PV BASED LANDMINES DETECTING ROBOTIC VEHICLES FOR THE DEFENCE FORCE

Saritha.k¹, Saruthi.B², Tarun D³, Kathiravan . K⁴

DEPARTMENT OF ELECTRICAL AND ELECTRONICS ENGINEERING

THENI KAMMAVAR SANGAM COLLEGE OF TECHNOLOG, THENI, TAMILNADU.

ANNA UNIVERSITY, CHENNAI, TAMILNADU.

ABSTRACT:

The main purpose of our landmines detecting robotic vehicle is to identify the landmines for the defense field for the maximum possible area. If the landmines explode it causes severe damage to the soldiers and even causes toxic pollutants to environment. Conventionally the the robots before they are exploded in the warbased area. Here, the land mine detecting robots plays a vital role in saving the lives of soldiers. A slight modification in the conventional work is proposed here, which gives a key to solving the landmine issues in the defense field with an additional power setup for the robotic vehicle. Here the proposed work is implemented by using AVRM microcontroller an arrangement in a robotic vehicle with a PV panel setup. Thus, this PV -based Robotic vehicle detects buried mines to avoid human interruption in buried mines by sending alert messages to the control center of the defense force by sharing the location with the identification of land mines using the Global Positioning System. Hence this PV-based Robotic vehicle is useful for monitoring the defense area by the control center of the defense force.

Key Words: AVRM Cortex, GPS/GSM module, Landmines, Metal Detector, Solar panels, Robotic vehicle.

1 INTRODUCTION

It is important for landmines still hidden under the ground everywhere. It causes life disaster and durable and fleeting failure for individuals and other living creatures. It impacts the economy and quietness of the nations[1]. As a result of the battles between countries, landmines have turned into a certifiable overall issue and the opportunity of it needs a tremendous proportion of money to be spent on it. Numerous horticultural countries which are affected by stowed away explosives, to make this mission productive, spent a bundle of gross public compensation and human effort on breathing space of it[2]. Even though advancements kept on making, the manual landmine slack is still outstandingly preferred considering its consistency, consistency, and relentless quality [3]. Regardless, the weaknesses of the standard system are, that the association is slow and it is perilous to the trained professionals. This investigation has spread out a landmine acknowledgment wander robot to help the field, which is speedier, got, and more definite than the standard methodology[4]. Mine revelation is ordinarily performed by metal distinctive sensors. The distance between the sensor head and the covered landmine is the huge limit that chooses the execution of the landmine acknowledgment cutoff of the metal finder. By changing the opening and level among the landmine and sensor head, the presentation of the metal locater can be moved along. The limit of the robotassisted secret dangerous area with canning is acted profitably, accepting the sensor heads stay aware of uniform opening with ground level[5]. The more prominent need is given to human security in this endeavor. The robot can be worked from a safer distance or from the area where the landmines have proactively been cleared. Since the landmine area head is projected before the vagabond, the gamble of the impact is killed. By this philosophy, the vagabond, as well as the individual, are safeguarded to remotely work. Bluetooth controller is used for correspondence between wonder, and what's more, director since it is of insignificant cost and unquestionable level security benefits. Various shield activities can be accomplished by this drifter robot. It can convey stuff and officials. In like manner, the major

wander robot model showed in Fig. 1. can be changed over into exceptional endeavor given out robots like Metal revelation robot, Army conveying robot, or Battle robot[6]. This paper is elucidated as follows. Region, one portrays the show about the structure, region two depicts the composing study, section three inspects the framework, region four depicts the results and discussion, and fragment five wraps up the paper by portraying the future degree quickly.

