© June 2024| IJIRT | Volume 11 Issue 1 | ISSN: 2349-6002

Arduino-Based Autonomous Car using IR Sensors

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***Abstract*—The project focuses on the development of an autonomous car, using an Arduino Uno board and an array of components including the HC-05 Bluetooth module, L298N motor driver, IR sensor, 2x3.7V batteries, and NEO 6M GPS module. The fundamental objective of this project is to achieve autonomous navigation capabilities a combination of IR sensors for lane and obstacle detection and GPS coordinates for destination-based travel. The integrated software and hardware architecture facilitate automatic and manual modes, with the system capable of transitioning to manual control upon detecting obstacles. Through a designed code structure, the car is equipped to precisely follow specified coordinates to reach predefined destinations and subsequently return to the source. The utilization of IR sensors for lane and obstacle detection, the integration of the GPS module for coordinate-based navigation, and the seamless transition between automatic and manual modes collectively make this project a noteworthy demonstration of autonomous robotic navigation.**

Keywords—Arduino UNO, HC-05 Bluetooth Model, L298N motor driver, IR Sensors, Neo 6M GPS Module.

I. INTRODUCTION

This project is about building a small model of a self-driving car. It uses an Arduino Uno board, sensors, and GPS to navigate its way around. The car can follow a line on the ground and avoid obstacles. It can also go to a specific location using GPS coordinates.

The car can switch between driving itself and being controlled by a person. This project shows how different parts work together to make a self-driving car. It also shows how self-driving cars could be used in the future. The car uses IR sensors to see the line on the ground and avoid obstacles. The sensors send signals to the Arduino board, which tells the motors how to move. The GPS module tells the car where it is and where it needs to go. The Arduino board uses

this information to calculate the best route. The car can switch between driving itself and being controlled by a person. This is done using a Bluetooth module. The person can use a smartphone or computer to control the car. This is useful for situations where the car cannot drive itself, such as in heavy traffic or on narrow roads.This project shows how self-driving cars could be used in the future. They could be used to transport people and goods, or they could be used for other tasks such as delivery or security. Self-driving cars could make our lives easier and safer.

II. RELATEDWORK

In [1], Researchers introduced an autonomous car platform that relies on the SoftMax function. This function scales the outputs of each unit to a range between 0 and 1, similar to a sigmoid function. The system utilizes a single camera for all inputs and operates at a speed of 5-6 km/hr, regardless of whether lane markings are visible. However, this model only detects lane markings and turn signs, without sensing traffic signals or stop signs.

In [2], In another study (referenced as [2]), an autonomous RC car was developed. The thesis behind this project focused on neural networks and autonomous vehicles. The system used an embedded Raspberry Pi camera for input and grayscale images for training the neural network. Its primary function was to detect lane markings in various directions, offering no additional features beyond that.

In [3], A third approach (referenced as [3]) involved creating a simulator that mimicked real roads and city streets with traffic. This system combined camera and LiDAR data to gain a better understanding of the surroundings and identify obstacles of all types.

Unlike the previous models, it aimed for a more comprehensive perception of the environment.

In [4], The researchers explored object detection using deep neural networks, specifically convolutional neural networks (CNNs). Training a neural network from scratch requires significant time and computational resources because finding an adequately sized dataset with accurate ground truth labels is challenging. However, employing a Regional Convolutional Neural Network (RCNN) helps identify relevant regions within an image, allowing real-time outputs. This type of deep neural network is particularly valuable for medical image processing, such as detecting tumors, where the complexity of the dataset surpasses that of a typical road environment.

In [5], Their model for a self-driving vehicle using a Raspberry Pi camera attached to the vehicle. They conducted experiments on various track configurations, including straight sections, curves, and combinations of both. From a total of 24 recorded videos, they extracted 10,868 images and organized them into different folders (e.g., left, right, straight, and stop). The paper provides clear descriptions of the hardware components, software, and neural network architecture used in the model. Leveraging image processing and machine learning techniques, they successfully designed, implemented, and tested the model. However, it’s worth noting that the vehicle occasionally deviated from the track, which could pose challenges if it encounters nearby obstacles in a real-world scenario.

