Operating an Autonomous Vehicle via Raspberry Pi

Prof. Ayub Mulani *Guide, Dept. of Electronic and Telecommunication Engineering, Keystone School of Engineering,* Pune, India

Anmol Maske
Student, Dept. of Electronic and Telecommunication Engineering Keystone School of Engineering
Pune, India

Onkar More
Student, Dept. of Electronic and Telecommunication Engineering Keystone School of Engineering
Pune, India

Fahad Shaikh
Student, Dept. of Electronic and Telecommunication Engineering Keystone School of Engineering
Pune, India

Abstract— **The Project pursuits to construct a monocular imaginative and prescient independent vehicle prototype the use of Raspberry Pi as a processing chip. A Pi camera is used to offer important real-time data from the actual global to the vehicle. The vehicle can attain the given destination competently and intelligently, as a result, heading off the chance of human errors. Many current algorithms like lane detection, object detection are blended to offer the significant to control the vehicle. This could prove out to be a boon with inside the car industry. It could assist lessen the attention required and pressure placed up at the mind, whilst additionally minimizing injuries because of careless or disobedient driving.**

Keywords— Autonomous Car, Raspberry Pi, Object Detection, Ultrasonic Sensor, IR Sensor

I. INTRODUCTION

Road Safety is one of the fore most troubles confronted globally. Every 12 months five million deaths is reported worldwide. These deaths are majorly due to human negligence and human error. The maximum not unusual place motives for street injuries are over speeding, drink & driving, distractions to driver, crimson light jumping, and lane converting, and warding off protection gears like seat belts. Traditional and guide motors require entire human manipulate and interest over them even as travelling, wherein a maximum of the humans make errors which subsequently effects into, into street injuries. To conquer this problem Autonomous cars era comes into the picture. Autonomous cars are vehicles that can sense their environment and circulate properly without human input. Various high-end sensors are located in extraordinary elements of the auto which detects its surroundings and sends the statistics to the High-performance computing gadgets which then instructs the car to observe specific direction and take selections. Majorly with the assistance of video cameras, the car detects the visitor's lights, street signs, pedestrians, and different motors on the street and sends the actual time photographs to the processor. Machine learning knowledge is typically used for notion and decision-making actual time. The algorithms want to make the selections inside a fragment of a second for making use of a break or to make a flip proper or left. The primary focus of the undertaking

is to layout and broadens a low-value prototype of the autonomous car which makes use of Raspberry Pi because the middle functioning unit and makes use of sensors and device gaining knowledge of the era. The car makes use of the middle processing unit as Raspberry pi, which is interfaced with the 8MP Pi digital digicam module, which feeds the captured photographs to the raspberry pi. Based on which detection like street lanes, visitors' signals, boundaries are finished and instructions are shipped to function the auto and observe designed direction on our self-made track, which facilitates vehicle to tour to special region cautiously and timely.

II. PROBLEM STATEMENT

Non-self sufficient cars were round for an at the same time as, and consistent with an internet study, the share of injuries due to human mistakes may be very high. Every year, nearly 1.three million human beings die in street injuries across the world, a median of three, 287 deaths consistent with the day. When it involves India, the variety of human beings killed in street injuries in 2013 by myself became 137,000. Speeding is a severe offense. The root reasons of those accidents are speak me at the phone, riding at the same time as intoxicated and violating site visitor's laws, and the numbers are regularly increasing, posing a severe threat. No rely on how tough we strive to elevate focus approximately site visitors guidelines and the significance of keeping a wholesome riding environment, incidents keep arising without warning. Human errors can by no means be absolutely removed; however accidents ought to be avoided. And on this situation, generation has definitely stored the day. The improvement and enhancement of this generation has visible an exponential increase in the latest years, beginning from the very early radar-primarily based totally collision detection to the latest generation. Self-riding cars are one of the maximum talked-approximately technologies with inside the present day era. What became as soon as only a dream has grown to be a reality.

III. LITERATURE SURVEY

The version proposed via way of means of Gurjashan Singh Mohammad Dawud Ansari and Pritha G[1] upta in developing a prototype of self-reliant vehicle includes implementation of lane detection set of rules in conjunction with

impediment detection. Their venture pursuits to construct a monocular imaginative and prescient self-reliant vehicle prototype that's able to achieving at a particular destination

Truong-Dong Do, Minh-Thien Duong [2], proposed a monocular imaginative and prescient-primarily based independent vehicle prototype with the use of deep studying on Raspberry Pi. Convolution Neural Networks (CNNs) have proven exceptional effects on this domain. The foremost purpose in the back of those exceptional effects is their potential to analyze tens of thousands and thousands of parameters with the use of big information. In this work, authors have centered on locating a version that without delay maps uncooked input pictures to a are expecting steerage perspective as output the use of a neural network. The CNN version parameters were skilled via way of means of the use of information accrued from car platform constructed with RC vehicle, Raspberry Pi 3 Model B computer and the front going through the camera

