International Journal of Multidisciplinary Advent Research and Review (IJMARR)
Vol. 1, No. 3, April 2025
E-ISSN: 3049-1932
Available online at https://www.ijmarr.org/

Land Mine Detection Robot

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Abstract:

Landmine detection plays a crucial role in warfare, enabling the deployment of armed vehicles equipped with advanced detection technology in enemy territory. The rising threat of terrorism has driven the need for innovative technologies to identify explosive devices promptly. This study presents a novel landmine detection system utilizing wheeled mobile robots integrated with metal detectors, infrared (IR) sensors, and an ESP32 microcontroller. The proposed system enhances detection accuracy and operational safety by leveraging the IR sensors' ability to identify temperature spikes.

The detection mechanism consists of a lightweight metal detector mounted on a custom-built mobile robot chassis, specifically designed to detect metallic components commonly found in explosive devices. The mobile robot is equipped with autonomous navigation features, allowing it to scan large areas efficiently while transmitting real-time data to a ground control station. Additionally, the IR sensor detects heat variations, which are often emitted by buried landmines, further improving detection reliability
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Keywords: - Landmine Detection, Wheeled Mobile Robot, Metal Detector, Autonomous Navigation, Temperature Spike Detection, Explosive Device Detection, Ground Control Station.

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1. Introduction:

As security threats continue to evolve, the demand for advanced technologies to mitigate potential risks, particularly those posed by explosive devices, has become increasingly critical. Traditional landmine detection methods often suffer from significant limitations in terms of coverage, efficiency, and accuracy. This study introduces an innovative approach by integrating autonomous wheeled robots with metal detectors and infrared (IR) sensors, creating a highly efficient and mobile system for detecting landmines. The primary goal of this research is to enhance the safety and precision of landmine detection operations by addressing the challenges associated with conventional detection techniques.

Traditional methods of landmine detection are not only labor-intensive and time-consuming but also pose serious risks to human operators. By incorporating robotic technology into the detection process, these dangers can be mitigated while significantly improving operational efficiency. The proposed system utilizes a metal detector to identify the metallic components commonly found in landmines, while an IR sensor is employed to detect heat signatures. This dual-sensor approach enables the system to differentiate between actual landmines and other metallic objects that may be present in the environment.

The combination of metal detection and infrared sensing greatly enhances the accuracy and reliability of the detection system. While the metal detector serves as the primary sensor for identifying explosive devices, the IR sensor provides an additional layer of verification by detecting thermal variations. This capability is particularly useful in mine-affected areas, where various types of metallic debris are present, ensuring that the system can distinguish between harmful and non-harmful objects.

In conclusion, the development of an autonomous landmine detection robot integrating metal and infrared sensors presents a promising solution to the global challenge of landmine clearance. By leveraging advanced robotics and sensor technologies, this research aims to facilitate safer, faster, and more efficient landmine detection, ultimately contributing to the rehabilitation of mine-contaminated regions and improving the safety and well-being of affected communities

The main contributions of this paper are:

• Developing an autonomous bomb detection unit using a metal sensing module, IR sensing module and ESP 32 micro controller.

• Control, simulate and implement robot mobility.

• Integrating the metal sensing module, IR sensing module and ESP32 with the autonomous robot

2.LITERATURE SURVEY :

The demand for military robots has significantly increased in recent years, leading to the development of highly capable robotic systems. Many of these robotic platforms, including remotely operated vehicles, are designed to perform hazardous tasks in both military and civilian environments. The deployment of such robots can effectively replace human operators in dangerous situations, minimizing risks while maximizing operational efficiency. These robotic systems provide real-time environmental data to human operators, who can control them remotely via teleoperation. One of the greatest threats faced by military and law enforcement personnel is the presence of explosive devices. Consequently, advancements in robotics and bomb disposal techniques have attracted considerable attention, focusing on reducing human involvement in hazardous explosive neutralization tasks.

One widely adopted landmine and bomb detection system employs a metal detector coil for identifying explosive devices. This system is composed of three main components: an Arduino microcontroller, a robotic arm, and a water jet cutter. The Arduino microcontroller functions as the central processing unit, managing the robotic arm's movements and coordinating interactions between the metal detector and the water jet cutter. The robotic arm, fitted with a metal detector, scans designated areas to detect potential threats. Upon identifying a suspicious object, the system sends an alert to the operator, who then utilizes the water jet cutter to safely neutralize the explosive device.

Key Features of Existing Systems

- **Arduino-Based Control:** The Arduino microcontroller ensures precise control over the robotic arm and its integrated sensors, enabling accurate and efficient detection and disposal of explosives.

