

Fire Fighting Robot

Prof. Sachin Komble, Siddhi Chaudhari, Ishwari Chothave, Kunal Dalvi, Dharmraj Dange, Sameer Dhurate,

Department of Mechanical Engineering,

Vishwakarma Institute of Technology, Pune 411037, Maharashtra, India

Abstract— Robots are very popular in the era of automation. We can see that even very small things are done by robots. When it comes to extinguishing fire, it becomes a very risky task for human beings. Hence, here is the real use of robots. By taking these things in consideration, we proposed a robot which works autonomously and perfectly for extinguishing fire. This will definitely reduce the risk of humans. This study presents an autonomous robot that works to extinguish fire which is controlled from smartphone using sim module.

Keywords— Robot, IOT.

I. INTRODUCTION

This work is all about the system which can be considered as the perfect solution for the compact and risky fire zones. The robot is built in such a way that it has the capability to put out fires in critical conditions such as where the risks to human lives are. The rubber wheels help to run the robot on the ground and the special type of wheel rotation helps to take turns without using any complex turning mechanism. The robot is full of Sensors which helps to extinguish fire and also collect the smoke. In this there is a camera module for detecting if any human is looked at in fire also there is smoke collector to clearification for camera. By maintaining the safe distance it fires water on the fire and helps to reduce the fire. Because of this autonomous robot no one will go in difficult conditions. The robot will individually handle the fire.

II. LITERATURE REVIEW

[1] They worked on the cylindrically shaped robot made of Aluminium frame. The height of which is roughly around 80 cm, and the diameter is 40 cm. Its features include avoiding obstacles, remote monitoring and detection of fire. Its three flame sensors of the firefighting robot are used for building the fire detection system. Fire detection for firefighting robots is proposed using the adaptive fusion method. We are improving our approach to make it suitable for fire detection using computer simulations. We used sensor-based programming to program the fire detection and suppression process. In case of a real fire incident, the robot can use the technology of the proposed fire detection

system to identify the fire source, move to the fire source and extinguish the fire.

[2] Fire Detection and Fighting Robot and Program is combat technology based on the sensor. They created IR sensor-based modular obstacle detection at minimal cost to the robot's ultrasonic sensor. They envision using the portable and convenient Human Firefighting Robot Interface to create a generic user interface (GUI) based system status using the touch screen.

[3] Robot named QRob is intended to be smaller in size than to make small fires easier, other traditional fire-fighting robots' entrance point for a narrower depth of fire suppression space. To prevent from colliding with nearby objects and obstructions, while a flame it, QRob also has an ultrasonic sensor.. QRob was the outcome. Showcasing knowledge of how to locate fires remotely and automatically put out a certain type of fire distance using mobile operated by the user.

[4] This research proposes and develops a novel indoor fire fighting robot concept. It has the capacity to traverse a variety of indoor flooring surfaces, including stairs. Using various thermal insulation techniques, it can endure temperatures as high as 700o C for roughly 60 minutes. It delivers visual and audio data to the control unit for description of the fire environment inside the structure in addition to communicating with trapped and hurt victims inside the visible fire. With the aid of a remote control device, several of those firefighting robots can be deployed to operate together.

[5] They looked at the robots' current state and their specifications. Then they highlighted their issues and topics. The ability of group robots to cooperate is the key to the next generation of fire fighting and rescue robots. Better is the usable fundamental unit development. Public support is required, and global cooperation is crucial. Additionally, regular and close communication between researchers and firemen is required.

[6] This particular model is an IOT-based firefighting robot. Once they are informed, the authorities can use an automatic receiver placed to visualize the location of the fire and contact anyone trapped. The robot may be instructed to travel, turn on its water pump or carbon dioxide pump depending on the type

of fire, and do so over great distances. The installed sensors that produce a graph for analysis allow for the determination of the type of fire and carbon monoxide level. The analysis is helpful in providing safety authorities with further details about the quantity of toxic gasses inhaled over time by residents of the affected area so they may take the necessary steps to undo the harm.

