iJRASET
International Journal For Research in Applied Science and Engineering Technology

INTERNATIONAL JOURNAL FOR RESEARCH

IN APPLIED SCIENCE & ENGINEERING TECHNOLOGY

Volume: 9 **Issue:** V **Month of publication:** May 2021

DOI: https://doi.org/10.22214/ijraset.2021.34374

www.ijraset.com

Call: 08813907089 | E-mail ID: ijraset@gmail.com

International Journal for Research in Applied Science & Engineering Technology (IJRASET)
ISSN: 2321-9653; IC Value: 45.98; SJ Impact Factor: 7.429
Volume 9 Issue V May 2021- Available at www.ijraset.com

Thermal Screening UAV to Detect Heating Issues in Solar Panels and Heating Towers

Akash Patil[1], Sarthak Raut[2], Aashikesh Sawant[3], Mayur Shigwan[4], Prof. Shadab Ansari[5]
[1, 2, 3, 4]*Student,* [5]*Assistant Professor, Department of Mechanical Engineering, Theem College of Engineering, Boisar*

Abstract: ***Nowadays, Power Plants, Solar panels, Heating Towers and, large windmills are often located in remote areas and sometimes have heating issues. To detect these issues an operator must climb these high spaces and check for heating issues. So It involves a risk of life. It incurs high costs for sending multiple teams with safety gear to numerous towers and panels. It requires tons of your time to climb every single tower and check issues manually. So for a simple process, we propose a replacement system whereby we use a thermal screening drone to instantly scan for heating issues at a really fast pace. The drone uses a controller to work for the flight and ensure an extended range control.***
The thermal sensor may be a low-resolution sensor that will be wont to find thermal heating issues from a close range of objects. The thermal sensor footage is recorded using raspberry pi for later screening. Thus the drone automates and adds safety to the thermal screening process. In this way, we will ease the method and help industries to take care of more safety to avoid accidents.
Keywords: Thermal Screening, Drone, Solar Panel, Heating Towers, Thermal sensor

I. INTRODUCTION

A Drone or Quadcopter may be a Vehicle that features a large potential for performing tasks that are dangerous or very costly for humans. Examples are the inspection of high structures, humanitarian purposes, or search-and-rescue operations. One specific sort of Drone is becoming increasingly more popular lately: the quadcopter. When visiting large events or parties, professional quadcopters are often seen that are wont to capture video for promotional or surveillance purposes. Recreational use is increasing as well: for fewer than 50 Euros a little remote-controlled quadcopter is often bought to fly around in your front room or garden. In these situations, the quadcopter is typically in free flight. there's no physical contact between the environment and therefore the quadcopter and no cooperation between the quadcopters If would have the capabilities to collaborate the number of possibilities grows even further. for instance, a gaggle of Drone would be ready to efficiently and autonomously search a missing person during a large area by sharing data between.

Or, the combined load capacity of a gaggle of quadcopters is often wont to deliver medicine in remote areas. This bachelor thesis focuses on the utilization of a commercially available quadcopter platform, the Drone, to perform a task that needs physical collaboration and interaction: moving a mass. during this way a transparent interaction between the quadcopters and their surroundings is present.

As a preliminary step towards the view of collaborating aerial robots, the selection was made to perform this task in an inside scenario where position feedback is present. beginning with position control, additional controller logic is often implemented to counteract the forces imposed by a mass connected to the quadcopter. the selection is formed for the Drone, a generalized approach is chosen where possible to encourage the reuse of this research's outcome and deliverables.

A Drone has the potential for performing many tasks where humans cannot enter, for instance, heat and high altitude surveillance in many industries, rescue missions.

A Drone (Quadcopter) has four propellers with motors that generate the thrust for lifting the aircraft. A drone is additionally called the Quadcopter. the essential principle behind the quadcopter is, the 2 motors will rotate within the clockwise direction the opposite two will rotate in an anticlockwise direction allowing the aircraft to vertically ascend. While taking the flight with the assistance of a camera we will have live streaming and capture images.

A. Thermal Screening

Thermal screening and scanning is non-invasive, uses no radiation, a procedure that detects, records, and produces a careful analysis and pictures of skin surface temperature patterns (body heat) as a mirrored image of normal or abnormal human physiology. Thermal imaging may be a method of using infrared and thermal energy to collect information about objects, so as to formulate images of them, even in low visibility environments. It's a kind of technology that has built up a broad range of uses over the years.