2 EXISTING MODELS:

GPR has been viewed as the most reassuring distinguishing subsurface system for landmine opportunity exercises in the mix with a metal marker. This is a consequence of its ability to recognize both metallic and non-metallic landmines[7]. Moreover, the limit concerning imaging and post-treatment of data enables the distinctive confirmation of perceived objects. A system joining GPR and a metal locater is for the most part called a twofold sensor. The structure finder includes the metal as the fundamental sensor for the revelation and impediment of metal-containing objects, after which it changes to GPR as the assistant sensor fo[8]r the objective ID. GPR for landmine disclosure normally uses commonly high frequencies to perceive as well as picture little articles near the surface and to lessen the size of the radio wires for more clear managing and higher adaptability. With high frequencies, GPR ends up being more fragile to the heterogeneity of the media including the thing, which achieves bothersome dispersing in the data[9]. The bothersome scattered waves are usually implied as a wreck. Wreck spoils the idea of the GPR data and makes their examination and interpretation inconvenient. Because of the landmine area, a sham examination or interpretation of the data could provoke an impromptu blast.

3 PROPOSED MODELS:

Robots search mines with such a low strain that mine blasts are not set off. To cover productively totally mined regions, robots ought to adjust to speed up investigation to increment proficiency, particularly if any observation group exists.

Using robots in landmines detection provides the best sensor for robots because of its minimal expense, wide accessibility, high info For exceptionally unique antagonistic assignments, having the option to remove huge data about the world is critical to working, making vision an engaging sensory our project, we have aimed to do by AVRM microcontroller which receives the detection from the metal detecting sensor.rmation content, and data rate.



Fig (a) Proposed Model of PV Based Landmine Detecting Robot

The microcontroller will give the live location through GPS from this detection, and the Wi-fi modem comes with an AT command firmware processor. The whole setup would be driven by a helical gear motor where the robot would be in dynamic progress. The output and to debug the system module in case of system failure to rectify the problem would be shown by the LCD which is 32-bit and plays a vital role here. The proposed model of our project is shown in fig (a).

3 BLOCK DIAGRAM:



Fig (b) BLOCK DIAGRAM OF LANDMINE DETECTING ROBOT

4 FLOWCHART:

This is the flowchart of the landmines detecting robot in fig (c).



Fig (c)flowchart

5 HARDWARE IMPLEMENTATION:

The components that we have used in our model are listed below

- A. AVRM Microcontroller
- B. Metal Detection Sensor
- C. Global Positioning System
- D. Wifi
- E. Web camera
- F. Bluetooth
- G. Battery
- H. PV Panel
- I. Dc motor
- J. Mobile phone for receiving data

A. AVRM MICROCONTROLLER:

AVRM represents Alf-Egil Bogen Vegard Wollan RISC microcontroller, otherwise called Advanced Virtual RISC Microcontroller. These are altered Harvard design 8-digit RISC single-chip microcontrollers. AVR was one of the first microcontroller families to use on-chip streak memory for program capacity, rather than one-time programmable ROM, EPROM, or EEPROM utilized by other microcontrollers at the time.32K bytes of framework self-programmable glimmer program memory. 2K bytes of inward SRAM. 1024 bytes EEPROM. Accessible



in 40 pin DIP, 44 lead QTFP, and 44-cushion QFN/MLF.

Fig(d) AMICA Motherboard

There are three classes of AVR microcontrollers.

1.Tiny AVR: Smaller in size and Less memory.

2.MegaAVR: Popular, memory up to 256 kb, a few amounts of inbuilt peripherals, complex application.

3.XmegaAVR: Large Memory, High Speed, and complex application.

Here we have used AVR Microcontroller with **AMICA MOTHERBOARD** which is denoted in fig (d), and the pin diagram

of AVR MICROCONTROLLER is denoted in fig (e).



Fig (e)Pin Diagram of AVR MICROCONTROLLER

.B. METAL DETECTION SENSOR:

identification Metal is sensor Inductive proximity sensors that can identify metal targets is shown in fig (f). They don't identify non-metal targets like plastic, wood, paper, and earthenware. Not at all like photoelectric sensors, this permits inductive closeness sensors to identify a metal item through obscure plastic. The least difficult type of metal locator comprises an oscillator creating a rotating current that goes through a curl delivering a substituting attractive field. Assuming that a piece of electrically conductive metal is near the loop, vortex flows will be initiated (inductive sensor) in the metal, and this creates its very own attractive field. If one more loop is utilized to quantify the attractive field (going about as a magnetometer), the adjustment of the attractive field because of the metallic item can be identified.