[7] Here, a firefighting robot with an extinguishment platform is created. The "Rashed tree," often referred to as "Kerosene wood" locally, provides the material for the robot's basis. The water reserve has a 1 liter maximum capacity. In order to effectively put out a fire, a water spreader is employed. The usage of water spreaders is observed to significantly lessen the water's velocity. To find the fire and measure the distances between it and it, two sensors—the LM35 and the Arduino Flame Sensors—are employed. Through analogue readings from the serial monitor, the sensitivity of these sensors is verified throughout a range of daytimes and distances.

[8] In this project, they create a robot that can find and put out fire in a specific setting. The robot moves around the arena and avoids any pitfalls on its journey. Additionally, a live stream and map depiction were offered so that, in the event of any anomalies, people as well as the robot could see the process of putting out a fire. This project has lots of potential for growth. For instance, allowing the robot to move between floors is a good idea because burning houses or other structures typically have multiple levels.

[9] This paper introduces CeaseFire, a firefighting robot created to assist firefighting workers in the field. The project intends to lower the risk to people's lives from potential fire hazards. The robot can spray water and carbon dioxide to put out fires, use mist sprays to shield itself from burns, and broadcast live video frames of the fire spots.

[10] The main goal of this paper is to create a fire-suppression and detection robot. Disasters can be prevented with little risk to human life by inventing and implementing an autonomous robot capable of spotting and putting out fires. In this study, we are presenting an example of an autonomous robot that can locate interior fires and move toward them to use carbon dioxide to put them out. The design was successfully applied to a robot with four wheels. The front of the robot's chassis received the 3D printed mount. To guard against damage from external fire sources, the battery is housed inside the robot. A servo motor had an ultrasonic sensor installed directly on it. Multiple flame sources were successfully found by the robot, and they were put out from a safe distance. To extend the operational period and enable effective flame source detection, the robot's speed was slowed down to the necessary level. The threshold settings for the flame sensor must be manually determined.

III. DESIGN

We designed a 3D model of the robot in SolidWorks software. Also, the 3D model gives a perfect overview of the robot base. Also, we have put the correct dimensions of the chassis of the robot. The dimensions and specifications of the robot and all its components are described in table 1. The velocity of the water with which it extinguishes fire and its flow rate is calculated below.

