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COST-EFFICIENT REMOTE- CONTROLLED ROVER USING RASBERRY PI

RAMYA PRIYATHARSINI .T.G , RAMU . M , RAJESWARI . P

Abstract— Our mission's purpose is to develop and build a Raspberry Pi-based remotely operated vehicle (ROV). The Microcontroller is an excellent choice for developing this application and is both economical and efficient. The Rpi has been configured to drive the ROV in response to a remote signal from some other Raspberry Pi. Each switch is programmed to convey a distinct instruction from the distant modules to the hosting component; upon obtaining instruction from the distant component, the functional communication by operating the actuators. The hosting system is connected to heat, humidity, and obstruction detectors. The hosting component is equipped with cameras that record and distributes video recording input to a display next to the distant component. A bright LED is mounted next to the ROV to provide an interesting view of the undersea surroundings. A fully functional ROV can be utilized as undersea monitoring equipment to operate in the hazardous marine ecosystem. It can take water samples from a specific groundwater table. In addition, it can be utilized for undersea high-pressure applications with yet more modifications. The Raspberry PIC16F877A is being used to programme the machine. To communicate among two work teams, the UART interface is employed. Up to a specific extent, this machine can explore underneath.

Keywords— Raspberry Pi, LED, UART, automated guided vehicle

I. INTRODUCTION

A remotely operated underwater vehicle (ROV), sometimes referred to as a connected robotic submarine, is a connected humanoid navy ship controlled by controllers out of a distant ship. One sort of offshore platform is the automated guided vehicle (AUV), which is qualified to drive autonomously undersea to perform certain tasks and has no need for adequate support. The conventional acronym "ROV" refers to "remotely operated vehicle," and that is distinct from "autonomous mobile vehicle models," which can be conducted on the ground or even in the aircraft. Robotic underwater vehicles (ROVs) are unattended, change in dimension, and are commanded by humans. This is attached to the controlling console using an impartial buoyancy tether, a high load-bearing coaxial line, and an attachment points control system while functioning in difficult circumstances or greater depths (TMS). Its tethering monitoring system (TMS) maintains and distributes the ROV tethering connection, allowing the ROV to function at a greater diameter by being disconnected from both the movements of the submerged body. Typically, a barn mechanism holds the ROV in place while being lowered through the high-current zone or on bigger work-class ROVs. TMS works by varying the position of the string due to cable drag to reduce the amount of electricity in the water. The subsea connection, which comprises several wires, transports grid energy, camera, and detailed level between the commander and the ROV. ROVs are classified into two parts: surveillance and operation. The activity category is divided into lightweight and heavyweight, based on their maximal operating depths. Heavyweight class ROVs are capable of delivering depths of more than 3000 meters. A really big propelling plan is necessary to start generating the force needed to pull the amount of cable needed.

Underwater ROVs have usually categorized size, mass, capability, or energy characteristics. The following are a few examples of typical evaluations:

- Micro - Micro class ROVs are generally exceedingly thin and compact. Micro Class ROVs nowadays can weigh as little as 3 kg. These ROVs are employed instead of investigators in locations where divers would be unable to penetrate, including sewage, pipe, or smaller hole.

Ramya Priyatharsini . T.G , Faculty of Information Technology , Dhanalakshmi Srinivasan Engineering College , Tamil Nadu , India.
Ramu . M , Faculty of Information Technology , Dhanalakshmi Srinivasan Engineering College , Tamil Nadu , India.
Rajeswari . P , Faculty of ECE, Dhanalakshmi Srinivasan Engineering College, Tamil Nadu, India.

- Mini - Mini Class ROVs probably weigh approximately 15 kg. Divers can also employ Mini Class ROVs as an option. Yet another individual can bring the entire ROV equipment out on a rubber dinghy, install it, and finish the work without the assistance of others. To distinguish themselves from ROVs that might have been capable of completing remedial measures, certain Mini and Nano subclasses are known as "eye socket" categories.
- General - normally or less 5 HP (propulsion); on rare occasions, including on the earliest RCV 225, modest finger tricksters and vice grips have indeed been added. Smaller ROVs are only used for light surveying which may be sufficient to transport a radar device. The greatest operational depth is usually just under 1,000 metres, while one is being designed that can reach 7,000 metres.
- Moderate Working category - normally under 50 horsepower (propulsion). A few tricksters may well be able to be taken by these ROVs. For example, instead of chrome aluminium compositions, their undercarriage could be composed of polyolefins. Their total peak range is usually just under 2000 m.
- Heavyweight Working category - just under 220 hp (propulsion) and capable of carrying at least three tricksters. They can work at depths of up to 3,500 metres.
- Trench digging - Generally and over 200 hp (levitation) but not more than 500 hp (though some do), only with the capacity to move cabling lying sledge and operate at water up to 6,000 m in certain situations.