©IJRASET: All Rights are Reserved

ISSN: 2321-9653; IC Value: 45.98; SJ Impact Factor: 7.429
Volume 9 Issue V May 2021- Available at www.ijraset.com

II. METHODOLOGY

The consideration and planning for developing the UAV are as follow: -

A. Selection of gathering of components required to form a drone, Components like BLDC motor, frame, flight controller, etc.
B. Calculation of varied Forces, Calculation of motor rpm, Thrust of motor, the torque of the motor, the voltage required to run the motor, safety factors, coding, etc.
C. The most vital thing within a thermal screening drone is to pick parts like motor and frame because this helps to hold the load on the drone and lift the drone in the air. Also, the flight controller is named the brain of the drone because this provides stability to the drone and control all the movements.
D. Determining size of drone according to application, design in a 3D software and analysis.
E. Preparation of part drawing with all the small print and sending for manufacture to realize product with maximum precision.
F. And eventually manufacturing or assembling and collecting components.

Selection Of Components

SR NO	COMPONENT	QUANTITY	WEIGHT IN GM
1	Drone Frame	1	200
2	BLDC Motor 1000 Kv	4	235
3	Propellers 1045	4	45
4	ESC 30A	4	100
5	Flight Controller (APM 2.8)	1	60
6	Shock Absorber For APM	1	60
7	Thermal Camera AMG8833	1	10
8	Raspberry Pi Zero W	1	10
9	GPS Module M8N	1	25
10	Procus Action Camera 4K	1	58
11	LiPo Battery 2200 Mah	1	265
12	Power Module (5.3V/3A)	1	10
13	Electrical Components	NA	100
		Total Weight	1178

Table .I Components list

III. DESIGN OBJECTIVE

The basic objectives of the projects are: -

A. To Detect the heating issues in Solar panels, Windmills, and Antennas.
B. To reduce the time required to examine Solar panels.
C. To reduce the workload on workers and save their life.
D. To increase lifetime of Solar panels. A sincere attempt is made to accomplish most objectives as mentioned above and make it practically feasible.

©IJRASET: All Rights are Reserved

ISSN: 2321-9653; IC Value: 45.98; SJ Impact Factor: 7.429
Volume 9 Issue V May 2021- Available at www.ijraset.com

IV. COMPONENT FUNCTION AND SPECIFICATION

1) *BLDC Motor:* A brushless DC motor (BLDC motor), also referred to as an electronically commutated motor and synchronous DC motors, are synchronous motors powered by DC electricity using an inverter or switching power supply that produces an AC current to drive each phase of the motor via a closed-loop controller. The controller provides pulses of current to the motor windings that control the speed and torque of the motor BLDC motors are rated in kV where it rotates 1000 RPM per 1V supplied thereto if its rating is 1 kV. Each BLDC motor is capable of manufacturing 750 g of thrust force counting on kV rating. Motors are selected based upon their kV rating.

Fig.1 BLDC Motor and ESC

2) *Flight Controller Board:* It constitutes the brain of the craft. It gives the craft its stability and prevents it from wobbling or losing its balance. It calculates the quantity of thrust needed to balance the craft by adjusting the speed of the rotors. It controls the speed of the rotors. It contains inbuilt gyros which help to take care of the steadiness of the craft by sending out electronic signals to the motors by controlling their speed so as to catch up on the thrust of every motor hence these gyros help to stay the craft steady.