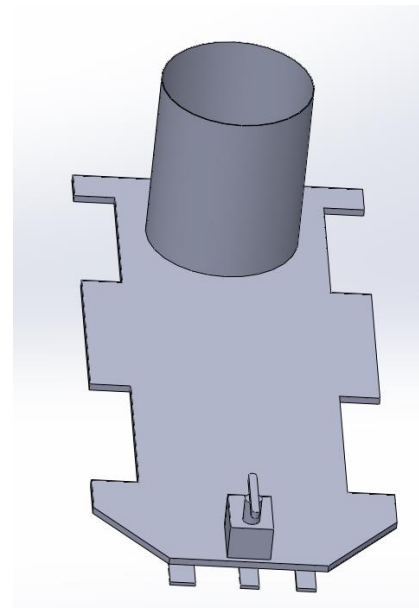


FIG 1: 3-D Design Of Chassis

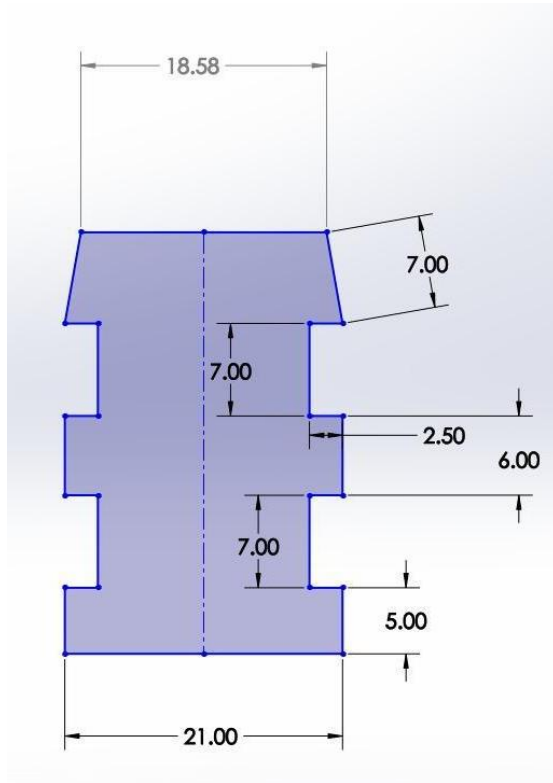


FIG 2: Dimensions of chassis

Table 1: Design specifications of robot and its components

Sr. No.	Component	Measurement
1	Total Weight	350 g
2	Velocity of water	18.7 cm/s
3	Discharge/Flow rate	9.4 cm ³ /sec
4	Water Range	22 cm
5	Flame sensor range	5-30 cm
6	Tank diameter	7cm
7	Tank height	11cm
8	Pipe length	28 cm
9	Pipe Diameter	0.8 cm
10	Wheel Diameter	6 cm

Calculations:

1. Velocity of water: It is the length covered by flowing fluid in 1sec.

$$\text{Velocity} = \text{Displacement/Time}$$

$$\text{Velocity} = 28/1.5$$

$$\text{Velocity} = 18.7 \text{ cm/sec}$$

2. Flow rate or Discharge of water (Q): It is the volume of fluid flowing through a pipe per second.

$$Q = \text{Area} \times \text{Velocity} \text{ or } Q = \text{Volume/time}$$

$$\begin{aligned} \text{Area of pipe} &= (\pi/4)D^2 \\ &= 0.7853 \times (0.8)^2 \\ &= 0.5026\text{cm}^2 \end{aligned}$$

$$\text{Velocity of water} = 18.7\text{cm/sec}$$

$$\begin{aligned} Q &= A \times V \\ Q &= 0.5026 \times 18.7 \\ Q &= 9.4 \text{ cm}^3/\text{sec} \end{aligned}$$

IV. WORKING FLOW

An algorithm was developed to describe the behavior of a robot equipped with a fire fighting system. A flow chart of the operation of the robot and sensor assembly is shown in Figure 4 and flow chart of detecting of fire is shown in Figure 5. It is mainly based on Arduino Uno and Node MCU platform. An Arduino Uno board and a Node MCU are employed on top of the robot, as shown below in the robot's circuit design. One is used to control wheels of the robot, the other receives input from sensors and performs specific tasks upon request. Hardware and software requirements and their usage are described in the section below.