Utilizing this procedure, we have executed our paper involving these inductive proximity sensors for recognizing the covered landmines in fig (f).



Fig (f)ProximitySensor for Detecting Mines

C. Global Positioning System:

The Global Positioning System (GPS) is a U.S.- possessed utility that furnishes clients with situating, route, and timing (PNT) administrations is shown in fig (g). This framework comprises three sections: the space portion, the control fragment, and the client portion. The U.S. Space Force creates, keeps up with, and works the space and control portions of GPS control fragment comprised of а worldwide organization of ground offices that track the GPS satellites, screen their transmissions, perform investigations, and send orders and information to the star grouping.



Fig (g)Global Positioning System

D. Wireless fidelity network

(WI-FI):

Wi-fi is a gathering of far-off association shows, which are ordinarily used for the neighborhood of contraptions and Internet access, allowing nearby highlevel devices to exchange data by radio waves. The logo of wifi is shown in fig (h). These are the most by and large used PC networks in the world, used all over the little planet in home and office associations to interact workspace and PCs, PCs, PDAs, splendid TVs, printers, and keen speakers together and to a remote change to relate them to the Internet, and in far off paths transparently puts like cafés, hotels, libraries, and air terminals to give the public Internet induction to phones.



Fig(h) Wi-Fi

E. Web camera:

A web camera is a camcorder that faces the client. A Webcam is utilized for video calling and taking selfies, but then most models coordinate an intensifier, and different clients select to incorporate earphones for better sound quality. Independent mouthpieces with more recognizable responsiveness are also utilized for studio presentations. Webcams, Network Cameras, and Home Cams. A Webcam is joined to a PC,



Fig(i) web camera

notwithstanding. the association and related cameras are free units utilized for taking notes. Generally a "network camera" is huge for an outright reconnaissance framework with several cameras for stores and workplaces (see network camera). А "home cam" communicates with the home affiliation like a printer (see related camera). See camming, Webcam blocker, POV camera, lifecasting, and spycam.

In this PV-based landmine seeing Robotic Vehicle, the web camera is utilized to screen the vehicle by finding it on the screen. The web camera that is used in our project is shown in fig (i).

F. BLUETOOTH:

Bluetooth is a short-range far-off development standard that is used for exchanging data among fixed and phones over short distances using UHF radio waves and building individual areas associations (PANs). It is used as a decision to wire affiliations, exchange records between adjoining advantageous devices, and connection point PDAs and music players with far-off headphones. In the most comprehensively used mode, transmission power is confined to 2.5 milliwatts, furnishing it with an incredibly short extent of up to 10 meters (33 ft). The convincing arrive at changes depends upon conditions, expansion material incorporation, creation test assortments, radio wire arrangements, and battery conditions. Most Bluetooth applications for indoor conditions, are where decreasing dividers and sign obscuring as a result of sign reflections make the span far lower than the decided view extents of the Bluetooth things.

In this mechanical vehicle, Bluetooth goes about as a point of interaction between GPS and the presentation.

G. BATTERY:

The lead-corrosive battery is a sort battery-powered batterv initially of designed in 1859 by French physicist Gaston Plant. It is the very first kind of battery-powered battery made. Contrasted with present-day battery-powered batteries, lead-corrosive batteries have moderately low energy thickness. Batteries are the most widely recognized power hotspot for portable robots. In the present plans, lithium sciences have generally supplanted lead-corrosive batteries. This FAO will start by contrasting the presentation abilities of Li-particle and LiFePO4 batteries. The batteries used is denoted in fig (j).



