ISSN (Online) 2394-2320

International Journal of Engineering Research in Computer Science and Engineering (IJERCSE)
Vol 4, Issue 12, December 2017

Embeded Based Handpicking Robot Using Memes

[1] Sai Lakshmi, [2] T.Sravan Kumar
[1] M.Tech Student, [2] Associate Professor
[1][2] Dept Of ECE, Ellenki College of engineering &Technology, Patelguda, Patancheru, Medak (dist), India.

Abstract - **The primary point of this task is to plan and build up a successful and effective hand picking robot utilizing "MEMS" sensor for the impair individuals. In this undertaking versatile impedance control is proposed for a robot teaming up with a human accomplice, within the sight of obscure movement expectation of the human accomplice and obscure robot progression. Human movement expectation is characterized as the want direction in the appendage model of the human accomplice, which is to a great degree hard to acquire considering the non-straight and time changing property of the appendage display. Neural systems are utilized to adapt to this issue, in light of which an online estimation technique is created. The evaluated movement aim is coordinated into the created impedance control, which influences the robot to take after the given target impedance shows under the proposed strategy and the robot can effectively work together with its human accomplice, which is checked careful exploratory investigations.**

Keywords — Raspberry-pi,LPC2148, MEMS, Zigbee.

INTRODUCTION

Society had officially perceived the need of automated human cooperation to lessen human workload, costs, exhaustion risk and to develop the profitability close by with proficiency. With the improvement of the modern generation, most rising assembling assignments that are either excessively mind-boggling, making it impossible to mechanize or too overwhelming to control are unrealistic and even impractical to be managed independently by utilizing people or completely modernized robots. This sincerely prompts the prerequisite of the human and mechanical coordinated effort to execute assignments.Proficient and profitable impacts of obligations completed with the guidance of the human and robot joint effort depend upon on the perception that robot and people having a similar workhouse and have reciprocal focal points. The robots quality lies in their most appropriate successfully in executing out the ordinary obligations at a high speed with ensured execution. Though people with their psychological capabilities exceed expect ations in observation the onditions/circumstances, thinking and their capability to determine the issue. In human and robot coordinated effort, one of the fundamental basic issues is to influence the robot to comprehend the movement aim of its human accomplice so the robot can "effectively" work together with its human accomplice. In such manner, to influence the robot to track in a recommended direction isn't material. In this task we consider an 'arm incapacitated' human teaming up with 'robot arm' for instance/contextual analysis for our human and robot joint effort. As clarified over the fundamental issue is to influence The robot to comprehend the goal of a human for the 'arm' development. Until unless the robot refines its movement as per the power applied by its human accomplice, it won't work as per its human accomplice intentions' (arm development as proposed by the human).

LITERATURE SURVEY

Robot is extremely helpful for humanity in doing questionable errand and there are distinctive methods for way to deal with control the robot like voice or remote correspondences however invalid of them are valuable in giving amicable condition to handicap people. Thus we propose a framework in which robot can be worked motion. To play out its allocated undertakings, the robot moves parts, items, devices and unique gadgets by methods for modified movements and focuses. The mechanical arm performs movements in space, its capacity is to exchange questions or devices from point to point, as trained by the controller. In assembling industry and atomic industry, a substantial portion of the work is tedious and sensible use of robotization will definitely bring about ideal use of machine and labor. Remote cam is the additional favorable position of the proposed framework. The proposed model will convey between the controller and the execution and it will likewise supplant the conventional joystick by the usage of client hand glove control. The "MEMS" sensor inside the glove can detect the development of fingers and the sensor yield is given to the controller. The controller sends the signs and as indicated by the signs the engine is running which changes the robot developments.