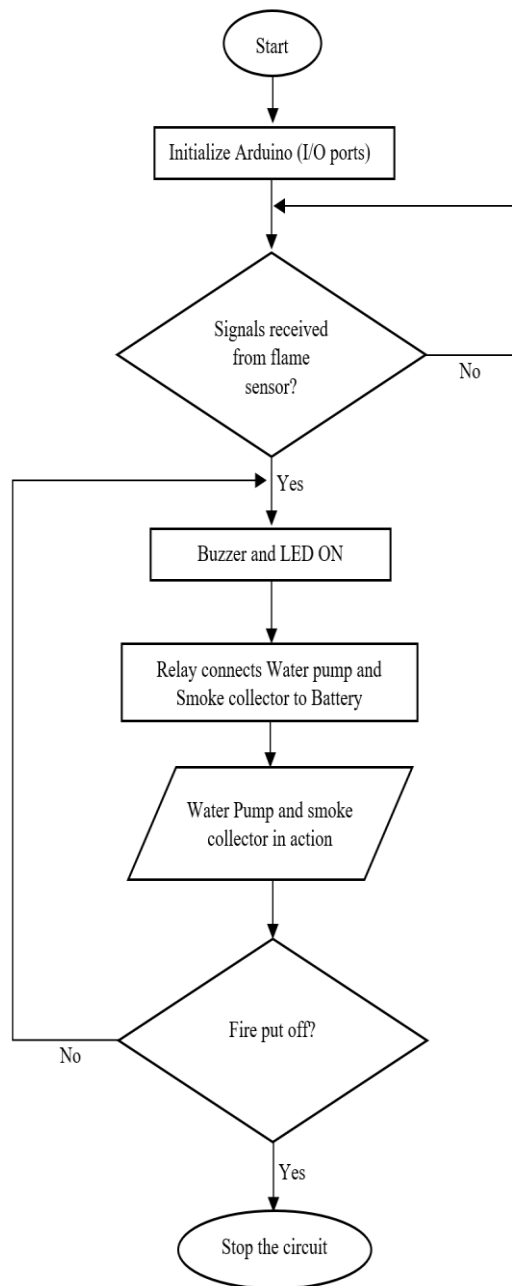


FIG 3: Flow Chart of working of Arduino

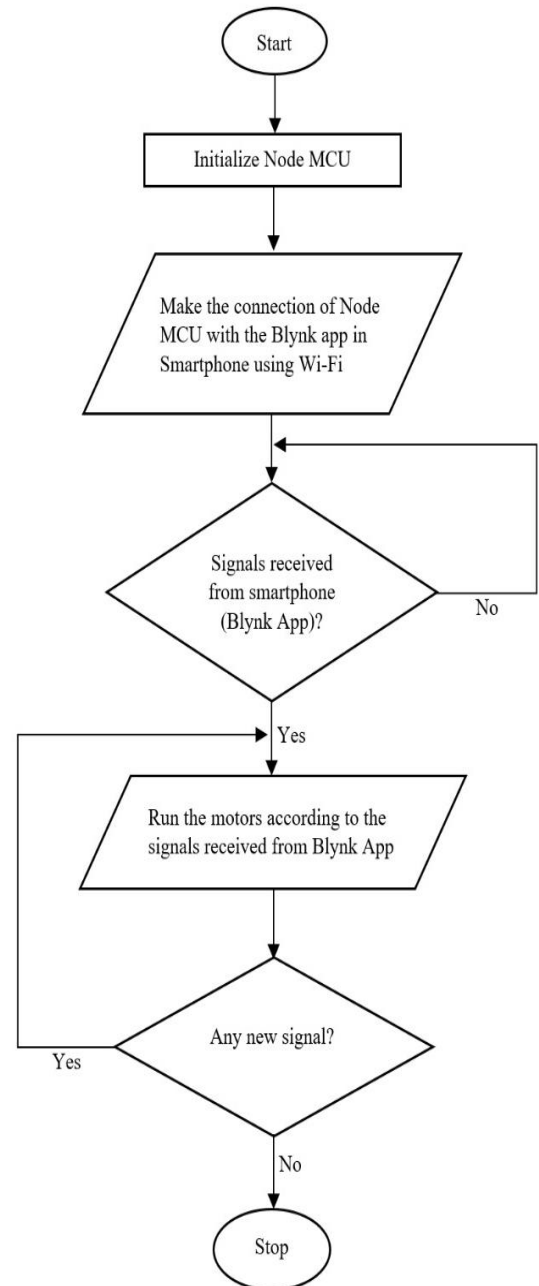


FIG 4: Flowchart for working of Node MCU

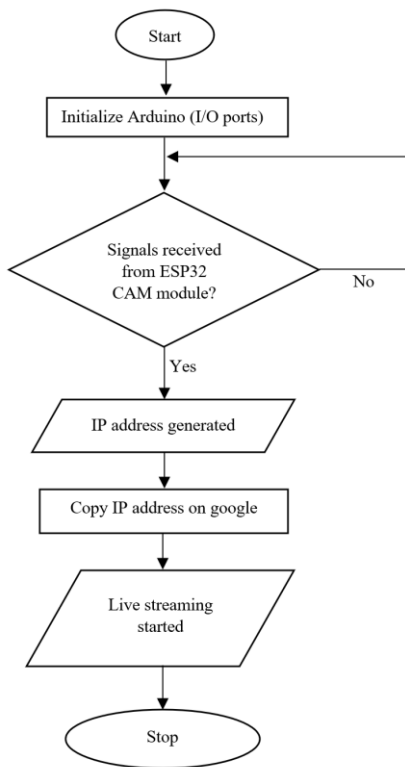


FIG 5: FlowChart for working of Camera module

Hardware Requirements:

The system's hardware is primarily based on the Arduino Uno and Node MCU platforms. The robot circuit design has an Arduino Uno board and a Node MCU placed on top of the robot as shown below. One is used to control the wheels of the robot and the other receives input from sensors and performs specific tasks as requested. Following are the hardwares we used.