Various universities, researchers, the fleet corp, and corporate bodies have contributed to the growth of ROVs in current history. Researchers are focusing on developing ROVs that can perform intensive tasks such as drilling & undersea manufacturing, research in incredibly intense aquatic images, and so on. The ROV PHOCA, for instance, would be a valuable asset in this regard, though it will be going to upgrade, restore, and operate lab instruments on the seabed. Moab and the newest ROV plan to go to their first naval exercises in springtime 2011. Another ROV, Minerva, has already been utilized in biomedical studies and collecting, hardware testing and improvement, archaeological studies, and providing true data in geophysical explorations, sponsored studies, and other applications. It is also just a valuable resource in several NTNU programs. The following are some of the significant gains of this article:

- The robotic may have been used to create a thorough undersea mapping of the bottom at a minimal price.
- Submarine study and specimen collection at various ocean levels might benefit our paleontologists.
- It already has a field of promise, so after some alteration and development of modern techniques, which assists in emergency preparedness by locating drowning aquatic automobiles in the shortest feasible period.
- Build a virtual, reduced ROV that uses water movement, is fueled by an internal battery and is operated by a Pic Microcontroller.
- Our ROV has to be capable of travelling forward and backwards.
- It will be capable of diving to a maximum thickness of 5 metres.
- It will be capable of collecting water samples at a specific depth.
- It will only be able to think and act, such as recording images and movies and identifying submerged things at the foundation phase when submerged.

The term refers to methodical findings in an area of application and a conceptual understanding of the procedures to be included. Aspects of the job's ideas and computational methods are included. It includes paradigms, conceptual basis, stages, and statistical or subjective approaches and assessments. It is not intended to continue providing answers but rather to assist in comprehending the conceptual basis of those which set of procedures or so may be appropriate to do this in a particular circumstance. The formation of perspectives meets all or some of the requirements for technology in general theory. This process is a national collection tendency to result instead of a physical collection.

It has already been formulated as having:

- An examination of the fundamentals of an ideology's techniques, regulations, and propounds.
- A methodical examination of methodologies that are, could be, or used in rigour.

II. RELATED WORKS

Cloud automation is a new area that brings together the principles of cloud technology and intelligent machines. It's a game-changing technology that takes the lead in the development of significant cost cuts in computers, data centres, wifi connections, and low-cost online cloud and edge systems. The Website is utilized to supplement the capability of robotics by freeing him of integer arithmetic activities on boarding and allowing them to perform efficient on-demand solutions. Mechatronics studies the development, building, management, and use of robotics and the data centres that command them, provide haptic stimuli and analyze data. By transmitting instructions and getting messages over a communications system, a human driver can remotely control from such a distance. Mobile robots have had enormous societal and economic consequences on human life during the last few years. Authors have successfully begun using mobile robots as information instruments to understand natural phenomena better. Deep-sea robotics are already being developed to examine distant earthquakes, follow hazardous eutrophication, evaluate weather conditions, and investigate gaseous planets [1], [2]. A server is a company provider that offers architecture, technology, and materials. Infrastructure as a Service (IaaS) is a concept for a business that subcontracts all of its operating supplies, including storage and communication. Whereas the cloud gaming conceptual framework was first established in the digital realm and imposed software as a service (SaaS), it has long been touted to the computer crimes globe, which includes automobiles such as people in cars with cellphones, as well as robotic systems such as land vehicles as well as surveillance drones [3]. Studies have extensively begun to combine cloud services ideas with mobile robotics, for example, [4], [5]. This method has proven especially effective due to computationally demanding areas such as image analysis and intelligence that robotic systems require since these activities consume a lot of capacity, time, and money. The complexity of accomplishing basic functions in a single robot, including such a sensor, actuator, and command, grows dramatically. As a result, the internet robot system delivers various forms of assistance. The rise of Robotics as a Service (RAAS), which is similar to scheme design [6], is an important linked scientific revolution. Despite the enormous possibilities of internet robotic devices, almost all current studies have concentrated on fog control of wheeled robots or limbs. For instance, Kehoe et al. [7] used cloud-based applications to control a manipulation attached to mobility mobile robots. Their method uses the Internet Glasses Vision-Based Technology to manage the recognition process, position estimate, and grab popular home objects, and then save the findings on a remote server. The usage of internet-connected robotics for delivering everyday activities utilizing onboard tricksters to assist elderly and disabled people has been suggested by Kamei et al. [8]. [9] proposes combining the perception mechanical management of tricksters with cloud applications. Scientists in automation have increasingly focused on using cloud computing in both single and wireless interconnected mobility robotic devices. [10] investigated true tool paths for robotic systems on the internet utilizing integer arithmetic optimization techniques. In [11], researchers used fog inter graphics compute nodes to analyze 3D perception alterations in robotic textures for navigational reasons. In recent years, an amount of smartphone robot devices have indeed been created for detecting factors on high seas and dangerous eutrophication and eruptions. In the surveillance of large regions, portable robotics with sensing devices have many benefits: minimal rates, simplicity of automating, extensive management reach, and adaptability [12]. Several studies, for example, [13], [14], have studied interior and exterior sensing devices utilizing the robotic system. Boots are little mobility robotics designed to capture images that will be processed in the cloud utilizing Microsoft Windows Azure [15]. Nevertheless, since these

