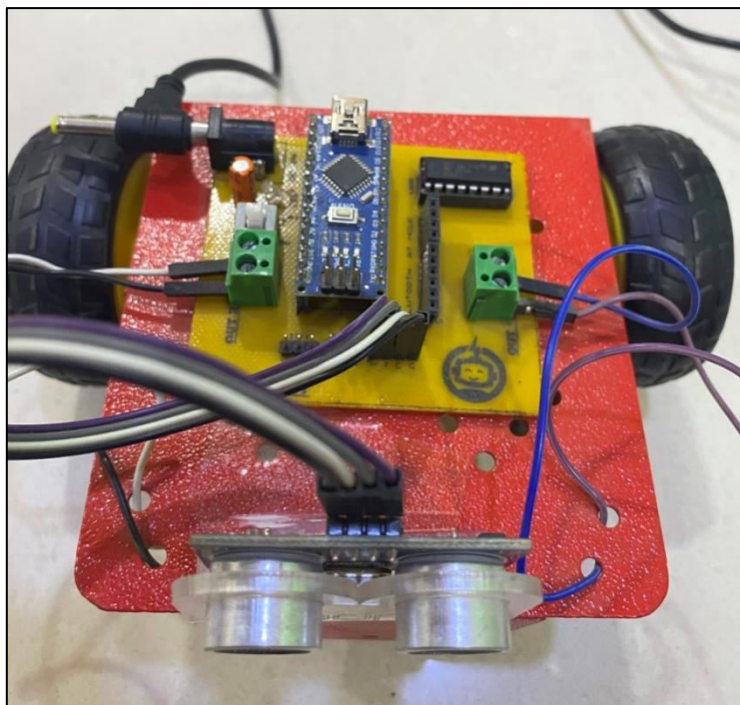
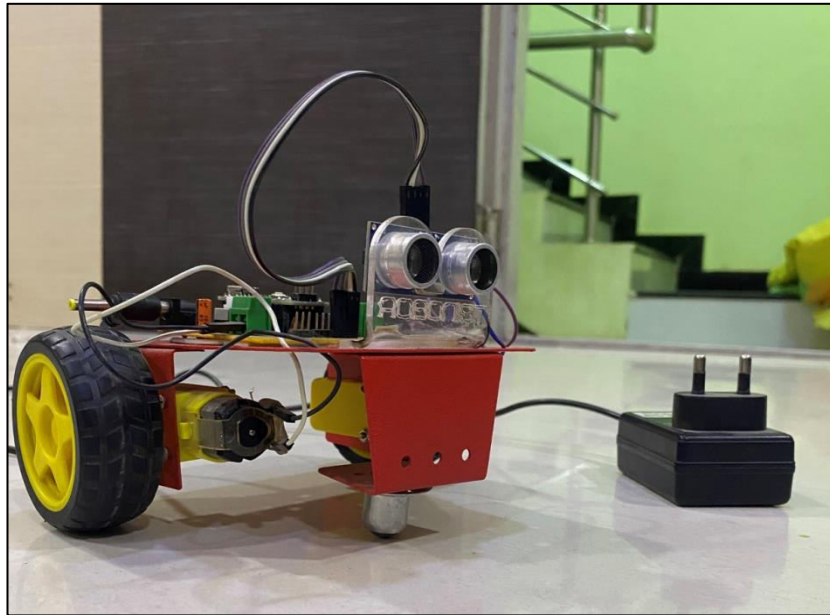
#### IV. FUTURE SCOPE

This robot is able to produce the basic walking movements using two gear motors. They developed the robot with a very good intelligence which is easily capable to sense the obstacle and by processing the signal coming from the sensor it is perfectly avoiding the obstacle coming in the path.



## V. RESULT AND DISCUSSION

The following images show the working scenario and outcomes of this system.



