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GESTURE CONTROL HUMAN FOLLOWING ROBOT

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ABSTRACT

A rapidly developing subject of study, humanoid robots has drawn a lot of interest recently and will be crucial to robotics research and numerous applications in the twenty-first century and beyond. A "Human Following Robot" that can communicate and coexist with humans is necessary in our fast-paced environment. These robots may aid people in a variety of scenarios and gather or keep track of specific data related to the human subject thanks to their capacity to follow humans. This article describes a prototype that combines an Arduino Uno with common sensors such as an infrared and ultrasonic sensor. The controller is responsible for controlling the motors, while the microprocessor handles all processing. There are several ways to further customize this robot, including via the use of Bluetooth and PixyCamera.

Keywords: IR sensor, ultrasonic sensor, Arduino micro controller, human tracking, human following, and artificial intelligence.

I. INTRODUCTION

With its sophisticated gestures and strong obstacle recognition skills, the Gesture-Controlled & Obstacle recognition Robot is a cutting-edge device that aims to improve human-machine interaction. This groundbreaking research is the perfect answer for applications that need smooth human-robot interaction in dynamic contexts because it combines the accuracy of gesture recognition with the dependability of obstacle avoidance. The flex sensor, which recognizes hand motions from the user and allows the robot to react to precise orders without the need of physical controllers, is the central component of this robot's operation. With the use of this sensor, a more natural and intuitive method of

engagement is made possible, resulting in a user-friendly experience whereby the robot may be controlled with basic hand gestures.

The vibration sensor, which is an essential component of the robot's obstacle detecting system, supports the gesture control. This sensor makes sure the robot can go through different types of settings securely by identifying and reacting to possible obstructions. The vibration sensor's real-time response enables the robot to change direction, preventing accidents and guaranteeing a smooth functioning.

Two servo motors provide the required torque and control for precision positioning, enabling the robot to move about and perform precise actions. With the help of these motors, the robot can carry out intricate movements with extreme accuracy, which improves its capacity to interact with its environment and precisely obey directions from the user.

The Gesture-Controlled & Obstacle Detection Robot exemplifies the integration of modern sensor technologies with advanced robotics, offering a versatile platform for exploring new ways of human-robot interaction. This project not only demonstrates the potential of gesture-based control systems but also underscores the importance of obstacle detection in creating autonomous robots that can safely and efficiently operate in real-world scenarios. Through this innovative approach, the robot sets a new standard for interactive robotics, paving the way for more intelligent and responsive systems in the future.



Fig 1.1 : Gesture controlled and obstacle detection robot

1.1: Problem Statement:

In many environments, such as shopping malls, airports, and public spaces, individuals frequently encounter challenges in navigating while managing personal items or belongings. The difficulty of simultaneously moving and carrying items can lead to inconvenience, physical strain, and a lack of efficiency, particularly in busy or dynamic settings. Traditional methods of personal assistance often require manual effort, are not user-friendly, or lack the flexibility needed to adapt to the ever-changing nature of such environments.

The Gesture-Controlled & Obstacle Detection Robot is designed to address these challenges by providing a smart, hands-free solution that can follow individuals and assist with navigation while avoiding obstacles. This innovative robot eliminates the need for constant manual control, instead offering an intuitive gesture-based interface that allows users to direct the robot with simple hand movements. Additionally, its obstacle detection capability ensures safe and efficient navigation in various settings.

The core problem tackled by this project is the absence of a reliable and adaptive system that can assist individuals with personal navigation and item management in diverse and complex environments. The Gesture-Controlled & Obstacle Detection Robot aims to fill this gap by providing an advanced, user-friendly

solution that enhances convenience, reduces physical strain, and offers seamless interaction, ultimately improving the overall user experience in public and private spaces alike.

1.2: Problem Scope:

The scope of the Gesture-Controlled & Obstacle Detection Robot project encompasses the development of an advanced robotic system designed to assist individuals in navigating complex environments by following them and avoiding obstacles using intuitive gesture-based controls. The project aims to address several critical challenges associated with personal mobility and assistance, focusing on functionality, user experience, environmental integration, scalability, and safety.