In Saha Anik, Dipanjan Das Roy, TauhidulAlam and Kaushik Deb [3] targets to transform the photo from RGB layout to gray-scale layout. Then the flood-filling set of rules was implemented to label the linked components. Then the largest linked issue is extracted that is not anything the lane

H.Yoo, U.Yang, and K. Sohn generates lane gradient maximized photograph from a color photograph primarily based totally on linear discriminate analysis. This produces sturdy edges to the lane boundary in numerous illuminations. Then Canny edge detector is implemented to get edge photograph. After edge detection Hough transform is implemented to get preliminary lane detection. The Hough transformation can constitute curved lanes, so curve becoming is used for detecting curved lanes. Three parameters of the quadratic curve are used to estimate the lane model. For the primary body the training records is given manually and for remaining frames the training records are up-to-date for adapting illumination changes

A complicated selection primarily based totally mechanism is crucial to make sure secure navigation for self-sustaining cars with inside the unsure surroundings. In this paper, they focus on detection of pedestrians, vehicles, road signs using image processing and machine learning. To make sure disciplined riding with inside the world of self-sustaining cars, pace manage in step with the terrain kind wishes to be specified. They have proposed lane detection and speed control algorithms

"Implementing Canny edge detection algorithm for noisy image" Authors of this paper have essentially defined use of Edge Detection and particularly focus on Canny Edge detection and how the noise-reducing approach is critical due to the fact conventional Canny edge detection is very sensitive to noise. It offers the maximum notable effects in a robust surrounding and produces optimum results.
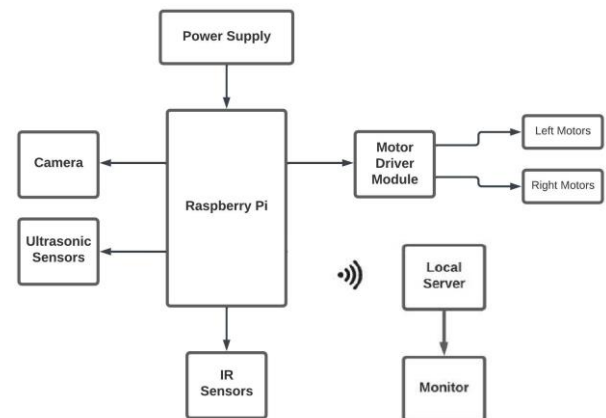
IV. METHODOLOGY

A. Arichitecture

Fig. 1: Block Diagram of the model

The model prototype it's advanced targets to position into impact automation through manner of approach of handling obligations along with self-using through lane line detection, save you sign and location traffic signal detection, and fore collision avoidance. This prototype entails numerous sensors prepare operating simultaneously. The IR sensors are linked to 2 of the front ends of Raspberry Pi. It is used for detection of the lane strains and lane following. The ultrasonic sensor is used to come across the item in among the lanes and degree the space in among. In order to construct a hardware version of self-riding car, a chassis is chosen because the base on which all forums are hooked up, and four wheels are attached - 2 wheels in the front and a couple of wheels in back, to the chassis. The L298H motor driving force controls the movement of the motors. It responds to the command acquired from the Raspberry Pi. USB webcam is used for photograph processing alongside Python library to come across real-time items and to observe site visitors rules. All the programs, written in Python language, to enforce photograph processing algorithms are dumped into Raspberry Pi.

B. Hardware Used

1) Raspberry Pi 4

Fig. 2: Raspberry Pi 4

Raspberry Pi four B+ is the primary processing head of this prototype car. It may be taken into consideration as a single board pc that works on LINUX working system. The 4 GB ram mounted offers a first-rate processing speed, making it appropriate for enhance applications. Here, its miles used for picture processing with assist of OpenCV software. Machine Learning Algorithm is used to educate the version in the use of Convolution Neural community techniques. Traffic Signal and item detection is likewise protected below the idea of Machine Learning.