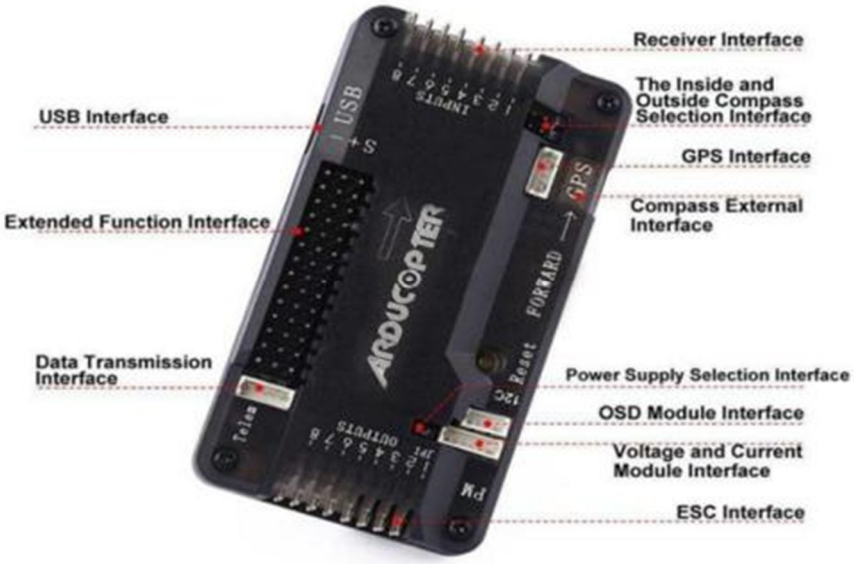


Fig.2 Flight Controller Board

©IJRASET: All Rights are Reserved

3) *Frame:* The body of the Drone is formed of synthetic material to stay it light but sturdy. it's 'X' shaped having four arms stretched in opposite directions. the ideas of the arm are fitted with a power-full brushless motor which can help to lift the craft. It consists of a platform which can mount the flight stabilizer and GPS system..There are two main things to note about the frame of your drone. the primary being what percentage arms there are. Each arm will normally have one motor, which may have one propeller.

Fig.3 Drone Frame PA66GF30 Material

4) *Thermal Camera AMG8833:* Add heat-vision to the project with an Adafruit AMG8833 Grid-EYE Breakout! This sensor is consists of an 8x8 array of IR thermal sensors. When connected to any microcontroller like Raspberry Pi it will return an array of 64 individual infrared temperature readings over I2C. It's like those fancy thermal cameras, but compact and straightforward enough for straightforward integration. This sensor will measure temperatures starting from 0°C to 80°C with an accuracy of +-2.5°C. It can detect a person's from a distance of up to 7 meters (23) feet. With a maximum frame rate of 10Hz, It's perfect for creating a human detector or mini thermal camera.

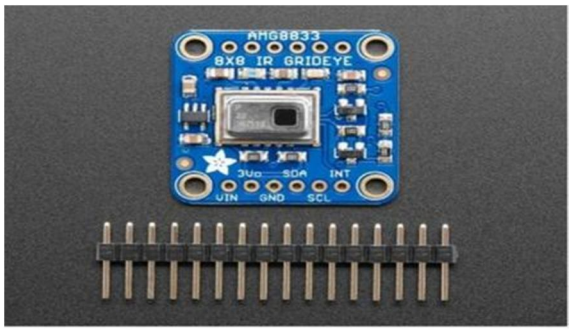


Fig.4 Thermal Camera

5) *LiPo Battery:* Lithium-Ion Polymer (LiPO) batteries are utilized in quadcopters. The cells in batteries are 3.7V per cell and may produce a huge amount of current for the BLDC motors. These batteries are rated supported their C-ratings. It takes completely two hours for full charging. a totally charged battery are often used for 20 minutes during a quadcopter depending upon the payload as shown in Fig.5. So maximum source power it can provide is 75A. LIPO batteries can't be used below 80% of the utmost capacity.

Fig.5 LiPo Battery

©IJRASET: All Rights are Reserved

V. WORKING PRINCIPLE

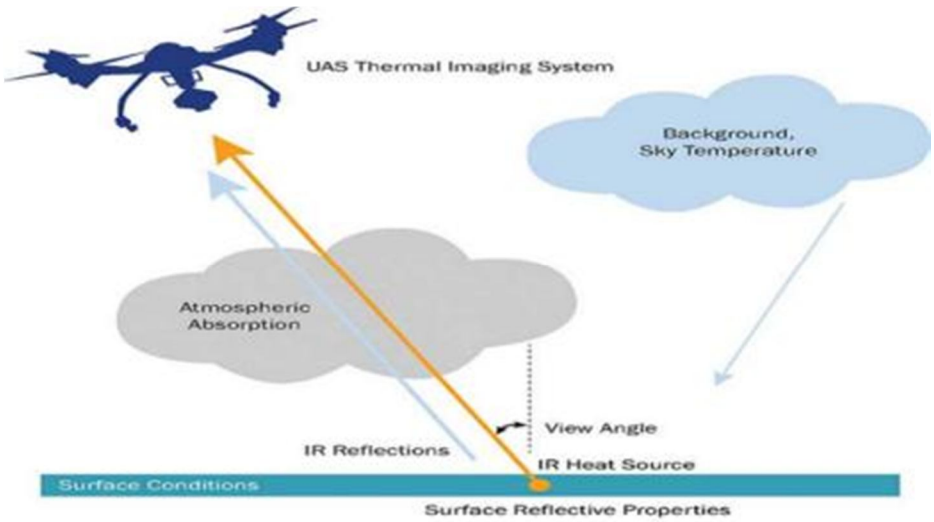


Fig. 6 Working of Thermal UAV

Thermal scanning and screening are based upon the science of infrared energy (otherwise referred to as "heat"), which is emitted from all objects. This energy from an object is additionally mentioned because of the "heat signature", and therefore the quantity of radiation emitted tends to be proportional to the general heat of the thing.

