# Obstacle Avoiding Robot Car

**Tanishq Subhash Wavre**

**Sahil Santosh Jaiswar**

Department of Electronics and Computer, Shreeyash Collage of Engineering, CHH. Sambhaji Nagar, India

## Abstract

This paper presents the design and implementation of an obstacle-avoiding robot car using an ultrasonic sensor integrated with an Arduino Uno microcontroller. The project aims to provide a cost-effective solution for autonomous navigation and collision avoidance in robotics. The robot detects obstacles in real-time and autonomously adjusts its movement direction to avoid collisions. The system comprises key components including the HC-SR04 ultrasonic sensor, L298N motor driver, DC motors, and a rechargeable power source The robot is programmed using Arduino IDE and tested under various scenarios. The results indicate a high degree of obstacle avoidance accuracy, proving its viability for basic smart automation applications.

## I. Introduction

The 21st century has witnessed unprecedented advancements in science and technology, especially in the field of robotics and embedded systems. Robotics, once considered a futuristic concept, is now an integral part of modern-day applications ranging from industrial automation and healthcare to agriculture, defense and domestic use. Among the different branches of robotics, mobile robotics is rapidly gaining popularity due to its versatility and ability to perform tasks in dynamic and unstructured environments. A mobile robot is an autonomous or semi-autonomous machine capable of moving through and interacting with its environment. One of the most essential capabilities required for such robots is **obstacle detection and avoidance**. This ability enables a robot to perceive its surroundings and make decisions to avoid collisions, ensuring

Safe and uninterrupted operation. Whether it is a warehouse robot navigating aisles, a delivery robot moving on sidewalks, or a robotic vacuum cleaner in a home .

Obstacle avoidance is a critical feature that determines the effectiveness and safety of the robot. Traditional robotic navigation techniques often depend on human control, predefined paths, or line-following sensors. These approaches are not flexible and often fail when faced with sudden obstacles or changes in the environment. Moreover, such systems require constant monitoring and user input, which reduces their autonomy and limits their use in complex or unknown environments.

. Therefore, there is a growing need for autonomous robots that can independently sense and react to their environment using real-time data. This project focuses on the design and implementation of an **Obstacle Avoiding Robot Car** using an **ultrasonic sensor (HC-SR04)** and an **Arduino Uno** microcontroller. The goal of this project is to create a smart, low-cost, and efficient robotic system capable of navigating autonomously by avoiding obstacles. The robot continuously scans its surroundings using the ultrasonic sensor, which emits ultrasonic waves and calculates the distance based on the time it takes for the echo to return. If an obstacle is detected within a preset range the Arduino processes this data and commands the motor driver (L298N) to change the robot's direction, thereby avoiding a collision. This system is simple yet highly effective, and it serves as an ideal educational and experimental platform for students and enthusiasts looking to understand the basics of sensor-based robotics. It combines the core disciplines of **electronics, mechanical systems, and software programming** into a single working prototype Through this project, one can gain a practical understanding of concepts like embedded C programming, motor control, sensor interfacing, and autonomous decision-making. The application potential of this robot is vast. In the field of **warehouse automation**, similar robots are used to transport goods while avoiding humans or other machines. In **agriculture**, such systems can be used for monitoring and maintaining crop fields. In **rescue missions**, mobile robots equipped with sensors can enter hazardous zones to search for survivors or assess damage, all while avoiding debris and obstacles. Even in **domestic settings**, obstacle-avoiding robots are found in robotic vacuum cleaners and smart home security systems. What sets this project apart is its use of **ultrasonic sensing**, which offers a good balance between cost, simplicity, and accuracy. Ultrasonic sensors are less affected by lighting conditions compared to infrared sensors and are more reliable for short to medium-range detection.

## II. LITERATURE REVIEW

The field of autonomous mobile robotics has seen significant growth over the past few decades, driven by the increasing need for intelligent systems that can operate without continuous human intervention. One of the fundamental capabilities required in autonomous robots is **obstacle detection and avoidance**, which allows robots to safely navigate environments, avoid collisions, and perform tasks efficiently. This capability has been implemented in various forms using different sensing technologies and control algorithms. The concept of obstacle avoidance in mobile robots dates back to the 1980s and 1990s when early systems used **infrared (IR) sensors**, **bump sensors**, and **basic proximity detectors**. These systems were capable of detecting nearby objects but had several limitations, including limited range, poor accuracy, and susceptibility to environmental conditions such as lighting and surface reflectivity. One of the earliest commercially successful robots with basic obstacle avoidance was the **iRobot Roomba**, which used infrared sensors and random navigation algorithms to avoid obstacles and cover floor areas. While effective for simple household tasks, these systems lacked precision and were unable to make intelligent decisions based on complex environmental input. Ultrasonic sensors, such as the **HC-SR04**, introduced a more reliable and cost-effective method for measuring distances. These sensors operate by emitting ultrasonic waves and calculating the time taken for the echo to return after reflecting from an obstacle. The use of ultrasonic waves allows for accurate measurement regardless of ambient light, making them superior to infrared sensors in many conditions. Several researchers and developers have integrated ultrasonic sensors into autonomous robot platforms for effective obstacle detection. A study by **A. J. Gonzalez et al. (2016)** demonstrated that ultrasonic sensors could provide stable and accurate distance measurements for autonomous indoor navigation systems.