- **Arduino UNO R3:** The microcontroller used in the Arduino UNO platform is ATmega328. All sensors and actuators excluding DC motors are connected to the Arduino board. All the actions like detection of fire and taking action on it are done by this microcontroller according to code.
- **Node MCU:** The microcontroller is based on ESP-12 module of ESP8266. We used this microcontroller for robot movement and connected this robot to a smart phone by using the WIFI.
- **L298N:** L298N is used to control the speed and direction of two DC motors simultaneously. This module can drive DC motor with voltage from 5 to 35 V and peak current up to 2A.
- **18650 Lithium Ion Battery:** We are using this rechargeable battery for powering our robot. This is the primary battery type used in portable appliances and electric vehicles.
- **12 Volt Water Pump:** We are using this for supplying water to pipe which mounted on servo motor.
- **Buzzer:** It sounds after the fire gets detected. It is used as an emergency indication.
- **LED:** It is used as an indicator when a fire is detected. It blinks after detection of fire.
- **Servo Motors:** It is used to control the angle of water pipe and hence controlling the water direction. Also it is used to control the angle of the camera module by which we can get different views of the camera on our display.
- **Flame sensor:** It detects the flame and sends signals to Arduino board then the arduino board takes action according to that.
- **9 Volt Power:** The 9 Volt Battery is a electric battery that provides a nominal voltage of 9 volts. This power supply is only for Node MCU.
- **DC motors:** It is used to forward and backward movement of the robot.
- **5V relay:** 5V relay is automatic switch, widely used in automatic control circuit, control high current with low current signal. Relay Signal Input Voltage Range 0 to 5V.
- **Water Tank:** We are using this water tank for water storage and supply to the pipe when it required.
- **LCD Display:** It is used for showing the current condition. Like emergency cases go to the safe zone and this type of messages are shown by display.
- **ESP CAM 32 Modul:** It capture the live images or video of the surrounding situations and shows on our

ip address on our mobile phone. This also works on the wifi module.

- 12V DC Fan: This fan we used for suction of the smoke caused by the fire.

Software Requirements:

The entire system is designed and developed using the Arduino IDE software and the Blynk app. These tools play a very important role in the software part of the project.

- Arduino IDE: The popular open source integrated development environment (IDE). This allows the user to program her and control compatible cards according to the requirements. The Arduino board is programmed using the Arduino IDE to read sensor inputs and direct actuators to control the wheels and robotic arm. The function and working with it becomes more interesting as it is also compatible with the Blynk app that controls the mechanism.
- Blynk App: This is the digital platform that allows users to create a graphical user interface (GUI) by dragging and dropping its widget onto their smartphone. This is used for real time control of the robot's movement, speed and orientation.

V. METHODOLOGY

Special material protects the robot body its components from the fire. This allows it to be used for extinguishing in any situation. This system uses different sensors to get inputs and perform action. After the fire is extinguished, the pump, smoke collector, relay and flame sensors are turned off which saves battery. Signals from these sensors are provided to microcontroller and it drives the robot and nozzles connected to the water pump. So when the robot detects a flame, the flame sensor sends a signal to the Arduino board and the board resolves. We are using a camera module to get the live images of the situation around the robot. This will help the controller to know the current condition surrounding the robot. The live streaming of the views of the camera can be seen on the computer. This camera is fixed on the servo motor which helps for movement of the camera at different angles and for getting the different views through it. Obviously there will be a lot of smoke around the robot due to the fire which will create hindrance for the camera to get the proper images. It will get blurry images due to smoke. Hence we are using a smoke