**Fig 5 Overview of the System**



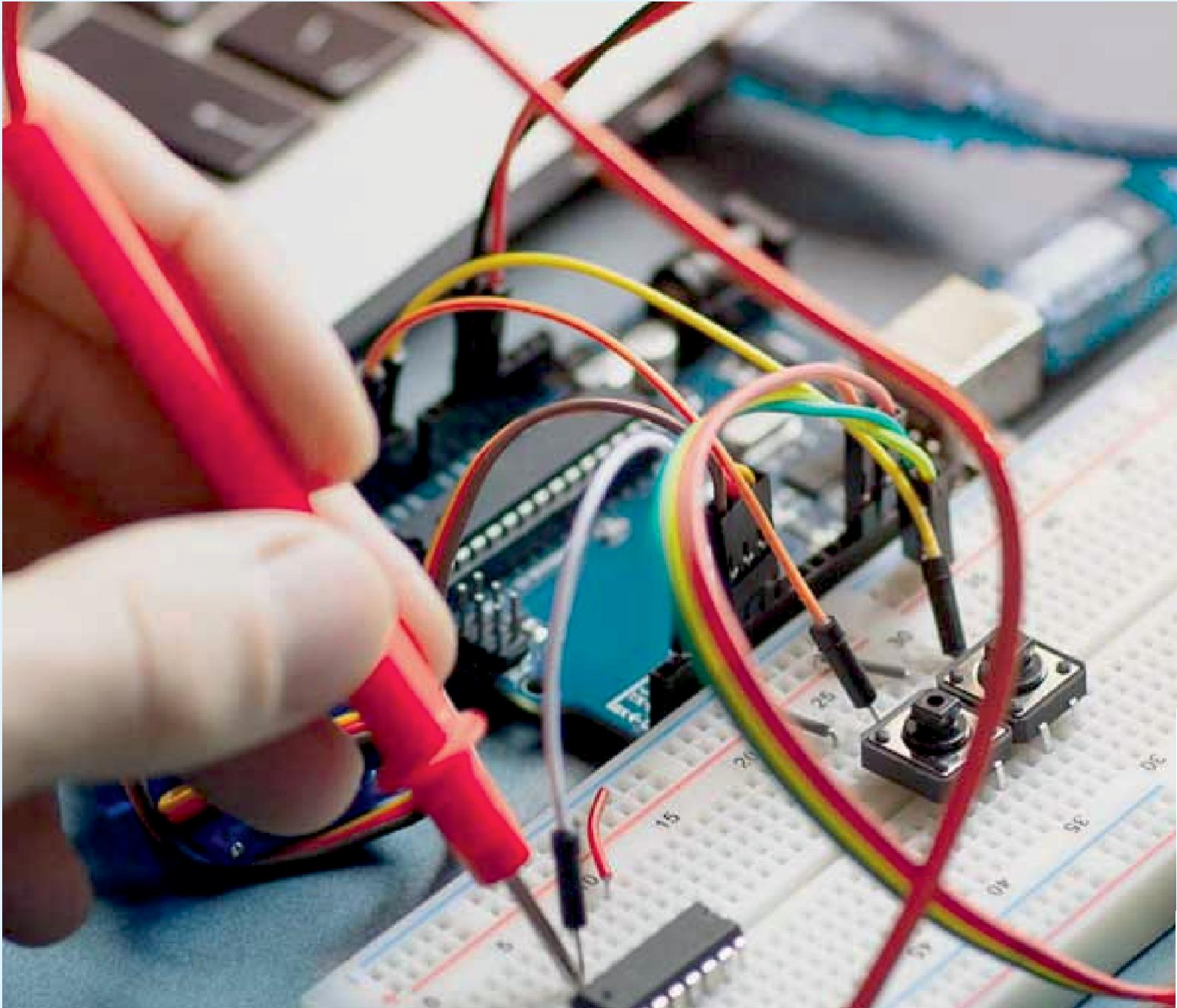
## VI. CONCLUSION

This undertaking fostered a deterrent keeping away from robot to distinguish and stay away from snags in its way. The robot is based on the Arduino stage for information handling and its product partner assisted with speaking with the robot to send boundaries for directing development. For hindrance identification, three ultrasonic distance sensors were utilized that gave a more extensive field of recognition. The robot is completely independent and after the underlying stacking of the code, it requires no client mediation during its activity. At the point when put in obscure climate with deterrents, it moved while keeping away from all impediments with extensive exactness. To advance the development of the robot, we have numerous contemplations for development. Nevertheless, the vast majority of these thoughts will cost more cash and time also. In ongoing cameras can be utilized to identify the deterrent in any case, it is smarter to get CCD or modern use ones to get clear and quick pictures. Indeed, even the ones we referenced in the camera holder part will be better a result of the unique programming.

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Impact Factor: 8.18

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