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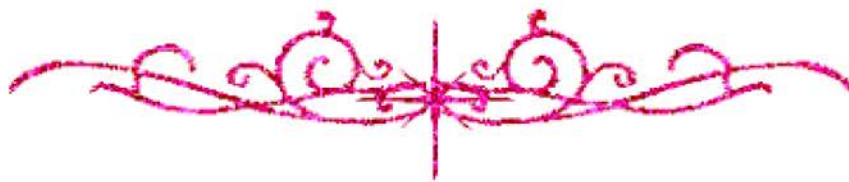
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ZAGAZIG UNIVERSITY
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DEVELOPMENT OF ULTRASONIC RANGING SYSTEM
FOR A MOBILE ROBOT

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A Thesis

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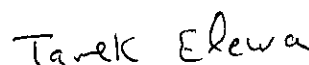
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ABSTRACT

The aim of this study was to develop an Ultrasonic (US) range finding system for an experimental mobile Robot, which detects and avoids obstacles by measuring the object distance using the Time of Flight (TOF) technique. This has been achieved in three stages. In the first stage, a single Transmitter/Receiver range finding system was developed. A 40 kHz square signal was experimentally generated and magnified to a level sufficient to drive the piezoelectric transducer (transmitter), which in turn converted this square signal into an ultrasonic wave. The signal was then emitted to the surrounding environment. On colliding with target, the ultrasonic signal would be reflected and detected by the receiver, which in turn converts this ultrasonic signal into an electric signal that provides the microcontroller with an external interrupt. The time elapsed from emission to detection of the reflected pulse was recorded and used along with the speed of sound in air for estimating the object distance.

Due to the poor angular resolution and the small coverage area associated with the single sonar system, a multi sonar system was developed in the second stage to overcome such limitations and improve the target resolution. An array of four transmitting transducers was used for the transmission unit; each transmitter was surrounded with two receivers. The operation of these transmitters and receivers was controlled using two different multiplexing logic circuits. An interface with the PC has been successfully implemented in the third stage. The object distance estimated by the microcontroller was verified and displayed on the PC in both numerical and graphical format.

Experimental measurements were taken on various targets with different geometry and positions by the developed single and multi sonar range finding systems. For single sonar range finding system, the object distance and time of flight were experimentally taken on flat horizontal surface, inclined surface with an angle of inclination of 60 degrees and on a corner target. The obtained results reflected the ability of the single sonar system to detect the flat object when placed in a horizontal position. While for the other two cases, the single sonar system has failed to identify the object position and geometry.

For multi sonar range finding system, the object distance and recorded time were experimentally taken on flat target placed in horizontal position and in inclined positions with inclination angles of 30, 60, 80 and 90 degrees. The obtained results reflected the high performance of the multi sonar range finding system over the single one for all the studied cases. In addition, the multi-sonar system has successfully identified the corner location and geometry. It also detected the cylindrical objects from multi viewpoints.

LIST OF CONTENTS

	Page
ACKNOWLEDGEMENT	I
ABSTRACT	II
LIST OF CONTENTS	III
LIST OF FIGURES	V
LIST OF TABLES	VII
LIST OF ABBREVIATIONS	VIII
LIST OF SYMBOLS	IX

CHAPTER 1 INTRODUCTION

1.1 Field of Study	1
1.2 Scope of Study	2
1.3 Outline of Thesis	4

CHAPTER 2 LITERATUE REVIEW

2.1 Introduction	5
2.2 Sensors	5
3.3.1 Ultrasonic Transducers	6
3.3.2 Performance Factor	8
2.2.2.1 Transducers Design Considerations	8
2.2.2.2 Environmental factors	12
2.2.2.3 Target Considerations	17
2.2.2.4 Potential Range Errors	21
2.3 Multiple Transducers	27
2.4 Ultrasonic Ranging Techniques	29

CHAPTER 3 SYSTEM DESIGN AND IMPLEMENTATION

3.1 Introduction	32
3.2 Development of A single Transmitter/Receiver Sonar	32
3.3 Microcontroller Based Single Module Ultrasonic Transreceiver	35
3.3.1 Generation of transmitted Pulses	37
3.3.2 Window Comparator	40
3.3.3 Distance Measurements	40
3.3.4 Flowchart	40
3.4 Multi-sonar Range Finding System.....	44
3.4.1 Sensors Configurations	44
3.4.2 Principles of System Operation	45
3.4.3 Multiplexing Logic Circuits	48
3.4.4 Software Flow Chart	49