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robotics are so tiny, they are unsuitable for use in both inside and outside authentic situations.

III. PROPOSED SYSTEM

One goal of the development is to produce a teleoperated undersea robotic that can travel vertically and horizontally, feel temperatures, detect impediments, and deliver a camera feed to serve as an observing vehicle. That's not a simple task to formulate a strategy that is a complete failure. Thus far, the majority of the components have worked out well. We've compiled comprehensive circuits consisting of two sections (distant and hosting) that are fully functioning in communication and operation. It can sense both temperatures and obstacles. The electronics effectively regulate the engine to maneuver the ROV undersea and gather samples from a specific groundwater table. A significant amount of time was spent on physical operations and fault detection in this application. The lack of information and prior experience with semiconductors has become a significant disadvantage that we have fought to learn how to overcome. The charges used throughout the ROV are not intended for recreational use. The ROV circuits could've been burned if the improper connections were brief. Upcoming plans must examine the reliability of the semiconductors' construction. The experimental ROV is operational, despite significant limitations. The need for an inner structure is reduced due to the decision to accept a skeletal casing. It can tow a substantial portion of cabling from either the ROV. The entire premise has been enhanced, and the flow has been improved. This part describes the development's overall network art and design. It also explains the benefits of the strategy and its ramifications. The technology that is being used and future expectations of technology enhancements are also highlighted. There are four primary parts to fundamental architecture.

1. The controller
2. Propulsion
3. sensors
4. Communication

1) Controlling unit

There are two pieces to this remote controller. There are two types of modules: distant and hosting. The component can be accessed remotely. The system's primary tracking and monitoring equipment are the distant modules. It determines when a conversation should begin and then when it should terminate in the hosting component.

It can converse with the hosting modules. The controller device is attached to the hosting modules using two known UART connections. The connection between the hosting and distant modules is not simultaneous since they are linked to various aspects. The distant capsule's job is to deliver commands to the hosting component. It also collects data from the hosting modules and displays that on the Lcd screen so that the user may manage it easily and comfortably. Figure 1 depicts the distant component's working process. The distant module's important parts include an MCU, various actuators, an adjustable resistor, a GLCD screen, and a TFT screen. The hosting device senses the modulation and demodulation output of the detectors. It senses analogue signals from the detectors using an ADC, momentarily saves the existing information, and transmits it to the distant component. This hosting module also gets big quantities of information from the distant subsystem and follows them by implementing the instructions.

Consider the following scenario:

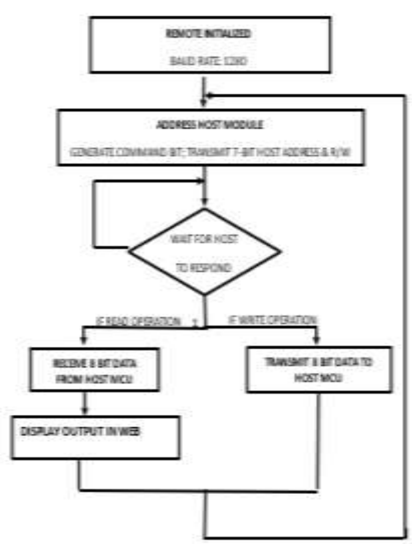

Figure 1. Remote module operating sequence

It may turn on or off the thrusters and raise or reduce the switching frequency of a Pulse Modulated Signal (PWM) to modify the velocity when it repeats demands from the distant module. The following flow figure describes the operating system process (Figure 2).