Functionality and Operation:

The primary objective is to create a robot capable of autonomously following a user while accurately navigating diverse environments. The system will rely on a flex sensor for gesture control and servo motors for movement. The robot must efficiently detect obstacles using sensors and adjust its path in real time to ensure smooth and uninterrupted operation. A key challenge will be optimizing the robot's responsiveness to gestures and obstacle detection to maintain a reliable and seamless following experience.

User Experience:

A central focus of the project is to enhance user experience by offering an intuitive and user-friendly interface. The robot should respond to simple hand gestures via the flex sensor, providing hands-free control and minimizing the need for direct manual intervention. The system should adapt to individual user preferences and various environmental conditions to maximize convenience and reduce the physical effort required from the user.

Integration with Environment:

The robot must be capable of effective integration into a range of environments, such as public spaces, shopping malls, or airports.

This involves navigating different floor surfaces, maneuvering around obstacles, and adapting to dynamic changes in the environment. Ensuring the robot's adaptability and performance across these settings is crucial for its practical utility and widespread application.

Scalability and Versatility:

The design of the robot should allow for scalability and versatility, accommodating various use cases and environments. The system should be adaptable to future enhancements and capable of evolving with technological advancements. It should offer a versatile platform that can be modified or expanded to meet different user needs and operational scenarios.

Cost and Budget Considerations:

Developing the Gesture-Controlled & Obstacle Detection Robot will involve costs related to the acquisition of components such as sensors, motors, and controllers, as well as design and manufacturing expenses. Budget considerations will influence the selection of components and the overall feasibility of the project. Balancing the cost with the expected benefits and ensuring cost-effectiveness is vital for successful project execution.

Stakeholder Collaboration:

The successful implementation of the project will require collaboration with various stakeholders, including users, developers, and technology providers. Engaging these stakeholders during the development process is essential for aligning the robot's capabilities with user needs, addressing potential concerns, and ensuring that the final product meets the intended objectives.

Safety and Reliability:

Safety and reliability are paramount considerations in the design of the robot. The system must be capable of operating safely in various scenarios, avoiding collisions, and providing consistent, dependable performance. Comprehensive testing and validation will be essential to ensure that the robot meets high

safety standards and can be trusted in real-world applications.

The Gesture-Controlled & Obstacle Detection Robot project aims to tackle these challenges by delivering an innovative, practical solution that enhances user convenience, integrates seamlessly into different environments, and provides a reliable, safe, and enjoyable user experience.

1.3: Advantages of the Gesture-Controlled & Obstacle Detection Robot

The **Gesture-Controlled & Obstacle Detection Robot** offers several significant advantages, making it an innovative solution for personal assistance and mobility in various environments. These advantages include:

1. Hands-Free Control:

The robot allows users to control its movements through simple hand gestures using a flex sensor. This hands-free control enhances convenience, particularly in scenarios where manual control would be cumbersome or impractical.

2. Improved Safety:

With integrated obstacle detection capabilities, the robot can autonomously navigate around obstacles, reducing the risk of collisions and ensuring safe operation in dynamic environments. This feature is crucial in crowded or complex settings, such as shopping malls or airports.

3. Enhanced User Experience:

The robot's intuitive design and responsive gesture control system offer an improved user experience. Users can interact with the robot naturally and effortlessly, making it more accessible and user-friendly for people of all ages and abilities.

4. Adaptability to Various Environments:

The robot is designed to operate effectively in a wide range of environments, from smooth indoor surfaces to more complex outdoor

settings. Its ability to adapt to different conditions ensures reliable performance in diverse scenarios.

5.Reduced Physical Strain:

By providing automated following and obstacle avoidance, the robot reduces the physical effort required from users, particularly those who may have mobility challenges or need to carry heavy items. This can help prevent fatigue and physical strain during long periods of use.

6.Versatility and Scalability:

The robot's design is versatile, allowing for future enhancements and modifications. Its scalable architecture enables it to be adapted for various use cases, from personal assistance to more specialized applications in healthcare or logistics.

7.Cost-Effective Solution:

The use of widely available components such as flex sensors, vibration sensors, and servo motors makes the robot a cost-effective solution. This affordability opens up opportunities for widespread adoption, making advanced robotic assistance accessible to a broader audience.