collector for collecting smoke around the robot and as a result, the camera can collect clear images around it. Meanwhile, the relay is turned off, the circuit is opened, and the water pump is stopped when the fire is extinguished, the circuit is automatically cut off and everything stops. The system is semi-autonomous as all the functions are performed automatically and only movement mechanism is controlled by the user using the mobile phone. The design concept of the system is described in two phases. The first stage includes a robot with sensor mounts and the second stage includes the Blynk app. We used a cloud database to store the actions. There are two types of boards that use the first is an Arduino and the second is a Node MCU. Arduino is used for all flame detection and water pump control, and an Node MCU is used to control the bot. The most interesting fact about the project proposed in this document is that the range is the same as that of the WiFi, so users get the flexibility to operate this robot from their mobile phones with wide range. For example, let's say a cylinder of LPG caught fire then in such cases, firefighters enter the house and extinguish the fire, which is a very risky task. In this case, the Fire Robot enters house and safely extinguishes the fire. We also focussed to make it trustworthy to the common public and to provide its user manual as appropriate.

VI. IMPLEMENTATION

Physical development of the project has been completed including circuit fabrication and 3D design for the project. The design of the robot and the layout of the sensors in the system were designed using SolidWorks and AutoCAD. Both circuit boards are precisely programmed to operate each sensor and according to the conditions available. The circuit runs in two phases, the first phase contains the mobile phone controlled DC motor assembly which is connected to the node MCU. This mechanism is shown in Figure 1. The second phase is for control of the remaining units. Its mechanisms and operations is shown in Figure 2.

