



FINAL YEAR PROJECT REPORT

**AUTONOMOUS NAVIGATION &
OBJECT TRACKING ROBOT**

In fulfillment of the requirement
For degree of
BEE (Electrical Engineering)

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APPROVAL FOR SUBMISSION

We certify that this project report entitled "AUTONOMOUS NAVIGATION AND OBJECT TRACKING ROBOT" was prepared by AIMAN HAFEEZ & RAYYAN IDREES have met the required standard for submission in partial fulfilment of the requirements for the award of Bachelor of Electrical Engineering at Bahria University.

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ABSTRACT

During the previous decades, a tremendous growth in the field of robotics automation has been made. Daily activities involve interaction with smart machines that present a certain level of autonomy. Robots ensure that a task can be done more accurately and efficiently. They can perform the repetitive task without any difficulty. In this autonomous robot, finding object in an unexplored area is a major mission in this work, for advance work the robot will pick the required object. A self-customized mobile robot having low-cost and low-power equipment's will be utilized in this project. The Robot Operating System or ROS is being executed with the help of Jetson Nano. Mapping is established using Rplidar . A mobile robot structure planning for object detection and navigation is being developed in this project. This work proposes a pose planning method to observe a target object using 2D information from Rplidar. The proposed planning method is utilized under the ROS environment; the ROS Navigation stacks nodes help to process sensor information. The mobile robot navigation is handled by the ROS Navigation stacks. 2D ROS navigation stack takes information of odometry, sensors and velocity of wheels to send to mobile robot. To be able to work on navigation stack the robot must be running ROS which has tf transform tree to place and publish sensor data using the correct ROS messages command. ROS navigation stack is also needed to configure robot pose, shape and structure to perform the high level tasks. The object detection model is trained through python. The camera will find where in the frame object is located by extracting its bounding boxes. Then it follows the goal point of the map generated by SLAM. In the end, robot moves towards the object and pick it up with the help of robotic arm.

TABLE OF CONTENTS

DECLARATION	3
APPROVAL FOR SUBMISSION	6
ACKNOWLEDGEMENTS	7
ABSTRACT	8
LIST OF FIGURES	11
LIST OF TABLES	14
APPENDICES	15

CHAPTERS

1	INTRODUCTION	16
	1.1 Background	16
	1.2 Literature Review	16
	1.3 Problem Statement	21
	1.4 Aims and Objectives	22
	1.5 Scope of Project	22
	1.6 Sustainable Development Goals of Project.	23
	1.6.1 Introduction	23
	1.6.2 Justification	23
	1.6.3 Mapping of Sustainable Development Goals	24
	1.7 Environmental Aspects of Project	24
	1.7.1 Introduction	24
	1.7.2 Environmental Impact Assessment(EIA)	24
	1.7.3 Environment Impact Statement (EIS)	25
2	DESIGN AND METHODOLOGY	26
	2.1 Components	26
	2.2 Block Diagram	27
	2.2.1 Methodology	28

		10
3	DESIGN IMPLMENTATION	29
3.1	Room Map Generation	29
3.2	ROS Navigation Stack	31
3.3	Data From Wheel Encoders:	32
3.4	Sensor Fusion Using the ROS Robot Pose EKF Package	33
3.5	Controlling Robot Velocity Remotely Using ROS	34
3.6	Two Wheel Differential Drive	35
3.6.1	Right Wheels ticks through ROS	36
3.6.2	Left Wheels ticks through ROS	37
3.6.3	Initial to Goal Pose Publisher:	38
3.6.4	2D initial pose data through ROS:	39
3.6.5	2D goal pose data through ROS:	39
3.7	Launching the Autonomous Robot	40
3.8	Headless Setup	41
3.9	Hardware	44
3.9.1	Jetson Nano:	45
3.9.2	Rplidar:	46
3.9.3	Robotic Arm:	47
4	RESULTS AND DISCUSSIONS	49
4.1	Robotic Arm:	50
4.2	Map Generation	51
4.2	Navigation:	52
4.3	Object Detection:	52
4.4	Tracking	53
5	CONCLUSIONS AND RECOMMENDATIONS	54
5.1	Map Generation:	54
5.2	Navigation:	54
5.3	Object detection:	54
5.4	Object Tracking:	55
	REFERENCES	56