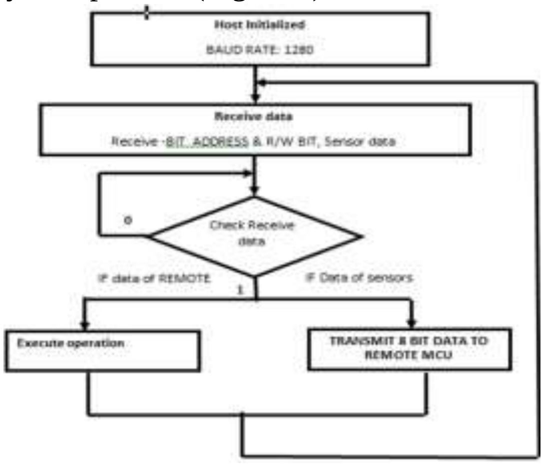

Figure 2. Host module operating sequence

2) Propulsion

Propellers are used to propel all widely viable ROVs. Thrusters are propellers that are connected to electromagnetic or mechanical actuators. Surface waves and rotors are the two main forms of rocket engines. Due to the obvious effectiveness disparity among rotors and sprayers at slower revs, currently accessible ROVs use launchers. Sprinklers function by rapidly raising the speed of a tiny control volume. Consequently, spinners perform better at slower revs, while jets of water perform faster than average velocities. Spray nozzles, for instance, are commonly utilized in elevated sailboats, while blades are commonly used in reduced boats. The equation of motion is depicted in Figure

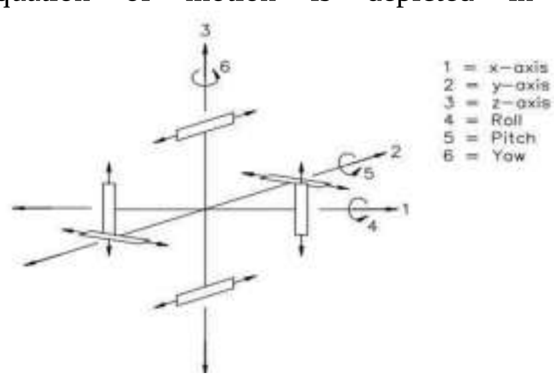

Figure 3. Degrees of freedom

3) Sensors

Sensors are devices that react to noxious stimuli such as temperature, lighting, noise, gravity, magnetic, or a specific movement by transmitting input to measure or manage. The devices are made up of the large device. Temperatures, moisture, the existence of aspects environmental, illuminance, and other parameters are typically measured by such sensors from their surroundings. The hosting component's purpose is to prepare the sensor's outputs for a converter or other content sample design, then do the translation and permanently return results. Afterwards, whenever the translated sensing data is required, the distant modules will gather most of it for showing purposes. These are information from the surroundings that must be watched and evaluated. Some judgments made by the computers are based on the observations, which the masters will subsequently instruct to do certain activities on the agent devices.

4)Communication

The interaction between the distant component and the hosting modules is achieved using two-line sequential connections. For aesthetic reasons, the hosting modules gather data first from distant modules and provide it to the distant component via cable. Sequential communication is the process of communications utilized on the universal serial bus. There are several types of the serial port which can be used. The following are some of the most often used synchronous serial frameworks:

1. RS-232
2. Universal Serial Bus (USB)
3. Ethernet
4. Serial Peripheral Interface (SPI)

USB and the Internet were elevated messages amongst different media topologies. Every conversation has its methodology, which is distinct from the others and relatively complicated. However, RS-232 is a widely used set of protocols. It's simple to set up; however, it's a slow network technology. The RS-232 protocol is a slow networking standard. USB and Gigabit, on the other hand, are elevated connections. However, we utilized RS-232 for the serial port in our design since an Internet connection is complicated, while

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USB is only productive and useful for absurdly short-range information transfer. RS-232, on either extreme, is simple to set up if used for greater distances communications than USB, making it ideal for our purpose. UART is a sequential system that transmits cables and a commonality to communicate Pi-based Pis. It's a quick and easy approach that's perfect for our purpose.