2) Pi Camera

Fig. 3: Pi Camera

Pi Camera is one of the essential aspect of the prototype designed. The digital digicam is 8MP which 30 fps resolutions alongside Sony IMX219 sensor with F2.nine aperture. The digital digicam offers a brilliant help for protection and protection motive. It is extensive variety digital digicam able to recording 2592x1944 stills, 1080p30 video on Camera module v2. The essential motive of that is to ship the stay feeds to the Raspberry Pi for in addition processing.
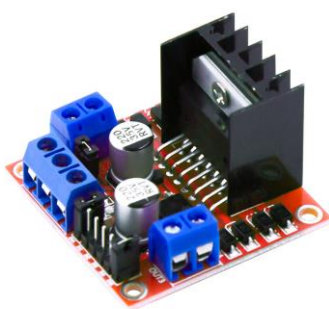
3) Motor Driver Module L298N

Fig. 4: Motor Driver Module L298N

The Motor Driver Module is used for driving DC and Stepper Motors. This module has a L298N motor driving IC and a 78M05 5V regulator. L298N Module can manage as much as four DC vehicles. The H bridge is used in conjunction with L298N IC to drive motors in any preferred directions.

4) RC Chassis Kit

Fig. 5: RC Chassis Kit

This is a longer model of four wheeled double-layer clever vehicle chassis. It comes with the 4 pairs of Wheels and Geared Motors of ratio 1:48. This is the primary thing on which all different additives are installed. This version does now no longer have guidance vehicles, however may be carried out with few changes with inside the program.

5) IR Sensors

Fig. 6: IR Sensors

The Infrared sensor is used for lane detection. It is a digital output device with adjustable sensing range. It has a transmitter and a receiver with a range of upto 20cm. The operating voltage is 5V to approx 3.3V.

C. Software Used

1) Python IDE

Python is an interpreted high-stage general-reason programming language. Its layout philosophy emphasizes code clarity with its use of tremendous indentation. Its language constructs and object-orientated method purpose to assist programmers write clear, logical code for small- and large-scale projects.

a) Python Libraries: A Python library is a group of associated modules. It consists of bundles of code that may be used time and again in exceptional programs. It makes Python Programming less difficult and handy for the programmer. As we don't want to write down the equal code over and over for exceptional programs. Python libraries play a totally crucial function in fields of Machine Learning, Data Science, Data Visualization, etc.

b) OpenCV: OpenCV could be a massive open-supply library for computer vision, machine learning, and image processing. OpenCV helps an enormous form of programming languages like Python, C++, Java, etcetera It can be used in various cases such as to recognize photos, faces as well as the handwriting of a human. Once it's combined with various libraries, beside Numpy that's a terribly optimized library for numerical operations, then the vary of guns will increase for your Arsenal i.e. one thing operations you may liquidate Numpy is also homogenized with OpenCV.

c) Haar Cascade Classifier: Haar Cascade classifiers are a powerful manner for item detection. Haar Cascade is a machine learning-primarily based totally technique in which plenty of positive and negative images are used to train the classifier. It is a way for combining an increasing number of complicated classifiers like AdaBoost in a cascade which lets in negative input (non-face) to be fast discarded whilst spending extra computation on promising or effective face-like regions. It substantially reduces the computation time and makes the technique extra efficient. OpenCV comes with plenty of pre-educated classifiers. Those XML documents may be loaded through cascade Classifier technique of the cv2 module. Here we're going to use those pre educated models for detecting objects.

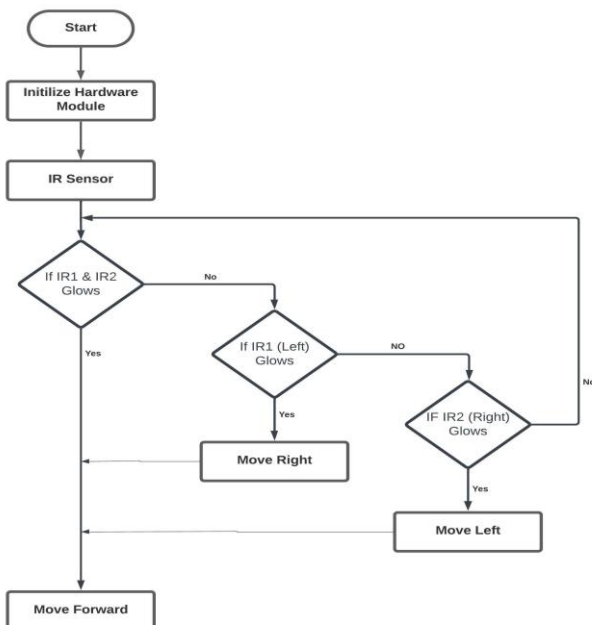## V. CONTROL FLOW WORK

A. Lane Following Flowchart (LFF)

Fig. 7: Lane Following Flowchart

For the purpose of lane detection and route tracking the car must be capable to differentiate between various roads, tracks, paths, as well as the lanes. For this purpose the lane detection comes into the picture. The 2 IR sensors are placed at the front of the car i.e. to the left side and to the right side of the car.