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PROPOSED SYSTEM

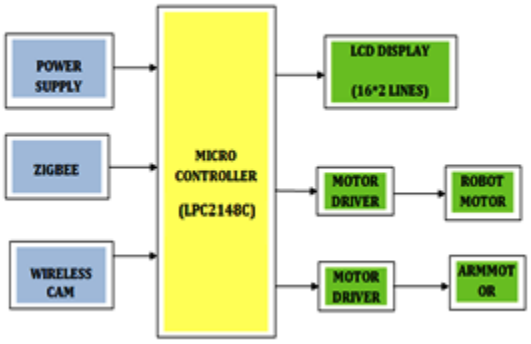

Fig-1: ROBOT section Block Diagram

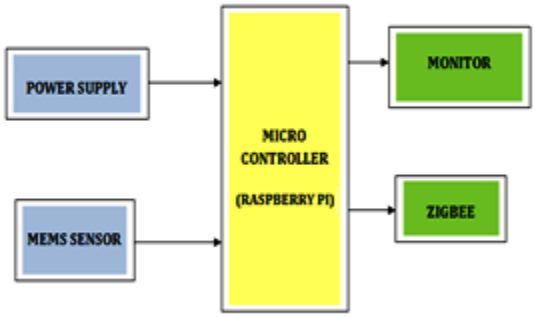

Fig-2: TRANSMITTER section block diagram

Fig-3:CAM Receiver Block Diagram

METHODOLOGY

Micro controller:

This section forms the control unit of the whole project. This section basically consists of a Microcontroller with its associated circuitry like Crystal with capacitors, Reset circuitry, Pull up resistors (if needed) and so on.

The Microcontroller forms the heart of the project because it controls the devices being interfaced and communicates with the devices according to the program being written.

Raspberry Pi:

The Raspberry Pi delivers 6 times the processing capacity of previous models. This second generation Raspberry Pi has an upgraded Broadcom BCM2836 processor, which is a powerful ARM Cortex-A7 based quad-core processor that runs at 900MHz. The board also features an increase in memory capacity to 1Gbyte.

ARM7TDMI:

ARM is the abbreviation of Advanced RISC Machines, it is the name of a class of processors, and is the name of a kind technology too. The RISC instruction set, and related decode mechanism are much simpler than those of Complex Instruction Set Computer (CISC) designs.

Liquid-crystal display (LCD)

It is a flat panel display, electronic visual display that uses the light modulation properties of liquid crystals. Liquid crystals do not emit light directly. LCDs are available to display arbitrary images or fixed images which can be displayed or hidden, such as preset words, digits, and 7-segment displays as in a digital clock.

USB Camera:

USB Camera is connected to the USB slot of the board, for live video streaming and if incorrect PIN is entered, it will capture the user's picture through the camera and sends it to the authorized person's mail using USB Wi Fi r which connects the device 10 the router to access it over I F network, At the users end, we will have live videos and captured user's pictures on the display who entered the wrong pin.

Fig.4: Webcam

PC Monitor:

The HDMI-VGA cable is attached updated raspberry-pi and the LJ R interface of the cable is attached updated. The face of the character getting captured can be visible on up-to-date. The Raspberry Pi has a HDMI port which

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you can plug without delay into a display or tv with an HDMI.

ZIGBEE:

Zigbee modules feature a UART interface, which allows any microcontroller or microprocessor to immediately use the services of the Zigbee protocol. All a Zigbee hardware designer has to do in this case is ensure that the host's serial port logic levels are compatible with the XBee's 2.8- to 3.4-V logic levels. The logic level conversion can be performed using either a standard RS-232 IC or logic level translators such as the 74LVTH125 when the host is directly connected to the XBee UART. The X- Bee RF Modules interface to a host device through a logic-level asynchronous Serial port. Through its serial port, the module can communicate with any logic and voltage Compatible UART; or through a level translator to any serial device. Data is presented to the X-Bee module through its DIN pin, and it must be in the asynchronous serial format, which consists of a start bit, 8 data bits, and a stop bit. Because the input data goes directly into the input of a UART within the X-Bee module, no bit inversions are necessary within the asynchronous serial data stream. All of the required timing and parity checking is automatically taken care of by the X-Bee's UART.