8.Increased Independence:

The robot's ability to follow and assist users without constant manual input increases personal independence, particularly for individuals with mobility impairments or other disabilities. It empowers users to navigate environments more freely and with greater confidence.

9.Seamless Integration:

The robot's ability to seamlessly integrate into various environments without disrupting the flow of activities makes it a practical solution for everyday use. Its unobtrusive design and operation ensure that it can be used in public spaces without causing inconvenience to others.

10. Innovation and Modernization:

The project represents a significant step forward in personal assistance technology, combining gesture control and obstacle detection in a single, cohesive system. This innovation not only addresses current challenges but also sets the stage for future advancements in robotics and assistive technology.

1.4 Proposed Solution:

The proposed solution for the **Gesture-Controlled & Obstacle Detection Robot** integrates advanced technology and essential components to create a versatile and user-friendly robotic system. This solution is designed to offer precise control, enhanced safety, and seamless operation across various environments, making it an effective tool for personal assistance.

1. Gesture Control Mechanism:

The robot is equipped with a flex sensor, which is worn by the user to capture hand gestures. This sensor detects the bending of the user's fingers and translates these movements into commands for the robot. By interpreting these gestures, the robot can be controlled intuitively, allowing the user to direct its movements without physical contact. This gesture-based interaction enhances the user experience by providing a natural and accessible method of control.

2. Obstacle Detection and Navigation:

To ensure safe and efficient operation, the robot is equipped with obstacle detection sensors. These sensors continuously monitor the environment for potential obstacles in the robot's path. When an obstacle is detected, the robot's control system processes this information and adjusts its movement

to avoid collisions. This capability is crucial for navigating crowded or complex environments, such as shopping malls or airports, where obstacles are common.

3. **Mobility and Actuation:**

The robot's mobility is provided by two servo motors, which control the movement of the robot's wheels or legs. These motors are responsible for executing the commands generated by the gesture control mechanism and obstacle detection system. The precise control offered by servo motors ensures smooth and responsive movement, allowing the robot to follow user commands accurately and adapt to changing environments.

4. **User Feedback and Interaction:**

In addition to gesture control, the robot incorporates a vibration sensor to provide haptic feedback to the user. This feedback mechanism enhances the interaction between the user and the robot by offering tactile confirmation of the robot's actions. For example, the vibration sensor can alert the user when the robot encounters an obstacle or successfully completes a command. This real-time feedback improves the overall user experience and ensures that the user remains informed about the robot's status.

5. **Safety Features:**

Safety is a key consideration in the design of the Gesture-Controlled & Obstacle Detection Robot. The system includes multiple safety features, such as automatic collision detection and an emergency stop function. These features are designed to prevent accidents and ensure the robot operates reliably in various environments. The collision detection system uses sensor data to identify

potential hazards, while the emergency stop function allows the user to halt the robot's movement instantly if necessary.

6. **Environmental Adaptability:**

The robot is designed to function effectively in a range of environments, including both indoor and outdoor settings. Its robust design and sensor-based navigation allow it to adapt to different surface types, navigate around obstacles, and maintain stability on uneven terrain. This adaptability makes the robot suitable for use in diverse scenarios, from personal assistance in public spaces to specialized tasks in industrial or healthcare settings.

7. **Pilot Testing and Refinement:**

To ensure the effectiveness of the proposed solution, a pilot testing phase is planned. During this phase, the robot will be deployed in real-world environments to assess its performance, user interaction, and safety features. Feedback gathered from users during this phase will be used to refine the system, addressing any identified issues and optimizing the robot's functionality. This iterative approach ensures that the final product meets the needs of its intended users and performs reliably in various conditions.

The Gesture-Controlled & Obstacle Detection Robot represents a significant advancement in personal assistance technology, offering a modern and innovative solution that combines intuitive control, safety, and adaptability. By leveraging cutting-edge sensors and actuators, this robot is poised to enhance mobility, improve user convenience, and provide a

reliable and efficient tool for personal and professional applications.

1.5 Aim and Objectives:

Aim:

The aim of the Gesture-Controlled & Obstacle Detection Robot project is to develop an advanced robotic system that enhances personal assistance by providing intuitive, gesture-based control and reliable obstacle detection. This robot is designed to offer users a seamless and user-friendly experience, allowing them to navigate and interact with their environment more efficiently. By integrating a flex sensor for gesture recognition, servo motors for precise movement, and sensors for obstacle avoidance, the project seeks to create a versatile and adaptable robot that can operate safely in various settings. The ultimate goal is to deliver a practical and innovative solution that improves mobility, reduces physical strain, and enhances overall user convenience in both personal and professional contexts.

