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# Development of an IoT-Enabled Underwater Rover Utilizing Raspberry Pi for Advanced Marine Exploration and Environmental Monitoring

[1] **Ms. Pooja Mallah** , [2] **Dr. Rakhi Gupta** , [3]**Mrs. Nashrah Gowalker**

[1] Student, Masters in Information Technology, K.C. College, HSNC University, Mumbai 400 020, India
[2] Head of the Department, I.T Department, K.C. College, HSNC University, Mumbai 400 020, India
[3] Asst. Professor, Department of IT, , K.C. College, HSNC University, Mumbai 400 020, India
Email - [1]mallapooja476@gmail.com, [2]rakhi.gupta@kccollege.edu.in , [3] nashrah.gowalker@kccollege.edu.in

***Abstract:*** *The development of IoT-based projects presents numerous challenges, particularly in achieving waterproof capabilities for underwater applications. This research aims to address these challenges by developing an IoT- based underwater rover that leverages the Raspberry Pi platform integrated with a camera module or USB webcam for capturing images and streaming live video. The rover is constructed from scratch using CPVC pipes and equipped with thrusters for precise underwater navigation. As a remotely operated vehicle (ROV), it can be controlled from a surface vessel using a user-friendly interface, akin to operating a video game, making it accessible for a wide range of users. Key components of the rover include a Raspberry Pi single-board computer, Pi Camera for visual data capture, and ultrasonic sensors for distance measurement, forming a robust platform for collecting real-time visual and environmental data underwater. This versatile system is designed for applications in underwater exploration, marine research, and environmental monitoring, where its capability to conduct detailed surveys and transmit data in real-time proves invaluable. The Raspberry Pi serves as a powerful central controller for the rover, facilitating not only real-time data acquisition and transmission but also the integration of multiple sensors to enhance operational efficiency and data accuracy. By integrating Pi Camera and ultrasonic sensors, the rover demonstrates significant advancements in marine technology, offering enhanced capabilities for detailed underwater surveys and environmental monitoring tasks. In conclusion, this research contributes to advancing marine technology and research methodologies by providing a scalable and adaptable IoT solution for underwater exploration and environmental monitoring. The integration of Raspberry Pi technology with underwater robotics opens new avenues for scientific discovery and practical applications in marine.*

***Key Words:*** *Underwater rover, Raspberry Pi, live video stream, CPVC pipes, thrusters, remote control, ultrasonic sensors, marine exploration, environmental monitoring, real-time data acquisition.*

## 1. INTRODUCTION:

This paper is focused on the ocean depths. A specialized vehicle designed to perform specific duties beneath the surface, like manoeuvring and recording real- time video. This endeavour could also serve a range of purposes, such as exploring the underwater world, inspecting submerged structures, and keeping track of underwater conditions. The rover has the capability to be operated from a distance and can be directed to move in left, right, up, and down directions. It addresses the difficulty of staying operational in oceanic environments

***A.*** Raspberry Pi.

The Raspberry Pi, a credit-card-sized single-board computer (SBC), is capable of transforming a monitor, TV, mouse, or keyboard into a fully functional PC. Boasting essential computer features such as wireless internet connectivity, HDMI ports, USB ports, and sufficient processing power and RAM for daily tasks, theRaspberry Pi is used in this project for programming the Pi camera to enable live video streaming.

***B.*** Pi Camera

It is possible to connect to a Raspicam module, a USB camera or other network video signals. The system is a RTMP, HLS and SRT server. You need a video source touse it as a streaming server.

***C.*** Underwater Rover

Underwater rovers, also called underwater robots or underwater remotely operated vehicles (ROVs), arerobotic vehicles specifically built to work beneath thewater's surface. Like their space equivalents, underwater rovers are unmanned and remotely operated by personnel on the surface, typically from a support vessel or a control centre. Underwater rovers are essential for investigating and researching underwater environments that are challenging or inaccessible to human divers. They gather valuable information and knowledge about ocean ecosystems, geological formations, and marine life,significantly enhancing our understanding of the Earth's oceans and their resources.

***D.*** Wired Remote Control

A wired remote control for a rover enables the operator tomanage the rover's movements and functions via a direct physical connection, usually through cables or wires. Thiscontrol method is commonly utilized in situations where wireless communication is impractical or unreliable, suchas in environments with high radio interference or when precise, low-latency control is required.