In [6], They have developed a car that recognizes three street signs (Stop, No Left Turn, and Traffic Light) using a combination of Deep Q-Network (DQN) and a Convolutional Neural Network (CNN). During training, the CNN achieved 89% accuracy on the training data and 73% accuracy on the test data. External factors like lighting and weather impact image quality and model predictions.

III. PROPOSED WORK

The methodology for the project is structured around meticulous steps to ensure the successful development and demonstration of the autonomous car model's capabilities. It commences with the systematic assembly of the 4WD Chassis Kit, emphasizing the secure and stable mounting of the various components including the NEO-6M GPS module and the 18650 3.7V batteries, which serve as reliable power sources for the model.

After completing this step, you’ll need to set up crucial hardware components. This involves connecting the L298N motor driver and the HC-05 Bluetooth module to the Arduino Uno microcontroller, as well as incorporating IR sensors for accurate obstacle detection and lane tracking. Subsequently, the software development phase involves coding for autonomous navigation utilizing GPS coordinates, developing algorithms for obstacle detection and lane tracking based on data from IR sensors, as well as implementing logic for seamless transitions between autonomous and manual control modes based on real-time sensor inputs. Rigorous testing and calibration procedures are then executed to validate the functionality and synchronization of the integrated components.

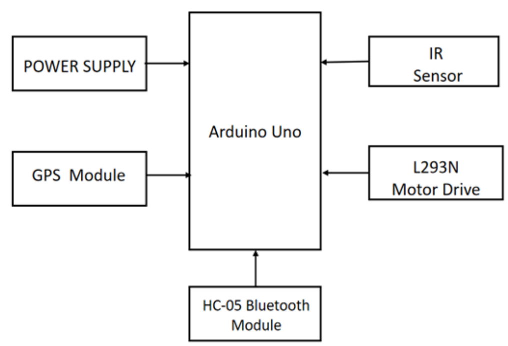

Figure 1: Block Diagram

A. Arduino Uno: The central microcontroller unit responsible for processing input data from sensors, executing control algorithms, and managing the overall operation of the autonomous car. The L298N Motor Driver interfaces with the car’s control system, responding to sensor inputs and navigation algorithms. Additionally, it integrates with IR sensors to provide real-time obstacle detection and lane tracking functionality.

B. L298N Motor Driver: The L298N Motor Driver serves as the bridge between the Arduino Uno and the motors, supplying essential power and control signals to facilitate the car’s movement. It responds to commands from the microcontroller, adjusting motor speed and direction according to navigation and obstacle avoidance algorithms.

C. IR Sensors:The components play a critical role in obstacle detection and lane tracking, supplying essential input to the microcontroller for safe and accurate navigation. They identify obstacles and continuously monitor lane boundaries, allowing the autonomous car to make well-informed decisions about its trajectory.

D. NEO-6M GPS Module: Utilized to receive accurate global positioning system (GPS) data, enabling the car to navigate and travel to predefined or dynamically specified locations. Interfaces with the microcontroller to provide essential location information for autonomous navigation and route planning.

E. HC-05 Bluetooth Module: Enables wireless communication capabilities, allowing for remote control, data exchange, and possible future expansion of the car's functionality through external interfaces. Interfaces with the microcontroller to facilitate Bluetooth communication for potential remote control and monitoring of the car's operations.

F. Power Supply: Serves as the primary power source for the autonomous car, supplying the necessary electrical energy for the operation of the motors, microcontroller, and other connected components. Provides the required voltage and current to drive the motor and the electronic components, ensuring uninterrupted functionality of the autonomous car.

ARDUINO UNO DEVELOPMENT BOARD:

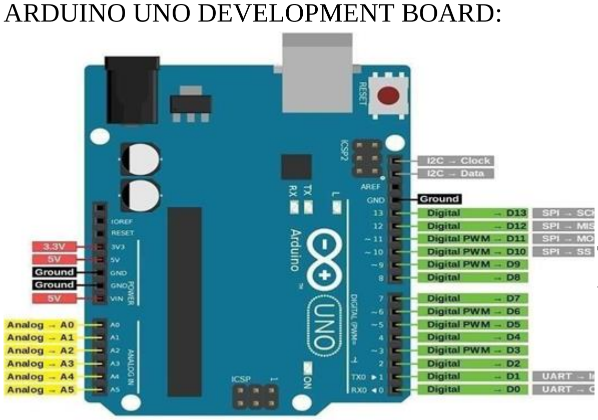

Figure 2: Arduino UNO development board

The Arduino Uno, a widely-used open-source microcontroller board, is built around the Atmel AVR microcontroller chip. It caters to a diverse range of electronic projects and is particularly beginner-friendly. With 14 digital input/output pins, six analog inputs, a 16 MHz quartz crystal, USB connectivity, and an ICSP header for programming, the Uno offers versatility. Whether powered via USB or an external source, it can be programmed using the user-friendly Arduino Integrated Development Environment (IDE). The Uno boasts an active community of developers and enthusiasts who freely exchange code and project concepts. For any project, user-written code typically involves just two fundamental functions: one to initialize the sketch and another for the main program loop.

HC-05 BLUETOOTH MODEL:

The HC-05 Bluetooth module is a compact and versatile wireless communication device that operates in the 2.4 GHz ISM band. It is based on the Bluetooth 2.0 + EDR (Enhanced Data Rate) specification, offering a maximum data transfer rate of 3 Mbps. The module is compatible with a wide range of devices, including smartphones, tablets, laptops, and microcontrollers. It supports Bluetooth 2.0 + EDR standard for reliable and efficient data transmission. Can operate as either a master or slave device, providing flexibility in communication scenarios. Utilizes a standard UART interface for easy integration with microcontrollers and other devices. Operates on a low power budget, making it suitable for battery-powered applications. Small footprint allows for easy integration into various projects. Supports a wide input voltage range of 3.3V to 6V, making it compatible with different power sources.

Figure 3: HC-05 Bluetooth Model

The HC-05 Bluetooth module is a valuable tool for wireless communication projects, offering a reliable and efficient way to connect devices over short distances. Its compact size, low power consumption, and ease of use make it a popular choice for hobbyists and professionals alike.

L298N MOTOR DRIVER:

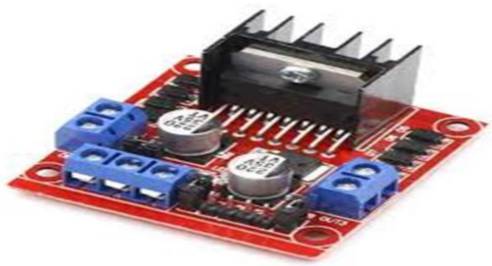

Figure 4: L298N Motor driver

The L298N, a dual H-Bridge motor driver, facilitates simultaneous speed and direction control for two DC motors. It accommodates motor voltages ranging from 5V to 35V, with a peak current handling capability of up to 2A. Let’s delve into the pinout of the L298N module. It features two screw terminal blocks for connecting motors A and B, along with another terminal block for the Ground pin, motor VCC, and a 5V pin. The 5V pin can serve as either an input or an output, depending on the motor voltage applied to VCC. Additionally, the module includes an onboard 5V regulator, which can be enabled or disabled using a jumper. When the motor supply voltage is 12V or below, we can enable the regulator, allowing the 5V pin to function as an output (e.g., to power an Arduino board). However, if the motor voltage exceeds 12V, disconnecting the jumper is crucial to prevent damage to the onboard 5V regulator. In such cases, the 5V pin serves as an input, requiring connection to an external 5V power supply for proper IC operation.

4WD CHASSIS KIT:

Figure 5: 4WD Chassis Kit

The 4WD Chassis Kit serves as the foundational framework for the autonomous car model. Constructed from durable and lightweight aluminum alloy, it provides a robust platform for mounting the various components. The kit's four independent suspension arms, coupled with high-torque gear motors, empower the car with exceptional maneuverability and off-road capabilities. The 4WD system ensures optimal traction and control on diverse terrains, enabling the car to navigate uneven surfaces and obstacles with ease. Additionally, the kit's modular design facilitates seamless integration with other electronic components, including the microcontroller, sensors, and motor driver. The 4WD Chassis Kit's versatility, durability, and performance make it an ideal choice for constructing a reliable and capable autonomous car model.