Objectives:

Develop Gesture-Based Control: Implement a flex sensor to enable gesture recognition, allowing users to control the robot's movements intuitively through hand gestures.

Integrate Obstacle Detection: Equip the robot with sensors capable of detecting obstacles in real-time, ensuring safe navigation and preventing collisions in dynamic environments.

Enhance Mobility and Precision: Utilize servo motors to provide precise movement control, enabling the robot to follow commands accurately and navigate various terrains smoothly.

Ensure User-Friendly Interaction: Design the robot to be easily operable, with an emphasis on user convenience and intuitive control mechanisms, reducing the need for complex manual inputs.

Test and Validate Performance: Conduct thorough testing in diverse environments to validate the robot's functionality, reliability,

and safety, gathering feedback for further improvements.

Achieve Versatility and Adaptability:

Ensure the robot's design allows it to be adaptable to different settings, such as homes, offices, or public spaces, and capable of handling various tasks effectively.

Incorporate Safety Features: Integrate essential safety features, including collision detection and emergency stop functions, to protect both users and the robot during operation.

Optimize for Future Scalability: Design the robot with scalability in mind, allowing for future enhancements and expansions based on evolving user needs and technological advancements.

II. LITERATURE SURVEY

The literature on Human-Following Robots delves into various aspects of robotic systems designed to track and follow users, highlighting advances in technology and practical applications. This body of work includes studies on sensor integration, navigation algorithms, and user interaction mechanisms.

A significant focus in the literature is the use of transmitter and receiver technologies for accurate user tracking. Research has explored the effectiveness of different communication methods, including infrared and radio frequency, to maintain a stable connection between the robot and the user. Studies have analyzed the precision of these systems in various environments and the impact of obstacles on signal transmission.

Navigation and mobility are crucial areas of investigation. Literature reviews discuss algorithms and control strategies used to ensure smooth and accurate following behavior. Researchers have examined path-planning techniques and obstacle-avoidance methods to enhance the robot's ability to navigate complex environments while maintaining a safe following distance.

User interaction and safety features are also key topics. The literature highlights the

importance of intuitive user controls for adjusting the robot's following parameters, such as distance and speed. Additionally, safety mechanisms, including collision detection and emergency stop functions, are examined to ensure reliable and secure operation in public spaces.

Case studies and experimental implementations provide practical insights into the performance of human-following robots in real-world scenarios. These studies showcase the effectiveness of various design approaches and highlight the challenges faced during deployment, including issues related to system integration and user acceptance.

Overall, the literature on Human-Following Robots emphasizes the integration of advanced sensors, navigation algorithms, and user-centric design to create effective and reliable robotic systems. By addressing these aspects, the research contributes to the development of robots that enhance user assistance and mobility in diverse environments.

III. BLOCK DIAGRAM

The methodology for implementing the Gesture-Controlled & Obstacle Detection Robot involves a structured approach to ensure its functionality and effectiveness. The project begins with selecting and assembling the necessary components, including the flex sensor, vibration sensor, and servo motors. These components are integrated to form the core of the robot's gesture recognition and obstacle detection capabilities.

The first step is the integration of the flex sensor, which is attached to the user's hand to detect specific gestures. The flex sensor's readings are calibrated to correspond with predefined gestures, which will control the robot's movements. The vibration sensor is then incorporated to detect obstacles. This sensor is positioned on the robot to sense vibrations caused by contact or proximity to obstacles, enabling the robot to respond accordingly.

Next, the servo motors are connected to the robot's mobility system. These motors are

programmed to respond to the signals from the flex sensor, translating the user's gestures into corresponding movements. The control system is developed to process the input from both the flex and vibration sensors, ensuring that the robot can follow user commands while avoiding obstacles.

A sophisticated control algorithm is implemented to manage the robot's responses to gestures and obstacles. This algorithm processes real-time data from the sensors and adjusts the servo motors' movements to ensure smooth and accurate operation. The algorithm also includes obstacle detection logic, allowing the robot to stop or change direction when an obstacle is detected.