In this model, a lane is designed on the road and the model is supposed to follow the lane as instructed. When both the IR's are high the car moves in forward direction. When the car tends to shift to left, the IR1(left) glows and the car move in the right direction. Same as if the car tends to shift to right, the IR2(right) glows and the car move in the left direction. In this way the model keeps on self correcting whenever it goes wrong and keeps following the lane until both the IR's goes low.

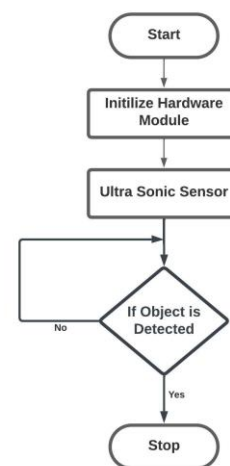### B. Object Detection Flowchart (ODF)

Fig. 8: Object Detection Flowchart

Object Detection is the basis of all the core applications such as autonomous cars, security, industrial appliances, etc. In this proposed model, ultrasonic sensor comes into picture. The sensor is used to detect the object which occurs in between defined path. If the object is detected the model stops running for some time and then again check for the presence of any object. As soon as the object is removed the car again starts running in its pre defined path.

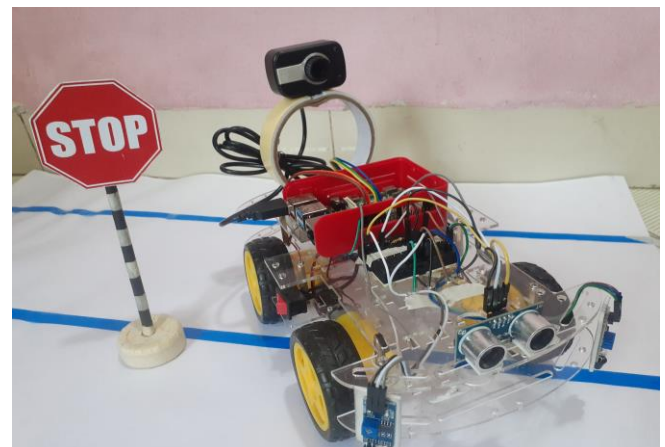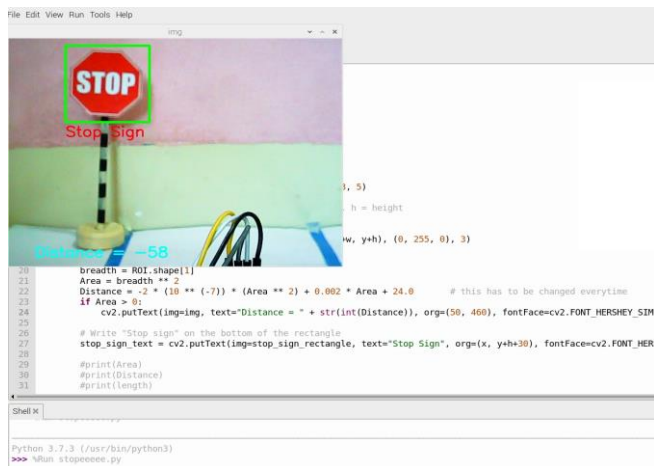## VI. TEST RESULT & ANALYSIS

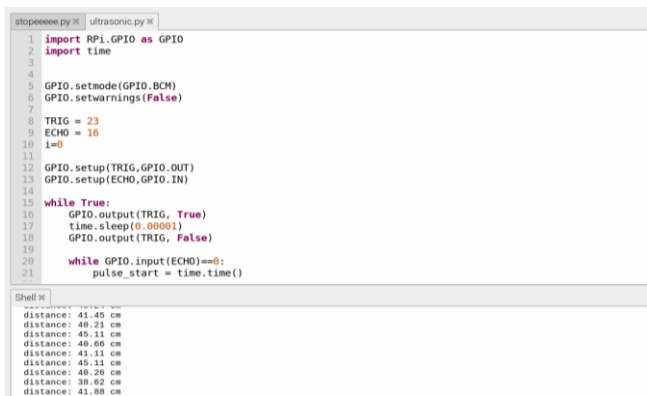Fig. 9: Prototype of Car

Fig. 10: Stop Sign Detection

Fig. 11: Ultrasonic Distance Calculation

VII. CONCLUSION

A low cost prototype of a self-sufficient car version is designed and evolved. With the assist of Image Processing and Machine Learning strategies, a success version is evolved which labored as consistent with our expectation. The proposed machine, reduces the human paintings of working the car. Furthermore, we additionally word that the given machine overall performance is a great deal higher than a mean user. Since the overall performance is higher and continually consistence, we hereby come to an end that the proposed machine can clear up the simple human mistakes that occurs. At last, the automobile is capable of observe lane efficaciously and

the visitor's symptoms and symptoms are detected nicely in addition to accompanied and choices are made accurately.

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