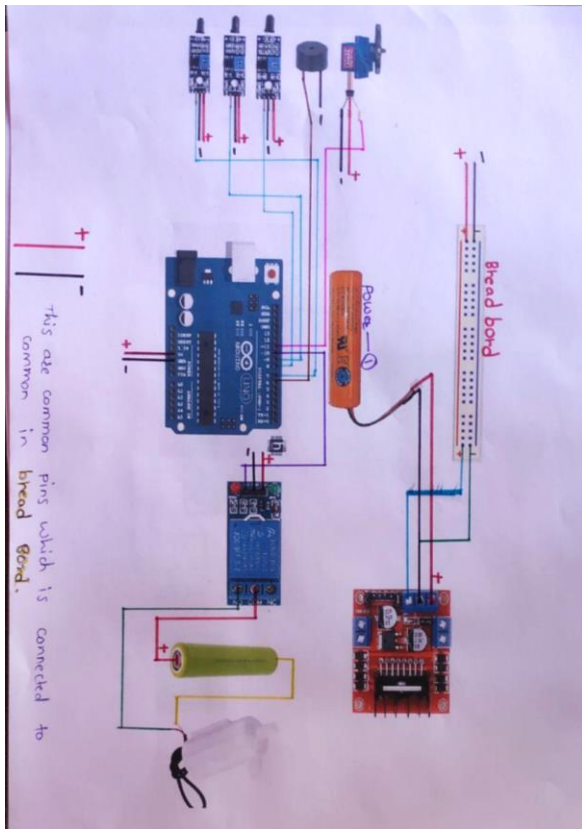


FIG 6: Circuit diagram of Arduino

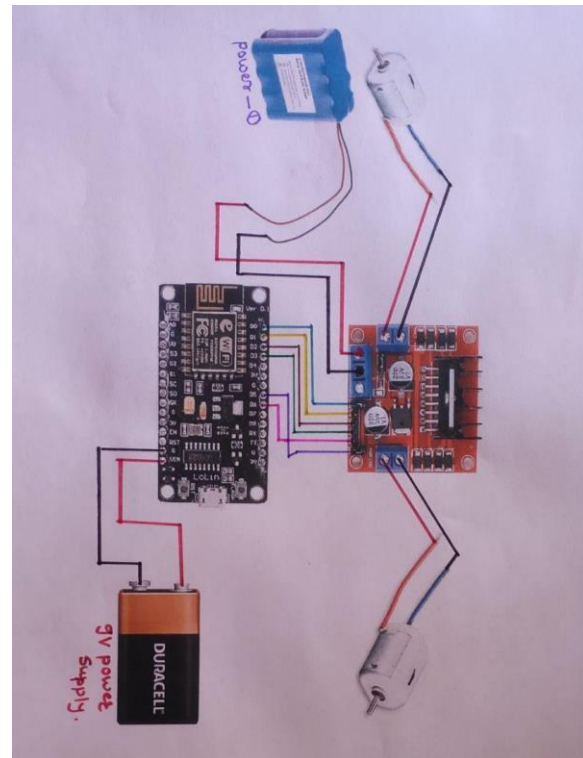


FIG 7: Circuit diagram of Node MCU

VII. RESULT AND DISCUSSION

After assembling all the components and sensors on the chassis, we have uploaded the code in node MCU and Arduino UNO. Then we have successfully tested the working of the project. The project worked successfully. All the sensors got perfect inputs and all the signals were perfectly sent to respected actuators. For testing purposes we have burned a piece of paper and operated the robot to extinguish the fire. The smoke was perfectly collected and also the camera module took the perfect view around the robot. The safe zone and emergency zone are displayed on the LCD display according to the fire conditions. All these operations were perfectly performed by the robot. All its results are shown in the images below.