Testing is conducted in controlled environments to evaluate the robot's gesture recognition accuracy and obstacle detection reliability. The robot's responses to different gestures and obstacle scenarios are observed, and any necessary adjustments are made to optimize performance. Visual indicators or audible alerts are incorporated to provide feedback to the user, ensuring clear communication and enhancing user interaction.

Following successful testing, the robot is fine-tuned based on the results, and a maintenance plan is established to ensure ongoing performance. Finally, the robot is deployed for real-world use, with continuous monitoring and user feedback being utilized to make further improvements. This methodology ensures the development of a robust, efficient, and user-friendly Gesture-Controlled & Obstacle Detection Robot.

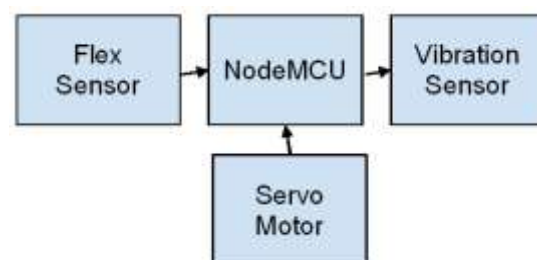


Figure.1: Block Diagram of Gesture-Controlled & Obstacle Detection Robot

IV. HARDWARE COMPONENTS

4.1 NodeMCU (ESP8266)

The NodeMCU ESP8266 is a powerful and versatile platform designed for Internet of Things (IoT) development. The ESP8266 is a cost-effective Wi-Fi microchip known for its capability to enable wireless communication in IoT applications. NodeMCU, on the other hand, is an open-source firmware and development kit that simplifies the process of prototyping and programming the ESP8266. With built-in Wi-Fi connectivity, the NodeMCU ESP8266 allows devices to connect to the internet wirelessly, making it suitable for a wide range of IoT projects. One notable feature is its support for the Lua scripting language, providing a high-level programming environment for developers. Additionally, it is compatible with the Arduino IDE, allowing those familiar with Arduino to use the NodeMCU platform. Equipped with General Purpose Input/Output (GPIO) pins, the ESP8266 facilitates interfacing with various electronic components, making it ideal for applications such as home automation and sensor networks. The NodeMCU ESP8266 has garnered significant community support, resulting in an extensive collection of libraries and documentation, making it a popular choice for rapid IoT prototyping and development.

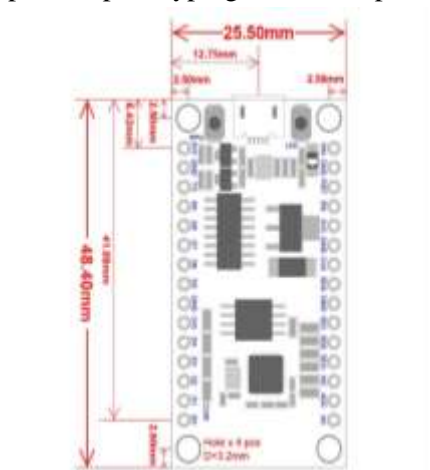


Figure.2: NodeMCU 2D View

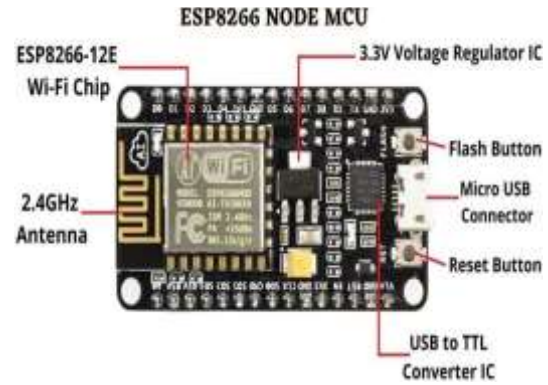


Figure.3: NodeMCU Parts

The NodeMCU ESP8266 development board typically has GPIO (General Purpose Input/Output) pins that can be used for various purposes, including interfacing with sensors, actuators, and other electronic components. Below is a common pinout configuration for the NodeMCU development board