Thermal cameras or imagers are sophisticated devices comprised of a sensitive heat sensor with the capacity to select up minute differences in temperature. As they gather the infrared from objects during a particular environment, they will start to map a picture supported by the differences and inflections of the temperature measurements. In general, thermal images are grayscale: with white representing heat, black representing colder regions, and various reminder grey indicating gradients of temperatures between the 2. However, newer models of thermal imaging cameras actually add color to the pictures, so as to assist users better identify distinct objects more clearly – using colors like orange, blue, yellow, red, and purple.

The results showed that when only weather change is taken into account, the margin of error might be acceptable for a few applications (the error in annual demand was less than 20% for all weather scenarios considered). However, after introducing the renovation outline, the error value increased up to 59.5% (depending on the weather and renovation scenarios combination considered).

The value of slope coefficient increased on the average within the range of three .8% up to eight per decade, which corresponds to the decrease within the number of heating hours of around 22-139h during the heating season (depending on the mixture of weather and renovation scenarios considered). On the other hand, function intercept increased by 7.8-12.7% per decade (depending on the coupled scenarios). The values suggested might be wont to modify the function parameters for the scenarios considered, and planes are often used for large-scale airborne temperature mapping to document temperature signatures on the size of whole suburbs directly. Compared to the previous approach, the latter is more encompassing, but it's also costlier and fewer controllable. Yet, the logic of the way to use a mixture of IR and UAV technologies as an IR survey solution isn't clear. Developing a protocol for the way to perform thermography surveys is therefore needed.

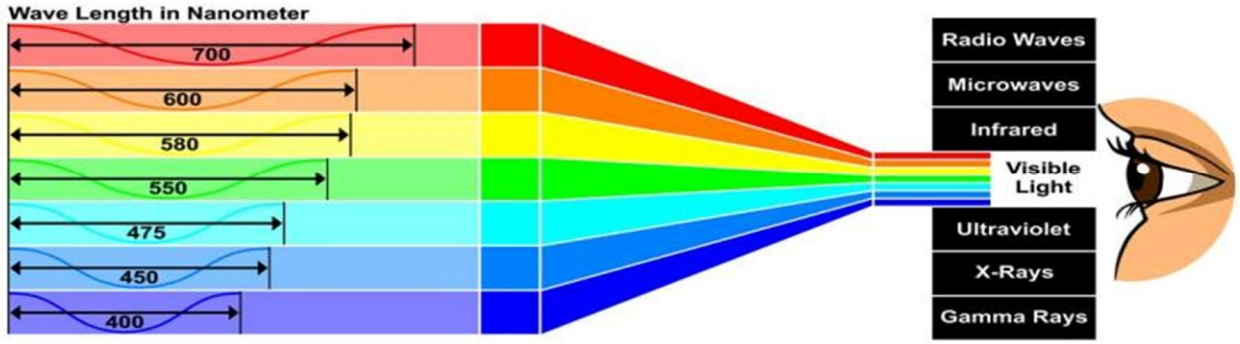


Fig 7. Wavelength Of light

©IJRASET: All Rights are Reserved

ISSN: 2321-9653; IC Value: 45.98; SJ Impact Factor: 7.429
Volume 9 Issue V May 2021- Available at www.ijraset.com