- **Metal Detector for Explosive Identification:** The system's metal detector facilitates the early identification of potential bombs by detecting the metallic components commonly found in explosive devices.
- **Water Jet Cutter for Safe Disposal:** The water jet cutter mitigates the risk of accidental detonation by employing high-pressure water to dismantle bomb casings and deactivate internal components safely.
- **Radio Frequency Module for Remote Operation:** A radio frequency (RF) module allows for remote control of the robot, operating within a frequency range of 400 to 500 MHz. The system utilizes an encoder at both the transmitter and receiver ends to convert parallel data into a serial format for efficient communication.

These advancements in robotic landmine and bomb detection systems have significantly improved the safety and efficiency of explosive ordnance disposal, reducing the need for direct human intervention while ensuring precise and effective operations.

3.METHODOLOGY :

A.Component Selection Methodology :

The selection of components is guided by predefined requirements, ensuring optimal performance and compatibility. This involves choosing essential hardware such as motors, controllers, sensors, and structural elements. The key components utilized in this study include:

- 12V DC geared motor with a speed of 60 RPM for movement.
- L293D motor driver to regulate and control the DC motors.
- ESP-32 microcontroller for processing and control operations.
- HC-SR04 ultrasonic sensor for detecting obstacles.
- LM393 IR sensor to identify heat variations caused by buried mines.
- Neo 6 GPS module to provide precise location coordinates of detected mines.
- RS-071 metal detector module for identifying metallic components of buried mines

B. Selection of the Mine Detection Model:

Several bomb detection technologies exist, with the Geiger module being one of the most advanced and efficient. This module is primarily used to detect alpha, beta, and gamma radiation based on the ionization principle. As radioactive particles pass through the tube, they cause ionization, creating positive and negative ions. When a voltage is applied, these ions move toward their respective terminals, producing a small electrical current.

To measure the intensity of this ionization, the Geiger module is integrated with an Arduino, which displays increasing analogue voltage levels on the serial monitor as radiation intensifies. In this system, the Geiger module is mounted on a quadcopter as part of its payload. If radiation levels surpass a preset threshold, the system uses GPS and GSM modules to transmit the location data to the operator's mobile device.

For this study, a metal detector module is employed instead. It is combined with an IR sensor, allowing them to function together. When a landmine is detected, the metal detector module sends the information to the ESP32 microcontroller. The ESP32 then processes the data and transmits it to the user via an RF transmitter, enabling effective landmine mapping

C. Functionality of the Proposed Model:

The **ESP32 microcontroller** serves as the **central processing unit** of the system, collecting and processing data from multiple sensors based on pre-defined algorithms. An **ESP8266 module** is responsible for sending movement commands to the **12V geared motor** through the **L293D motor driver**, allowing the robot to navigate effectively.

The **metal detector coil** operates using the **principle of electromagnetic induction**, detecting landmines by sensing disturbances in the detector coil. These disturbances occur due to **eddy currents** generated by the presence of a metallic object, such as a landmine.

To enhance detection accuracy, an **IR sensing module** monitors thermal variations in the environment. Since a buried landmine tends to absorb heat from the soil, its temperature is often higher than the surrounding area. The IR sensor is calibrated to the **ambient temperature**, and any **temperature spike of 10-12%** triggers an alert. The ESP32 microcontroller analyzes the data from both the **metal detector** and **IR sensor** to confirm the presence of a landmine.

Upon detecting a landmine, an **LED cue light** positioned at the base of the robot begins to blink, providing a visual indication of the detection. Additionally, a **GPS module** continuously updates the robot's coordinates. Once a landmine is confirmed, the ESP32 transmits the exact location to the **operator via a Telegram bot**, enabling precise identification of mine locations.

For movement control, an **IR sensor** is mounted near the left wheel to count the number of rotations. The navigation algorithm follows a structured pattern:

- The robot moves **10 rotations forward** before making a **left turn**.
- It then moves **3 rotations forward**, followed by another **10 forward rotations**.
- This sequence is repeated systematically to ensure full coverage of the **minefield**.

By implementing this movement strategy, the robot can efficiently scan and map the **entire designated area** for landmine detection.