NEO-6M GPS MODULE:

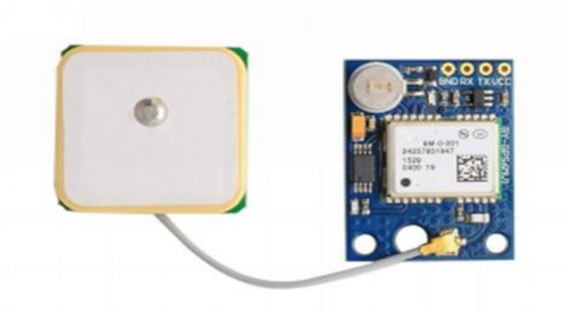

Figure 6: NEO-6M GPS Module

The NEO-6M GPS module serves as the project's navigation system, providing accurate positioning and timing information. This compact and high-performance module leverages a MediaTek MT3333 chipset and an active antenna to deliver exceptional sensitivity and fast acquisition times. Its support for multiple Global Navigation Satellite Systems (GNSS), including GPS, GLONASS, Bei Dou, and Galileo, ensures reliable positioning even in challenging environments. The NEO-6M's communication interface utilizes the ubiquitous UART protocol, enabling seamless integration with the Arduino Uno microcontroller. Moreover, its compact size and low power consumption make it ideal for integration within the autonomous car model.The NEO-6M GPS module's accuracy, reliability, and ease of use make it an indispensable component for precise navigation and positioning within the project. The NEO-6M's communication interface utilizes the ubiquitous UART protocol, enabling seamless integration with the Arduino Uno microcontroller.

BATTERIES:

Figure 6: 3.7V Battery

The 18650 3.7V battery plays a crucial role in powering the autonomous car model. With a compact cylindrical design and a nominal voltage of 3.7V, these lithium-ion cells offer a reliable and rechargeable energy source for the project. The high energy density and long-lasting performance of these batteries ensure extended operational times for the autonomous car, supporting continuous functionality during testing and demonstrations. The 18650 batteries' versatility and compatibility make them a popular choice for various electronic applications, providing a stable power supply to drive the motors, sensors, and microcontroller of the autonomous car. Their lightweight design and ample capacity contribute to the efficiency and portability of the overall system, enhancing the practicality and usability of the autonomous car model.

IV. RESULT

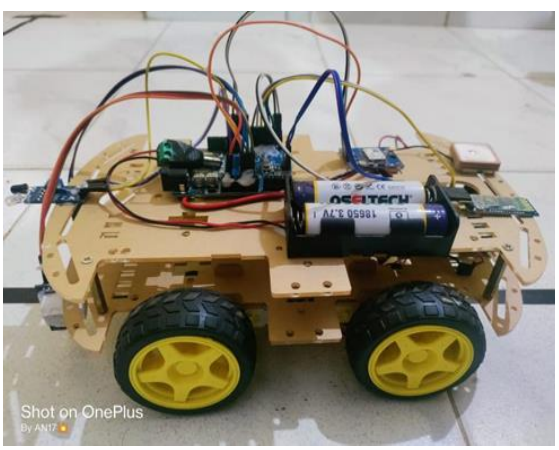

Figure 8: Autonomous Car Model

The project demonstrates the development of an autonomous car using an Arduino Uno board and several key components. These components include the HC-05 Bluetooth module, L298N motor driver, IR sensor, 2x3.7V batteries, and NEO 6M GPS module. The primary objective is to achieve autonomous navigation capabilities by combining IR sensors for lane and obstacle detection with GPS coordinates for destination-based travel.

The integrated software and hardware architecture enable both automatic and manual modes. When obstacles are detected, the system seamlessly transitions to manual control. Through a well-designed code structure, the car precisely follows specified coordinates to reach predefined destinations and then returns to the source.

The utilization of IR sensors for lane and obstacle detection, along with the integration of the GPS module for coordinate-based navigation, collectively makes this project a noteworthy demonstration of autonomous robotic navigation.

V. CONCLUSION

Autonomous driving holds immense promise for the future of mobility. By combining technologies such as GPS navigation, infrared sensors for obstacle detection, and seamless transitions between automatic and manual modes, we can create vehicles that enhance safety, convenience, and productivity. Consumers stand to benefit from reduced accidents, increased productivity during commutes, and improved mobility options. However, challenges remain, including technological advancements, consumer acceptance, and safety considerations. As we address these hurdles, the road ahead for autonomous vehicles looks exciting and transformative.

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