IJARSCT
International Journal of Advanced Research in Science, Communication and Technology
International Open-Access, Double-Blind, Peer-Reviewed, Refereed, Multidisciplinary Online Journal
ISSN: 2581-9429
Volume 5, Issue 4, April 2025
Impact Factor: 7.67

Line Following Roboat

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Abstract: *This project presents a line following robot that uses sensors and microcontrollers to navigate along a predetermined path. The robot is designed to follow a line or path marked on the floor, using infrared sensors to detect the line and adjust its trajectory accordingly. The robot's movement is controlled by a microcontroller, which processes sensor data and sends commands to the motors. The line following robot can be used in various applications, such as material transport, surveillance, and robotics research.*

Keywords: Line Following Robot, Autonomous Navigation, Sensor-Based Robotics, Microcontroller-Based Control, Robotics and Automation, Path Following Algorithm, Infrared Sensors, Motor Control, Robotics Research, Industrial Automation

I. INTRODUCTION

In recent years, robotics and automation have become increasingly important in various industries, including manufacturing, logistics, and healthcare. One of the key challenges in robotics is developing autonomous systems that can navigate and interact with their environment. A line following robot is a type of autonomous robot that uses sensors and microcontrollers to follow a predetermined path, marked by a line or other visual cue. This technology has numerous applications, including material transport, surveillance, and robotics research.

II. LITERATURE REVIEW

Line following robots have been a topic of interest in robotics research for several decades. These robots use sensors and microcontrollers to follow a predetermined path, marked by a line or other visual cue. This literature review aims to provide an overview of the current state of line following robot research, including the sensors and algorithms used, applications, and future directions.

III. METHODOLOGY

Step 1: Sensor Calibration

1. Infrared Sensors: Calibrate the infrared sensors to detect the line by adjusting the threshold values.
2. Camera Sensors: Calibrate the camera sensors to detect the line by adjusting the camera settings and image processing algorithms.
3. Ultrasonic Sensors: Calibrate the ultrasonic sensors to detect obstacles by adjusting the threshold values.

Step 2: Algorithm Development

1. PID Control: Develop a PID control algorithm to control the movement of the robot based on the sensor data.
2. Fuzzy Logic: Develop a fuzzy logic algorithm to control the movement of the robot based on the sensor data.
3. Machine Learning: Develop a machine learning algorithm to control the movement of the robot based on the sensor data.

Step 3: Robot Control

1. Motor Control: Control the movement of the robot using the developed algorithm.
2. Sensor Feedback: Use sensor feedback to adjust the movement of the robot.

DOI: 10.48175/IJARSCT-25160

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3. Line Following: Use the algorithm to follow the line accurately.

Step 4: Testing and Validation

1. Testing: Test the robot on different types of lines and surfaces.
2. Validation: Validate the performance of the robot using metrics such as accuracy, speed, and stability.

Tools and Software:

1. Arduino IDE: Use the Arduino IDE to program the microcontroller.
2. Python: Use Python to program the robot using machine learning algorithms.
3. MATLAB: Use MATLAB to develop and test the algorithm.
4. Simulink: Use Simulink to simulate the robot's movement and test the algorithm.

IV. IMPLEMENTATION

The platform consists of several modules:
Hardware Components:Microcontroller, sensors,motors,motor driver,power supply.
Software Components: programming language, algorithm ,sensor calibration.
Steps of implementing: built in robot ,write a code,calibrate the sensor,test the robot,define the algorithm.

V. RESULT AND DISCUSSION

Here's an overview of the results

1. Successful Line Following: The robot successfully followed the line with a high degree of accuracy.
2. Improved Navigation: The robot's navigation system was improved through the use of sensors and algorithms.
3. Increased Efficiency: Theefficiency was increased through the use of optimized algorithms and motor control.
4. Reduced Errors: The number of errors was reduced through the use of sensor calibration and algorithm refinement.

VI. CONCLUSION

In conclusion, the line following robot project has been successfully designed, developed, and tested. The robot is able to accurately follow a line using infrared sensors and a microcontroller. The project has demonstrated the potential of line following robots in various applications, including material transport, surveillance, and robotics research.
The line following robot project has been a successful demonstration of the potential of robotics and automation in various applications. The project has provided valuable insights and experience in designing, developing, and testing a robotic system. The findings and conclusions of this project can be used to inform future research and development in this area.

VII. ACKNOWLEDGMENT

We would like to express our sincere gratitude to Vishweshwarayya Abhiyantriki Padvika Mahavidyalaya, Almala, for providing us with the necessary resources and guidance to successfully complete this research on "Real Estate Website: A Digital Solution for Property Management and Transactions."
We extend our heartfelt appreciation to our mentor, Prof. Osmani F. W., for his continuous support, valuable insights, and expert advice throughout the development of this project. His encouragement and constructive feedback played a crucial role in shaping our research.
We are also grateful to our peers and faculty members for their valuable discussions and suggestions, which contributed to the improvement of our project.
Finally, we extend our special thanks to our families and friends for their unwavering support and motivation during the research and development process.
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