3.5	Microcontroller and PC Interface.....	51
3.5.1	Principle of Serial Operation	53
3.5.2	Software Program	54

CHAPTER 4 EXPERIMENTAL VERIFICATIONS

4.1	Introduction	55
4.2	Single Sonar Results	56
4.3	Multisonar Results	62
4.4	Data Fusion	76

CHAPTER 5 CONCLUSIONS AND RECOMMONATIONS FOR FUTURE WORK

5.1	Summary and Conclusions.....	78
5.2	Recommendation for Future Work	81

REFERENCES	82
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APPENDICES

Appendix A	89
Appendix B	106

LIST OF FIGURES

	Page
Figure 2-1, Ultrasonic transducers: piezoelectric (left) and electrostatic (right) -----	7
Figure 2-2, Typical sonar beam pattern -----	9
Figure 2-3, Diameter of the insonified footprint at the surface, assuming incidence --	9
Figure 2-4, Wavelength of sound in air at room temperature versus frequency -----	11
Figure 2-5, Maximum attenuation of sound in air -----	11
Figure 2-6, Speed of sound in air as a function of temperature -----	13
Figure 2-7, Reduction in the power per unit area in the cone OABCD -----	14
Figure 2-8, Variation in the attenuation of sound in air for varying humidity At frequencies between 40 and 200 kHz -----	15
Figure 2-9, Effect of target orientations and irregularities on the returned echo -----	18
Figure 2-10, Experiment configuration showing the four ideal cases for a sonar transducers -----	20
Figure 2-11, Low level sonar traces -----	21
Figure 2-12, Ultrasonic ranging error due to beam divergence -----	22
Figure 2-13, Beam splitting technique using two sensors -----	23
Figure 2-14, Specular reflection error occurs in smooth surface when the angle of reflection (b) is equal to the angle on incidence (a) [2]-----	24
Figure 2-15, due to Specular reflection, the measured range would represent the round trip distance through points A, B, C as oppose to actual distance between A and B [3]-----	24
Figure 2-16, Conventional system without cross talk [57] -----	25
Figure 2-17, Conventional system cross talk [60] -----	26
Figure 2-18, EERUF system with cross talk -----	27
Figure 2-19, (A) a wide angle transducer (B) single narrow beam transducer (C) Multiple transducers -----	27
Figure 3-1, Block diagram for single sensing system -----	33
Figure 3-2, Ultrasonic transmitters and high sensitivity receivers designed for sending and receiving ultrasonic sound through the air at 40 kHz-----	34
Figure 3-3, First stage amplification of the reflected signal -----	36
Figure 3-4, Second stage amplification of the reflected signal -----	36
Figure 3-5, Structure of the Intel 8031 microcontroller -----	37
Figure 3-6, Timing diagram for the generation of 40 kHz pulses -----	38
Figure 3-7, Microcontroller output signal (40 kHz) -----	39

Figure 3-8, Amplified reflected signal during a limited period, first stage -----	39
Figure 3-9, Amplified reflected signal during a limited period, second stage -----	41
Figure 3-10, output of window Comparator -----	41
Figure 3-11, Single sonar system developed in this study -----	42
Figure 3-12, Flowchart for the operation of single sonar system -----	43
Figure 3-13, Arrangement of multi sonar transducers -----	45
Figure 3-14, Block diagram of multi sonar system -----	46
Figure 3-15, Multi sonar system card -----	47
Figure 3-16, Flowchart for the operation of multi sonar system -----	50
Figure 3-17, Microcontroller/PC interface model -----	52
Figure 3-18, Transmitted and Received data lines for RS-232-----	52
Figure 3-19, Block diagram of interface circuit for serial communications -----	53
Figure 4-1, Experimental set up for Experiments 1 and 2 -----	56
Figure 4-2, Flat target placed parallel to the Sensor's plane (Experiment1)-----	58
Figure 4-3, Flat target placed at angle of 60° with the Sensor's plane (Experiment2) -----	59
Figure 4-4, Experimental set up for Corner target surface (Experiment 3)-----	60
Figure 4-5, An Example for corner target Surface (Experiment 3)-----	61
Figure 4-6, Experimental set up of the target surface (Experiments 4 to 8)-----	62
Figure 4-7, Target Surface placed parallel to the plane of Sensors (Experiment 4)---	64
Figure 4-8, Flat target placed at angle of 30° with the plane of Sensors -----	65
Figure 4-9, Flat target placed at angle of 60° with the plane of Sensors -----	66
Figure 4-10, Flat target placed at angle of 80° with the plane of Sensors -----	67
Figure 4-11, Flat target placed perpendicular to the plane of Sensors (Experiment8)-	68
Figure 4-12, Experimental set up for Corner target surface (Experiment 9)-----	69
Figure 4-13, An example for corner target Surface (Experiment 9)-----	70
Figure 4-14, Experimental set up of Cylindrical target surface -----	72
Figure 4-15, Cylindrical column with 30 Cm in diameter (Experiment 10)-----	73
Figure 4-16, Cylindrical model with 10 Cm in diameter (Experiment 11)-----	74

List of Tables

	Page
Table 3.1 , Technical Data sheet for the Ultrasonic transmitting and Receiving piezoelectric transducers Model -----	34
Table 3.2 , Correlation between Ultrasonic transmitting and Receiving transducers ---	48

List of Symbols

B	Gas constant
C	Speed of sound in air
c	Sound velocity which is equal to 343 m/s at room temperature
D	Spot diameter in inches
d	Transducer diameter
F	Temperature in degrees Fahrenheit
f	Operating frequency in kHz
G	Gravitational constant
I	Intensity (power per unit area) at distance R
I_i	Incident intensity
I_o	Maximum (initial) intensity
I_r	Reflected intensity
K	Ratio of specific heat, (for air = 1.4)
K_m	bulk modulus of elasticity
K_r	Coefficient of reflection
R	Range of measured distance (m)
T	Temperature of the air in °C
t	Time of flight (Sec.)
Z_a	Acoustic impedance for air
Z_o	Acoustic impedance for the target object
α	Attenuation coefficient for medium
θ	Total beam angles in degrees
λ	Acoustic wavelength
ρ	gas density