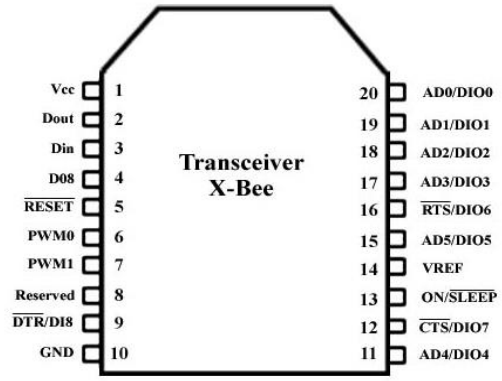

Fig .5: ZIGBEE pin diagram

MEMS:

Micro-Electro-Mechanical Systems (MEMS) is the integration of mechanical elements, sensors, actuators, and electronics on a common silicon substrate through micro fabrication technology. While the electronics are fabricated using integrated circuit (IC) process sequences (e.g., CMOS, Bipolar, or BICMOS processes), the micromechanical components are fabricated using compatible "micromachining" processes that selectively etch away parts of the silicon wafer or add new structural layers to form the mechanical and electromechanical devices. MEMS promises to revolutionize nearly every product category by bringing together silicon-based microelectronics with micromachining technology, making possible the realization of complete systems-on-a-chip. MEMS is an enabling technology allowing the development of smart products, augmenting the computational ability of microelectronics with the perception and control capabilities of micro sensors and micro actuators and expanding the space of possible designs and applications. Microelectronic integrated circuits can be thought of as the "brains" of a system and MEMS augments this decision-making capability with "eyes" and "arms", to allow micro systems to sense and control the environment. Sensors gather information from the environment through measuring mechanical, thermal, biological, chemical, optical, and magnetic phenomena. The electronics then process the information derived from the sensors and through some decision making capability direct the actuators to respond by moving, positioning, regulating, pumping, and filtering, thereby controlling the environment for some desired outcome or purpose. Because MEMS devices are manufactured using batch fabrication techniques similar to those used for integrated circuits, unprecedented levels of functionality, reliability, and sophistication can be placed on a small silicon chip at a relatively low cost.

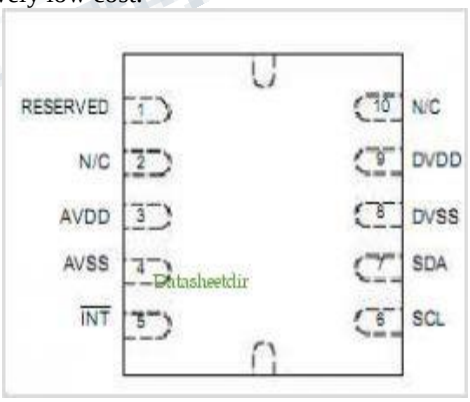

Fig .6: MEMS IC

DC Motor:

A DC motor relies on the fact that like magnet poles repels and unlike magnetic poles attracts each other. A coil of wire with a current running through it generates an electromagnetic field aligned with the center of the coil. By switching the current on or off in a coil its magnetic field can be switched on or off or by switching the

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direction of the current in the coil the direction of the generated magnetic field can be switched 180°.

Fig .7: DC Motor

Motor driver (L293D):

DC motors are typically controlled by using a transistor configuration called an "H-bridge". This consists of a minimum of four mechanical or solid-state switches, such as two NPN and two PNP transistors. One NPN and one PNP transistor are activated at a time. Both NPN and PNP transistors can be activated to cause a short across the motor terminals, which can be useful for slowing down the motor from the back EMF it creates. H-bridge. Sometimes called a "full bridge" the H-bridge is so named because it has four switching elements at the "corners" of the H and the motor forms the cross bar. The switches are turned on in pairs, either high left and lower right, or lower left and high right, but never both switches on the same "side" of the bridge. If both switches on one side of a bridge are turned on it creates a short circuit between the battery plus and battery minus terminals. If the bridge is sufficiently powerful it will absorb that load and your batteries will simply drain quickly. Usually however the switches in question melt.

CONCLUSION

The task "Inserted based hand picking robot" has been effectively outlined and tested.Integrating highlights of all the equipment segments utilized have created it. Nearness of each module has been contemplated out and put precisely along these lines adding to the best working of the unit. Also, utilizing exceedingly propelled IC's and with the assistance of developing innovation the task has been effectively executed.

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