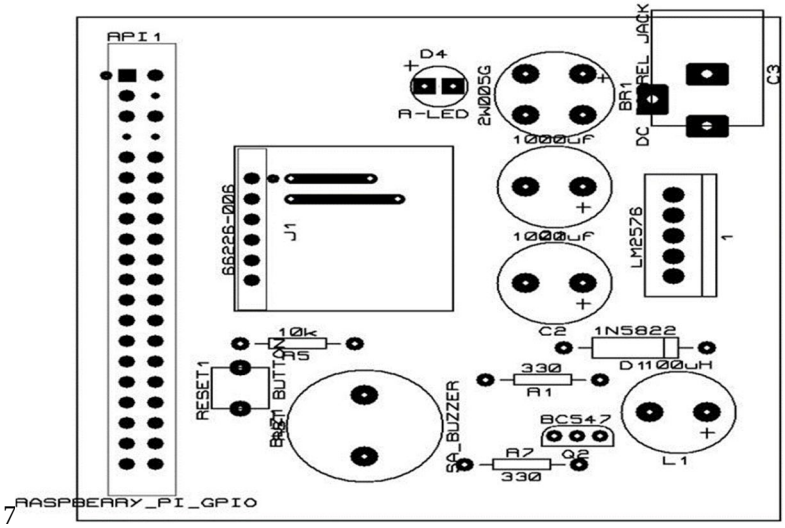


Fig. 8 Circuit Diagram Of Thermal Screening

A. Advantages

1) Easy to detect heat issue in solar panels and antennas.
2) Just a single team can inspect a number of towers/ panels.
3) Temperature Range: 0°C to 80°C (32°F to 176°F)
4) The inspection that required hours of time can be done in minutes.

B. Applications

1) Thermal Imaging
2) Rescue Operations
3) Gas leakage detection
4) Surveillance
5) Disease Control

VI. RESULT

A. Thermal Screening Results

1) It can detect humans from distances as far as 7 meters (23) feet.
2) Operating Voltage: 1.6V - 3.6V and Temperature Range: 0°C to 80°C
3) The accuracy is + - 2.5 ° C (4.5 ° F).
4) 64 pixels at a selectable rate of 1-10 samples per second

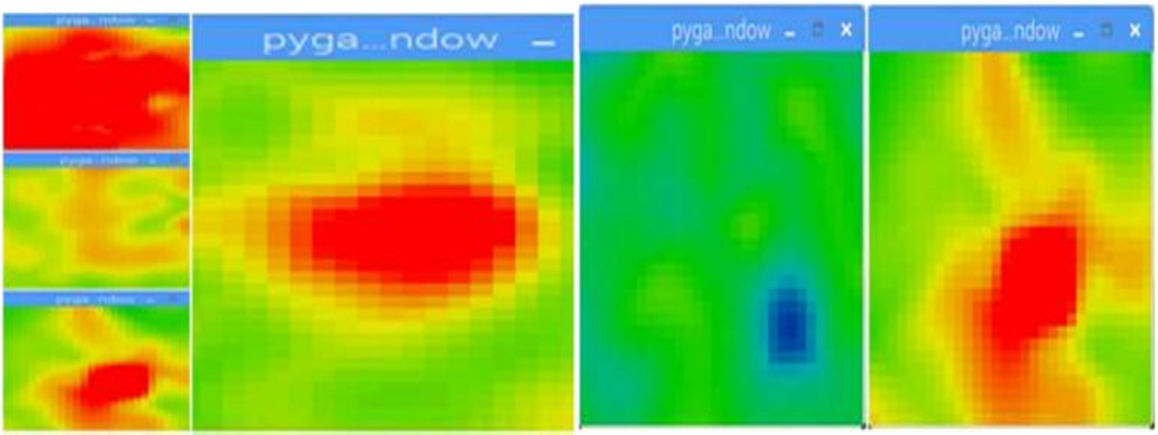


Fig. 9 Thermal images

©IJRASET: All Rights are Reserved

B. Drone Results

1) Altitude: 800 – 900 m
2) Latitude: 1000 m
3) Flight Time: 15 Min
4) GPS Enabled
5) Easily Take-off and Land
6) Automatic landing

Fig.10 Thermal Screening UAV

VII. CONCLUSION

In this project, we've found numerous point which must be booked into while designing the Thermal Screening UAV. the planning and motive of Thermal screening UAV are to extend the lifetime of panels, Towers and reduce the value required for scanning. Our drone uses a mixture of a video camera and thermal camera to urge the close-up solar array, electrical tower footage along thermal scan footage. The is design in such how that it can carry 1.5 Kg of payload altogether conditions.

The objective of Thermal Screening Drone is

A. Successfully fabricated Thermal Screening UAV.
B. Better thermal imaging at low cost.

Our UAV (drone) is far durable, Low cost and anyone can fly it. The drone uses a controller to work for the flight and ensure long-range control. It makes use of RF transmitter and receiver frequency to send and control commands from the user RC remote. Further testing and modification will significantly improve its thermal imaging range and make it autonomous. We consider the experience we got with designing and therefore the UAV could help within the industries.