It will then take a gander at flow endeavors to utilize reused electric vehicle (EV) batteries as the great power hotspot for computerized directed vehicles and coordinated factors robots and close with the conceivable utilization of zinc-air batteries as underlying parts in people in the future of versatile robots.

We are utilizing a lead-corrosive battery to give supply to the mechanical vehicle and the battery gets charged by PV boards.

H. PV PANEL :

A PV board is essentially a strong state semiconductor gadget that converts light energy into electrical energy. In the PV boards associated with the series, the flow of each going through the framework is equivalent. The framework voltage for any ongoing worth is the amount of all PV board voltages. In an equal associated framework, a solitary PV board voltage is the complete voltage of the framework. The current of each P-V board comprises the absolute PV board current of the framework.PV boards convert the sun's energy into electrical energy. Even though the essential energy (unpowered-powered ΡV free) boards' transformation effectiveness assumes a significant part in their turn of events and market infiltration.



In our project, a solar board is put on top of the tracker board which ingests the greatest daylight which is utilized as a supply to the motors or put away in the battery for some time later. It is shown in fig (k).

I.HELICAL GEAR DC MOTOR:

A gear motor is a part whose component changes the speed of the engine, driving them to work at a specific equipped motor can convey high force at low velocities, as gearhead capacities as a force the multiplier and can permit little engines to produce higher speeds which is shown in fig (i). A gear motor can likewise be characterized as a gear minimizer because basically, it is a blend of a speed minimizer with an engine normally working as a gearbox, to diminish speed making more force available. An equipped engine can be ordered given the engine they are matched with, including slope, helical, hypoid, spike, and worm gears. The helical gear units are coaxial units where the gear unit yield shaft is by the engine shaft. The in-line helical motor is generally utilized for slow speed/high force applications.

Due to creating a higher speed and change of speed during the specific applications we have utilized in our undertaking to drive our robots in powerful advancement.



Fig (i)Helical Gear Motor

6.WORKING PROGRESS:

The robot can utilize numerous sensors to gather data from the encompassed climate. The pre-owned sensors are metal recognizing sensors (MDS), nearness, and camera sensors. GPR can recognize landmines where situated on the ground or underground. It works better on dry surfaces; in any case, it can't be utilized in high-conductivity regions, for example, soils that are salt debased or dirt soils. Besides, the MDS has high-energy utilization.

The main job in demining is to ensure administrators are in the protected zone. The technique for distinguishing mine by robots is compelling because it diminishes the gamble, and the expense contrasted with manual identification.

7. DIFFERENT METHODS FOR DETECTING THE LANDMINES:

Landmines' acknowledgment of cooperation can be perceived by different procedures. Every system has its resources and hindrances. Including robots in my recognizable proof is a very reasonable system. It gives various advantages involving nearness sensors for perceiving the landmines Utilizing robots offers prosperity responses for saving deminers ' lives. It likewise has a multi-sensor structure that increases the steadfastness of the demining framework.

8. REASONS TO SUPPORT:

★ The robot can detect mines with high detection speed because of the

proximity sensor which helps to detect mines even in critical climatic conditions.

 ★ Ultrasound uses high-pitched sound waves to obtain an image of underground ultrasound detection ultrasound signal penetrates the soil and detects buried mines signals. In the wet ground, this technique works well. Ultrasound disapproves of the point of interaction with air and soil.

9. CONCLUSIONS:

The mechanical strategy was a powerful procedure that addressed the dangers for human administrators. The proposed framework utilizes a combination of staggered sensors as opposed to utilizing an over-the-top expensive one. We utilized a total inclusion way intending to track down all potential mines in the climate

- ★ If there are any obstacles or any critical in the path, The robotic vehicle transforms into a QUADPORTER and defeats the obstacles.
- ★ Implementing an advanced version in our PV BASED LANDMINES DETECTING ROBOTIC
 VEHICLE which acts as an automated vehicle using DATA SCIENCE.
- ★ If we get access from the military force by implementing the frequency response for further level detection of the landmines.

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