IV. SYSTEM DESIGN

The method of completing the circuitry and connecting it to the body is outlined. At the beginning of the assessment process, we constructed the circuitry on a PCB. Next, we looked for any errors or problems. We ultimately constructed the circuitry in the Computer motherboard and soldered the connections meticulously after resolving the problem discovered in the main method. Afterwards, we put it into action within the ROV's shell. Next, we looked to see any chance of liquid seeping. At this point, the batteries were installed within the ships and the lens and LED light. Lastly, we put it through its paces in drying, stationary, and reactive damp conditions. This flow chart depicts the basic operating method, the route of signal flow among MCUs (Raspberry Pi units), and the relationship between MCUs and other based designs. The distant component comprises an MCU, a GLCD, and a TFT Display screen, as indicated in the flow chart. The MCU of the hosting OEM harness connects to the MCU, engine, pumping, lens, and LED lights to make up the hosting modules. Reversible interaction occurs between the faraway component and the hosting component. When the device is switched on, the distant capsule's MCU gives a notification to the hosting component. The hosting component's MCU takes input and turns just on motors, pumps, and LED by choosing various pins, positive or negative. This collects sensed data and delivers these to the distant component's MCU on either extreme. The information is accessed by the distant component's MCU, which displays that on the GLCD. For example, the phone's live video could be sent to the hosting component, and the images are shown on the distant component's TFT Led screen. The Microcontroller inside the hosting component controls a few different sorts of circuits. These are briefly mentioned using a try figuring beneath (Figure 4).

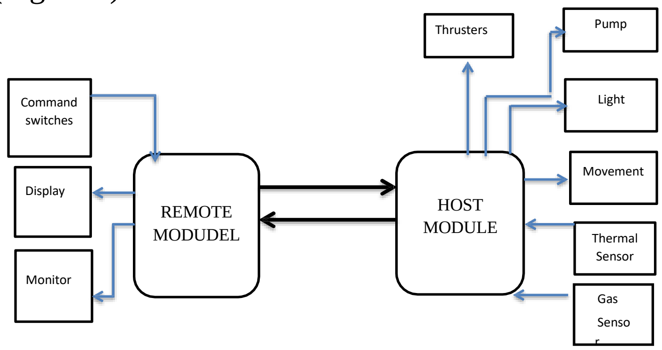

Figure 4. Block diagram of the complete circuit

V. RESULTS AND DISCUSSION

Simulations will be used to test modelling in this part. The many tests used will be detailed, followed by some conclusions and recommendations. A number of tests are required in order to achieve model correctness, try the system, and test the controller. Dry testing, static wet tests, and active wet tests are the three number of assessments that have been performed. Figure 5 depicts the design's prototype model.

Figure 5 . Prototype design

A model was constructed in PROTEOUS as a testing workbench to check the model generated in chapter modelling and estimate the real-time working procedure. Its primary goal is to verify that the models behaves as expected, calculate the required model upgrades and adjustments, and comprehend options and ideas for putting the circuit together. The system block is a block that contains all of the information about the system. This module simulates the behaviour of the system in response to a specific input signal. The controllers are the ones in charge. It is best to understand the controller's behaviour by using the switch. The remote's hardware includes a pulsed switch, Raspberry, LCD, and TFT LCD. The Raspberry unit has been connected to the pulsing switch and LCD. The remote's responsibilities include sending commands to the host module, receiving feedback, and processing data. The LCD displays the sensor output after it has been received and processed by the Raspberry Pi. Whenever a pulsed button is turned, a distinct character is generated for each individual switch linked to a separate Raspberry Pi pin. This means that each created character has a unique ASCII value. It delivers the Ascii value to the host module's Raspberry Pi for processing. A total of 15 switches are wired as input pins to the Raspberry Pi. Twelve of them regulate the motors' direction of movement and turn them on and off. Two of them are in charge of the motor's speed. One switch was used to turn off the device completely.

The circuit of the host module of numerous switches, Raspberry Pi, set of hardware, energy MOSFET, heat sink BJT, sensor, and other components. The Raspberry Pi unit has been connected to the sensor and motor driver circuits. The host's job is to accept commands from the distant module and respond appropriately by turning on various motors, lights, and pumps. It also communicates the sensor data to the remote module, which is shown on the LCD. When a pulsed switch in the distant module is pressed, the ASCII value is sent to the host module's Raspberry Pi. The data is received by the host module, which then takes action.