VIII. ACKNOWLEDGEMENTS

We take the prospect to direct our sincere thanks and gratitude to Hon. Principal, Prof. Dr. Aqueel Ahmed Shah, and Management of Theem College of Engineering, for providing motivation and far support throughout our project work. we might wish to gives our heartfelt thanks towards our Prof. Shadab Ansari and Prof. M.A. Gulbarga for his or her help, guidance, and encouragement, during the Project. Also, we are heartily thankful to all or any Lecturers in Engineering and professors within the Mechanical Department. We were motivated by the encouragement of our professors and this made us complete our work under their oversee.

IX. FUTURE SCOPE

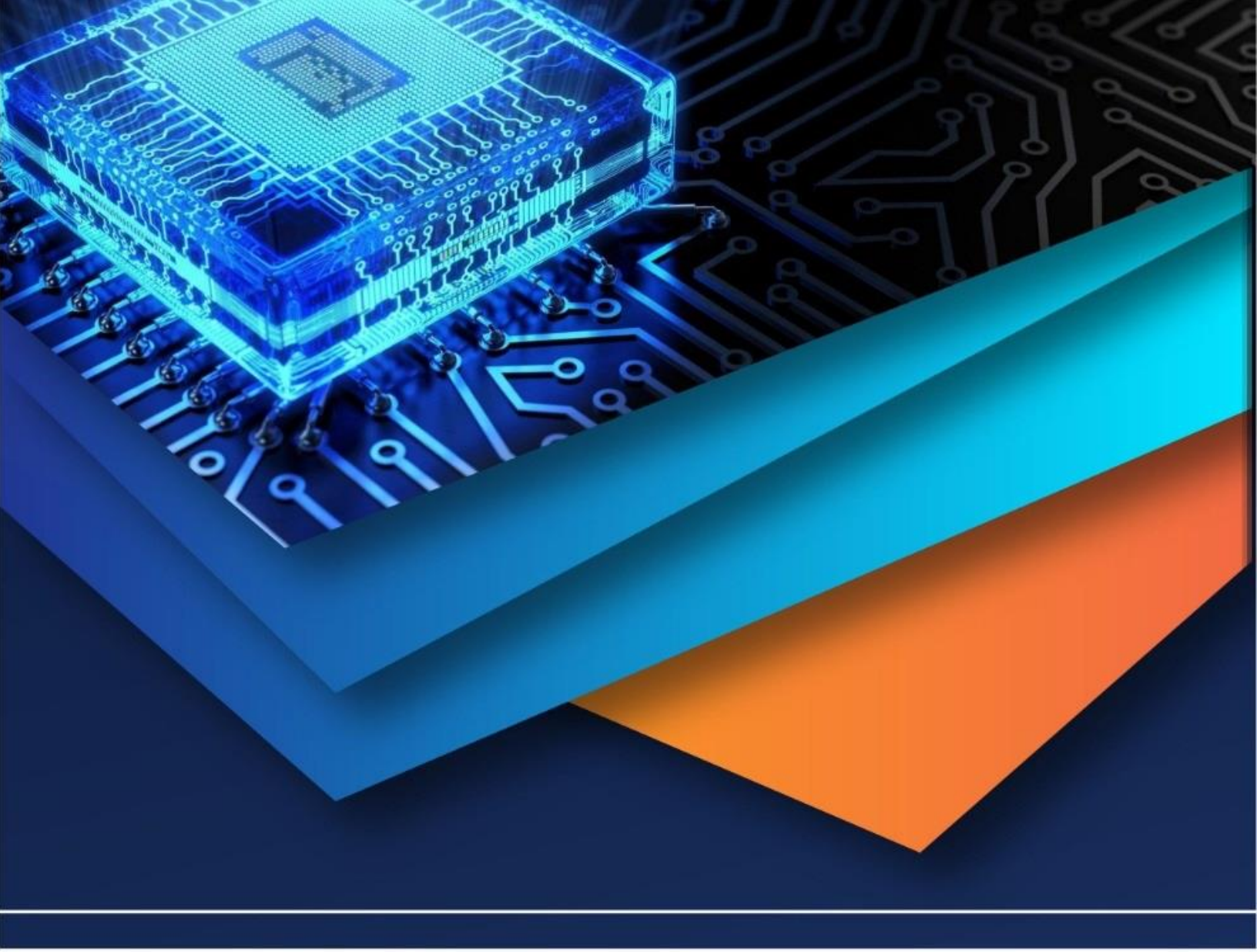
A. By modification we can make drones autonomous.
B. Suitable to detect any heating issue if we improve thermal imaging.
C. Improve battery can give more flight time and efficiency to drone.