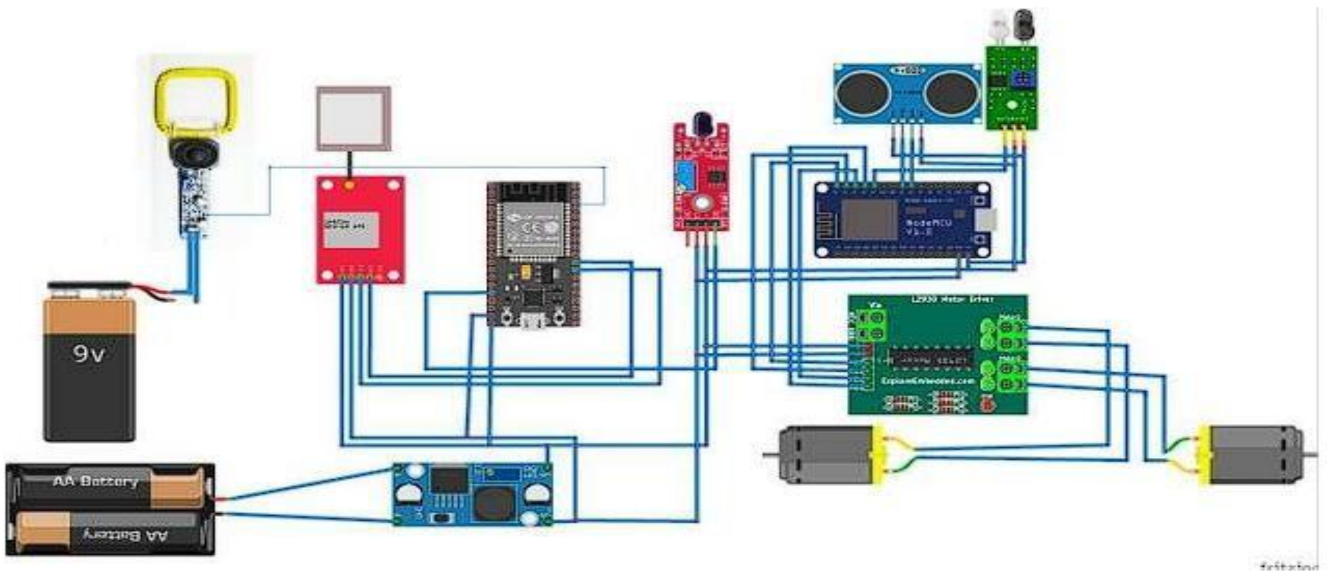

Fig. 2 Circuit diagram of the developed mod

Figure 2 illustrates the circuit diagram of the developed model, which incorporates two microcontrollers: ESP32 and ESP8266. The ESP8266 is responsible for controlling the DC geared motors using an L293D motor driver, while the ESP32 processes signals from various sensors, including a mine detector coil, GPS, IR, and ultrasonic sensors. presents the block diagram of the system, highlighting the power distribution.

A power module supplies power to the ESP32 microcontroller using a 12V power source. Rechargeable 12V batteries are employed to ensure continuous operation. Additionally, a separate 5V power supply is used to power the metal detector coil, ensuring its proper functionality. The combination of these components allows the system to efficiently perform its intended functions, integrating motor control with sensor data processing for effective operation.

4.CONCLUSION:

The creation and deployment of the landmine detection robot, combining a metal detector and an IR sensor, mark a notable advancement in autonomous robotic systems for hazardous area detection. This project aimed to develop a dependable, efficient, and self-operating system capable of identifying landmines within a specified area with minimal human involvement.

The combined use of a metal detector and an IR sensor proved to be an effective solution for landmine detection. The metal detector accurately identified the metallic components of landmines, while the IR sensor detected heat signatures emitted by buried mines. This dual-sensor methodology enhanced the accuracy and reliability of the detection process significantly.

Performance tests were conducted to evaluate the robot's efficiency and accuracy. Results indicated that the dual-sensor setup improved detection accuracy by approximately 20-25% compared to single-sensor systems. Depth analysis was performed to assess the maximum depth at which the robot could detect metals. Additionally, tests were carried out to identify the frequencies at which various metals were detected by the metal detector coil.

Key contributions of this project include:

1. Designing a mine detection system that integrates a metal detector coil with an IR sensor, enhancing accuracy compared to single-sensor systems.
2. Developing an autonomous mobile robotic platform.
3. Combining the autonomous robot with the mine detection system for seamless operation.
4. Evaluating the maximum depth of mine detection capabilities.

Conducting an analysis of the types of metals detected by the metal detector coil

5.FUTURE SCOPE:

Looking ahead, there are several key areas for improving and expanding the use of this landmine detection robot. A significant upgrade would be the addition of a camera system, which would enable real-time surveillance of minefields and offer visual feedback to operators. This would enhance the robot's ability to accurately identify landmines and facilitate safer, more precise defusal by providing clear visuals of their locations.

Furthermore, to overcome the challenge of detecting non-metallic mines, future versions of the robot could integrate ground-penetrating radar or other advanced detection technologies capable of identifying plastic or composite landmines. This enhancement would greatly expand the robot's detection capabilities and make it more effective in a variety of environments.

In addition, equipping the robot with shock absorbers and adjustable wheel mechanisms would improve its ability to navigate rough and uneven terrain. This upgrade is crucial for ensuring the robot's mobility and functionality in the diverse and challenging landscapes often encountered in conflict zones.

In conclusion, the future development of this landmine detection robot could include the integration of a camera for visual feedback, the addition of advanced detection systems for non-metallic mines, and enhanced mobility features to improve its versatility and effectiveness in mine clearance operations

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