The integration of microcontrollers, particularly the **Arduino Uno**, has simplified the implementation of obstacle avoidance systems. Arduino is an open-source microcontroller platform widely used in robotics due to its affordability, ease of programming, and extensive community support. Projects using Arduino-based systems with ultrasonic sensors have become popular in academic institutions and DIY communities. These systems use simple algorithms to detect an object, determine its distance, and decide whether to stop or change direction. **B. Patel and D. Shah (2020)** designed an Arduino-based obstacle-avoiding robot and tested it in indoor environments with varying obstacle arrangements. Their results showed successful avoidance with minimal false detections, highlighting the practicality of ultrasonic sensor-based navigation in low-cost robots. For effective obstacle avoidance, motor control is equally important. The **L298N motor driver** module is commonly used to control the direction and speed of DC motors in mobile robots. It allows for bidirectional movement and PWM (Pulse Width Modulation) speed control. Coupled with sensors and microcontrollers, it enables smooth and reactive robot motion. lawn care, offering convenience, precision, and sustaResearch by **K. Sharma et al. (2019)** focused on optimizing motor control based on sensor feedback to improve turning accuracy and reduce unnecessary movements Their work showed that combining real-time data processing with efficient motor control significantly enhanced the robot's performance in dynamic environments. Modern obstacle-avoiding robots often incorporate multiple sensors (e.g., ultrasonic, infrared, LIDAR) AI-based decision-making to enhance their capabilities. Some advanced systems use **Simultaneous Localization and Mapping (SLAM)** or **computer vision** for mapping unknown terrains and intelligently navigating through them.

However, these advanced systems often involve high costs and complex integration. For educational, low-budget, and prototype-level projects, a combination of **Arduino**, **ultrasonic sensors**, and **basic motor drivers** remains a highly viable and effective solutionDespite their advantages, ultrasonic sensors have limitations. They can struggle to detect soft surfaces, objects with odd angles, or extremely narrow gaps. Furthermore, single-sensor systems may suffer from blind spots, which can be overcome by adding multiple sensors or rotating mounts. From the review of existing systems and technologies, it is evident that ultrasonic sensors, when combined with microcontroller platforms like Arduino, provide an efficient and economical solution for implementing obstacle avoidance in mobile robots. These systems are ideal for educational purposes and foundational projects in embedded systems and robotics. This project builds upon this body of work by designing and developing a compact, affordable, and fully functional **Obstacle Avoiding Robot Car** that utilizes an ultrasonic sensor for real-time environment scanning and automatic maneuvering. By using open-source components and modular hardware, the robot can serve as a base platform for future enhancements such as GPS navigation, AI-based decision-making, and multi-sensor integration.

## III. CONCLUSION

In this project, the design and implementation of an **Obstacle Avoiding Robot Car** using an **ultrasonic sensor** and **Arduino Uno** were successfully demonstrated. The primary goal was to develop an autonomous robotic system capable of navigating an environment while detecting and avoiding obstacles in real time—without human intervention The robot uses the HC-SR04 ultrasonic sensor to measure distances and determine the presence of nearby objects. Based on these measurements, it executes programmed decisions via the Arduino microcontroller to either continue moving forward or change direction when obstacles he system proved to be simple yet effective for basic autonomous navigation. The real-time decision-making process enabled the robot to respond to environmental changes.

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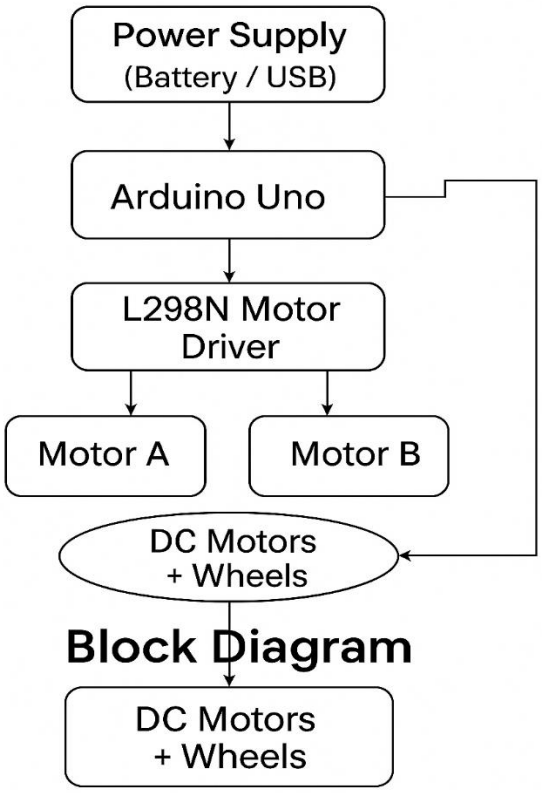


# Obstacle Avoiding Robot Car

**Block Diagram**

## Circuit Diagram