©IJRASET: All Rights are Reserved

REFERENCES

[1] Drone with thermal infrared camera provides high resolution georeferenced imagery of the Waikite geothermal area, New Zealand Sathiyamoorthy V, Arumugam K, Arun Pragathish M, Barath B.N, Baskar M & Balamurugan S (2018): "A Review of Mobile Oil Skimmer", International Journal of Engineering & Technology 58-60.
[2] Early detection of SARS-CoV-2 without human intervention to combat COVID-19 using drone technology
[3] Harwin S, Lucieer A. (2012). Assessing the Accuracy of Georeferenced Point Clouds Produced via Multi-View Stereopsis from Unmanned Aerial Vehicle (UAV) Imagery.Remote Sensing; 4(6):1573-1599
[4] Alex D (2015) Over 13,000 Raven SUAVs have been delivered from AeroVironment to a variety of global operators, making it the most widely used UAV of its kind. MilitaryFactory.com, 2 Feb 2015. http://www.militaryfactory.com/aircraft/detail.asp?aircraft_id=888. Accessed 26 Aug 2015
[5] Drone remote sensing for forestry research and practicesLina Tang & Guofan Shao
[6] Ambrosia V, Hutt M, Lulla K (2011a) Special issue: unmanned airborne systems (UAS) for remote sensing applications. Geocarto Int 26(2):69–70
[7] Ambrosia V, Wegener S, Zajkowski T, Sullivan D, Buechel S, Enomoto F, Lobitz B, Johan S, Brass J, Hinkley E (2011b) The Ikhana unmanned airborne system (UAS) western states fire imaging missions: from concept to reality (2006–2010). Geocarto Int 26(2):85–101
[8] Berni JAJ, Zarco-Tejada PJ, Suarez L, Fereres E (2009) Thermal and narrowband multispectral remote sensing for vegetation monitoring from an unmanned aerial vehicle. IEEE Trans Geosci Remote Sens 47(3):722–738
[9] Felderhof L, Gillieson D (2011) Near-infrared imagery from unmanned aerial systems and satellites can be used to specify fertilizer application rates in tree crops. Can J Remote Sens 37(4):376–386
[10] Harwin S, Lucieer A. (2012). Assessing the Accuracy of Georeferenced Point Clouds Produced via Multi-View Stereopsis from Unmanned Aerial Vehicle (UAV) ImageryMoCA (2019) Drone ecosystem policy roadmap. In: Global Aviation Summit, Mumbai, India. 15–16 Jan 2019
[11] DGCA (2018) Requirements for operation of civil Remotely Piloted Aircraft System (RPAS). File no. 05-13/2014-AED, office of the Director General of civil aviation. http://dgca.nic.in/cars/D3X-X1.pdf. Accessed on 17 May 2019
[12] Prajwal kumar M. Patil, Mallik arjun B. Koujalagi, Krishna Toli, "Modeling, Analysis & Fabrication of Quadcopter (Uav) With Payload Drop Mechanism," International Journal of Research in Advent Technology, Special Issue, 2019.
[13] Prem Kumar, Amirtharaja.S, Harie. S, Kishore Rohy. S, Kiruba. V, "Quad copter Video surveillance and control using computer", International Journal of Electrical and Electronics Engineers, vol. 7, Issue 01, 2015.
[14] S. H. Jeong, & S. Jung, "Novel design and position control of an omni-directional flying automobile (Omni-fly mobile), International Conference on Control Automation and Systems, 2010, pp.2480-2484.
[15] Stöcker C, Bennett R, Nex F, Gerke M, Zevenbergen J (2017) Review of the current state of UAV regulations. Remote Sens 9:459. https://doi.org/10.3390/rs9050459

©IJRASET: All Rights are Reserved



10.22214/IJRASET

45.98

IMPACT FACTOR: 7.129

IMPACT FACTOR: 7.429

INTERNATIONAL JOURNAL FOR RESEARCH

IN APPLIED SCIENCE & ENGINEERING TECHNOLOGY

Call : 08813907089 (24*7 Support on Whatsapp)