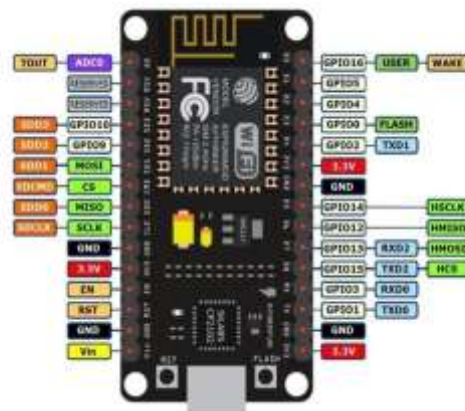


Figure.4: NodeMCU ESP8266 Pinou

4.2 Flex Sensor:

A flex sensor is a device that detects bending or flexing in a material and converts this mechanical deformation into an electrical signal. It operates by changing its resistance in response to the amount of bend applied to it. As the sensor bends, the conductive particles within its structure shift, altering the electrical resistance. This change in resistance can be measured and interpreted to determine the degree of flex. Flex sensors are widely used in applications such as gesture recognition, robotics, and wearable technology, where precise detection of movement or bending is required. They are characterized by their sensitivity to bending, durability, and ease of integration, making them an essential

component for systems that need to monitor or respond to physical movements.



Figure.5: Flex sensor

4.3 Servo Motor:

A servo motor is a type of rotary actuator that enables precise control over angular position, velocity, and acceleration. It consists of a motor coupled with a feedback mechanism, typically a potentiometer, encoder, or resolver, which continuously monitors the motor's position and provides feedback to the control system. This feedback loop allows for closed-loop control, ensuring accurate positioning and motion. Servo motors are widely used in applications requiring precise and controlled movement, such as robotics, CNC machines, 3D printers, and industrial automation. They offer a high torque-to-inertia ratio, enabling them to provide significant torque output while maintaining low inertia for fast response times. Additionally, servo motors can operate at variable speeds, allowing for smooth acceleration and deceleration profiles and precise velocity control. With their compact design, low electrical noise, and easy integration into existing systems, servo motors are essential components in electromechanical systems where accurate motion control is paramount. Moreover, servo motors are known for their high efficiency, which results in minimal energy wastage during operation, making them environmentally friendly and cost-effective.



Figure.6: Servo Motor

4.4 Vibration Sensor

A vibration sensor is a device designed to detect and measure vibrations, which are oscillations of a mechanical system. It works by converting the mechanical motion of vibrations into an electrical signal, which can then be analyzed to determine the intensity and frequency of the vibrations. Vibration sensors typically use piezoelectric elements, which generate a voltage when subjected to mechanical stress. This voltage is proportional to the amount of vibration detected. Vibration sensors are crucial in various applications, such as machinery monitoring, structural health assessment, and safety systems, where understanding and controlling vibrations is critical. They are known for their high sensitivity, accuracy, and ability to detect even minute vibrations, making them vital for ensuring the reliability and safety of mechanical systems.

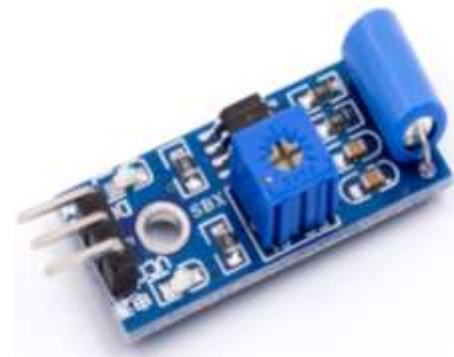


Figure.7: Vibration Sensor

V. CONCLUSION

This study presents the successful implementation of a human following robot prototype. In addition to its sensing ability, this robot also has the following capabilities.

The goal of creating this prototype was also to ensure the robot operated as efficiently as feasible. Tests were run under various circumstances in order to identify and fix algorithmic errors. An further benefit was offered by the several sensors that the robot had incorporated. The human-following robot is an autonomous vehicle system that can detect obstacles and adjust its trajectory to stay on course by moving and positioning the robot accordingly. To accomplish its purpose, this project makes use of an Arduino, motors, and a variety of sensors. The crew was forced to collaborate, communicate, and broaden their knowledge of mechanical systems, electronics, and programming integration as a result of this project.

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