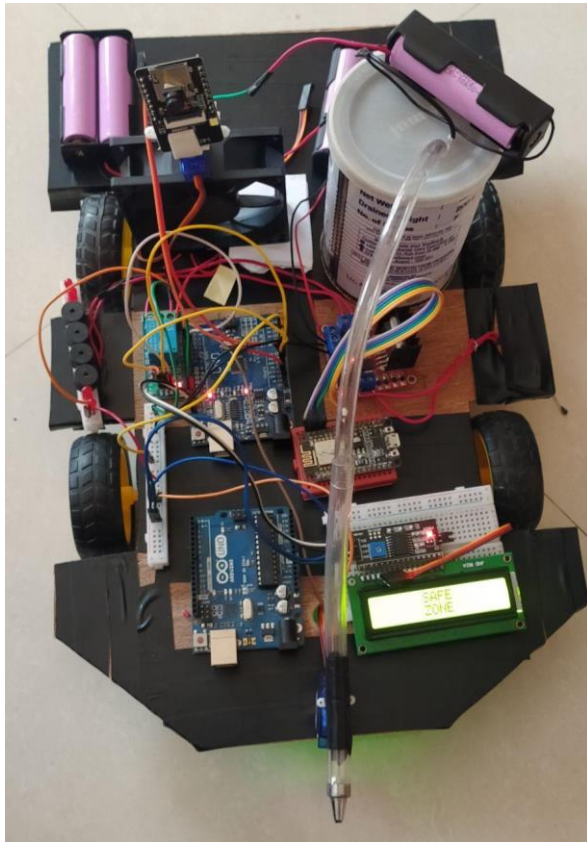


FIG 8:Top view of Fire Fighting robot

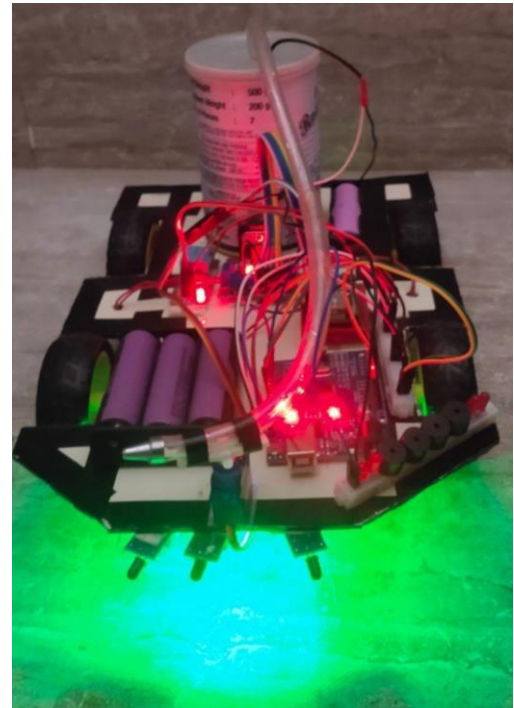


FIG 10 :Front View of Fire Fighting Robot

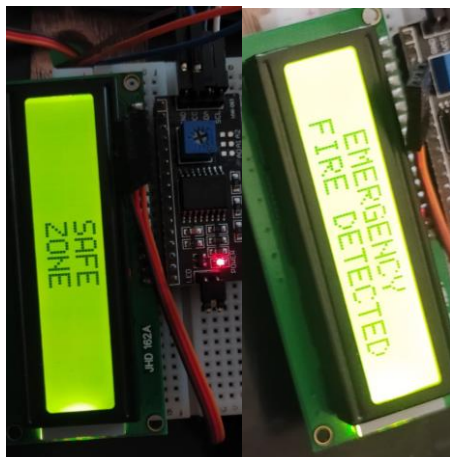


FIG 9 : LCD display in working mode

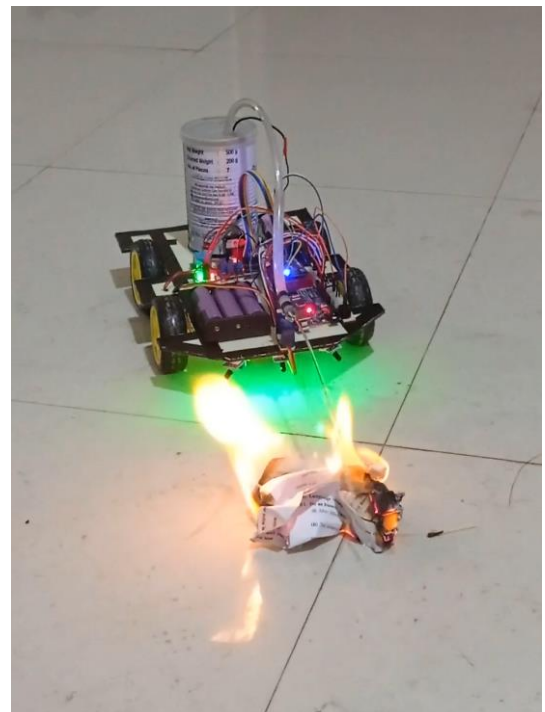


FIG 11: Robot in working mode

VIII. CONCLUSION

The most efficient result of our project is its successful outcome. This project is really power efficient, effective and works fine. 'A Firefighter Robot' proposed in this document is a solution to all the real world problems. The way the project works is that it is programmed to work according with signals from sensors and signals from mobile phones. The microcontroller used in the Arduino UNO reads the input from the flame sensor and the node MCU reads the input from the mobile phone. Arduino controls the trip time of relay and sends signal to the pump to take appropriate action. Its unique property is that it works under critical conditions and saves lives. Therefore the robot can also be called as a rescue robot. As a result, the project proved to be highly innovative and effective in reducing the risk of firefighters.

- [10] J. Suresh, "Fire-Fighting Robot," in *2017 International Conference on Computational Intelligence in Data Science (ICCIDS)*, New York, US, 2017.

IX. REFERENCES

- [1] K. Su, "Automatic Fire Detection System Using Adaptive Fusion Algorithm," in *IEEE International Conference on*, Taiwan, 2006.
- [2] T. L., "Develop a Multiple Interface Based Fire Fighting Robot," in *Proceedings of International Conference on Mechatronics*, Japan, 2007.
- [3] M. Aliff1, "Development of Fire Fighting Robot (QRob)," (*IJACSA International Journal of Advanced Computer Science and Applications*), vol. 10, pp. 142-147, 2019.
- [4] A. A. AlHaza Ta*, "New Concept for Indoor Fire Fighting Robot," in *World Conference on Technology, Innovation and Entrepreneurship*, 2015.
- [5] "Present Status and Problems of Fire Fighting Robots," in *National Research Institute of Fire and Disaster Japan*, Tokyo.
- [6] M. Kanwar1, "IOT Based Fire Fighting Robot," in *IEEE*, Vellor, Tamil Nadu, 2018.
- [7] T. Rakib, "Design and Fabrication of an Autonomous Fire," in *5th International Conference on Informatics, Electronics and Vision (ICIEV)*, Bangladesh, 2016.
- [8] A. Hassanein, "An Autonomous Firefighting Robot," Kuwait, 2015.
- [9] S. Mittal1, "CeaseFire: The Fire Fighting Robot," in *International Conference on Advances in Computing, Communication Control and Networking (ICACCCN2018)*, Ghaziabad, Uttar Pradesh, India, 2018.