Figures 6 and 7 depict a simulation diagram of the remote and host modules, respectively.

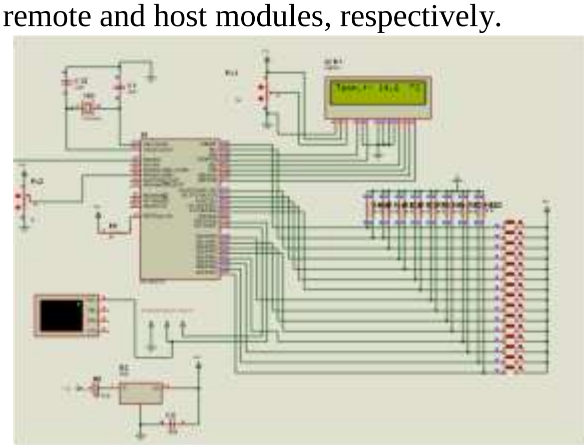

Figure 6. Simulation diagram of remote module

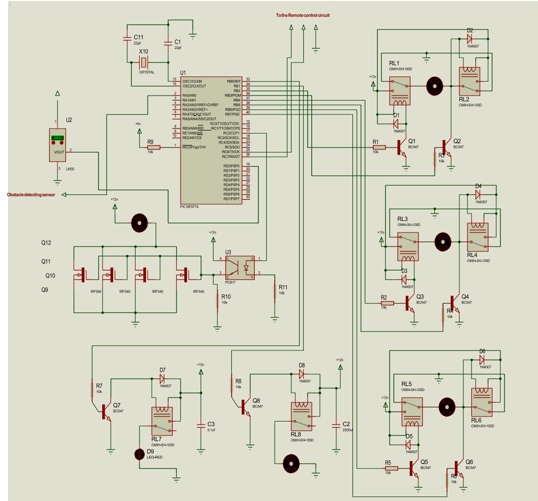

Figure 7. Simulation diagram of host module

This section's experiments and tests guarantee that the ROV is fully functional. Various types of run time errors can arise. During the test time, a last check is performed to see if there are any issues. If an issue is discovered that could cause the device to malfunction or hurt it, quick recovery actions are conducted to assure the ROV's optimum safety.

VI. CONCLUSION

This work aimed to develop and build a basic, reduced submersible vehicle ROV. We had been using a Microcontroller as a foundation and reduced local products to complete our design. Our project aims to create an ROV with elements that could receive sensed data and function in an aqueous electrolyte. We were able to create a compact, reduced ROV. When compared to real observational ROVs, the price is reasonable, and given that this is a model, there is a good likelihood that mass manufacturing prices will be lower. Our ROV design could be useful as an undersea surveillance bot despite various limitations. Our project has a lot more room for investigation and development. It can be used for business reasons with additional customization and enhancement of technical tools. Because this is a basic emerging field, there would be the potential for many adjustments and the addition of other senses to better the venture. Standardization instructions might be delivered first from the PC to the sensors via the PIC, eliminating the requirement for accessibility to the sensor/camera box if the program USART was fully implemented. The ROV's geolocation measurement would be substantially simplified due to this. The ROV can then be operated from the PC, and the streaming server could've been viewed on the laptop screen. When a computer manages it, a MATLAB simulator might be implemented to identify things automatically via picture analytics. As a result, it might become an autonomous system with the addition of extra detectors. Just the image sensor position information is stored to streamline conversations. The sensors can also produce sensor data, which can be sent to the PC through the PIC for the patient's benefit. A variety of other valuable detectors could've been incorporated into this ROV to improve its performance.

A gyro, for example, might assist it in maintaining its equilibrium while going underneath. A servo motor could've been connected to a sea route, an oil rig, or the deck of a vessel to undertake undersea operations such as replacing components. Cracks and flaws on the bottom of the ship, undersea oil/gas pipes, and underground cables could be detected using X-ray.

A steep engine might be employed only with the support of a tall AC source to undertake submerged massive excavating. If observing an item in the sea laterally is impossible, additional lenses may be mounted on the ROV's beams. A retractable lens might be stretched well outside the vessel and then turned upon arriving at the desired location. Most of these are another few ideas for future research.

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