## 2. PROPOSED SYSTEM :

This proposed system leverages the capabilities of wired remote control to ensure reliable communication and precise control over the underwater rover, facilitating efficient data collection and enhancing operational flexibility in challenging underwater environments

a. Design and Construction of the Enclosure:

The robot's enclosure must be fully waterproof and resilient to underwater pressure. It should be designed for easy access to internal components, facilitating maintenance and adjustments.

b. Selection of Propulsion System:

The propulsion system, crucial for determining the robot'smovement underwater, can include options like propellers, thrusters, or water jets. The choice of system should alignwith the desired speed and maneuverability of the robot

c. Testing and Adjustment:

Following assembly and programming, the robot should be tested in a controlled environment to verify its functionality. Necessary adjustments should be made based on the testing outcomes before the robot is deployedin the underwater environment

Below Table 1.1 illustrates the specific commands employed to control the rover with help of wired remote along with their functionalities:

| **Commands** | **Functions** |
|---|---|
| Switch 1 | Moves Forward |
| Switch 2 | Moves Backward |
| Switch 3 | Moves forward |
| Switch 1 **AND** Switch 2 | Moves backward |

**Table 1.1: Commands and Functions**

Table 1.1 provides concise reference to the user, understanding the commands available for controlling therover and detailing the associated functions triggered by each command

## 3. ADAPTIVE LEARNING

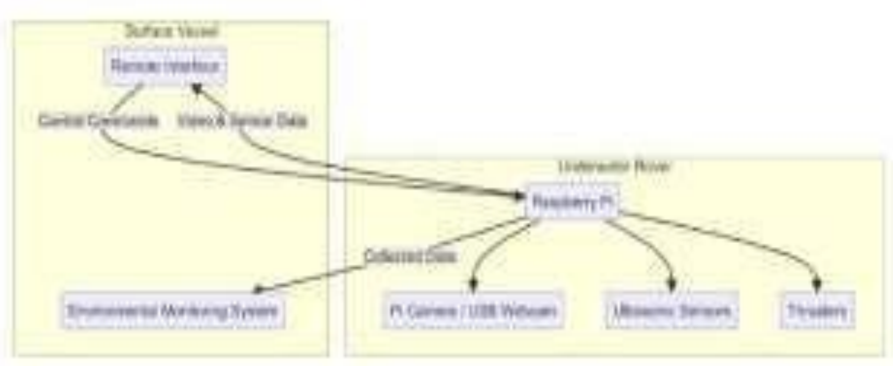


**Figure 1.1: Diagram**

## 4. SURVEY FINDINGS :

| Tests | Depth in Metres |
|---|---|
| Phase 1 | 90 Metres |
| Phase 2 | 150 Metres |
| Phase 3 | 250 Metres |

**Table 2.1: Depth Survey**

## 5. CONCLUSION :

The development of an underwater robot for ocean exploration represents a significant milestone to understand and protect the marine environment. This project has successfully demonstrated the capabilities of modern underwater robotics in addressing the challenges posed by deep-sea exploration, environmental monitoring, and resource management.

Through the integration of advanced sensors, high- resolution imaging, and robust control systems, underwater robot has proven its ability to navigate complex underwater terrains, collect valuable data, and perform intricate tasks with precision. The modular designand adaptability of the robot ensure that it can be equippedwith a variety of tools and sensors, making it suitable for awide range of applications, from scientific research to industrial inspection and conservation efforts.

This paper lays a strong foundation for future innovationsin underwater robotics. By pushing the boundaries of whatis possible, we move closer to unlocking the mysteries of the ocean, ensuring the sustainable use of its resources, and safeguarding its ecosystems for future generations. The success of this underwater robot project reaffirms the vitalrole of cutting-edge technology in advancing our understanding and stewardship of the world's oceans.

## 6. FUTURE ENHANCEMENT :

The future of underwater robots for ocean exploration is brimming with exciting opportunities, driven by technological advancements and growing demands in various sectors. Here are some key areas where this projectis anticipated to evolve:

***a. High-Resolution Imaging:*** Continued advancements in camera and imaging technology, will provide clearer and more detailed views of underwater environments, enhancing the robot's capabilities in exploration and monitoring.

***b. Customizable Platforms:*** Future underwater robots will feature highly modular designs, allowing easy integration of various sensors, tools, and payloads tailored to specificmissions.

***c. Specialized Tools:*** Developing more advanced and preciserobotic manipulators and tools for tasks such as sample collection, underwater repairs, and scientific experiments.

***d. Deep-Sea Mining:*** Future robots will be equipped to explore and extract valuable minerals and resources from the deep sea while minimizing environmental impact.

***e. Archaeological and Geological Exploration***: Underwater robots will increasingly be used to locate and study ancient shipwrecks and submerged archaeological sites, providing valuable insights into human history.

***f. Defense and Security:*** Enhancing capabilities for underwater surveillance and reconnaissance, including anti-submarine warfare and port security. Improving technologies for detecting and neutralizing underwatermines and other explosive devices, ensuring safer navigation for vessels.

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