

VISVESVARAYATECHNOLOGICALUNIVERSITY
JnanaSangama,Belagavi,Karnataka-590018

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A

PROJECT REPORT ON

"DRONE(UNMANNED AERIAL VEHICLE) using KK2.1.5 Flight controller board for surveillance"

Submitted in partial fulfillment of the requirements for the award of the Degree of

Bachelor of Engineering

in

Mechanical Engineering

Submitted By

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An ISO 9001:2015 Certified Institution

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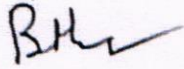


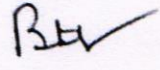
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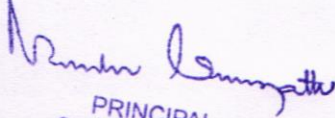
Certified that the Project Work entitled "DRONE (UNMANNED AERIAL VEHICLE) using **KK2.1.5** Flight control board for surveillance" is a bona fide work carried out by **Mr. SANTHOSH R (ISV19ME011), YATHISH H R (ISV19ME015), SRIKANTH R (ISV19ME014), KUMARASWAMY P G (ISV17ME005)** in partial fulfilment for the award of Bachelor of Engineering in Mechanical Engineering of the Visvesvaraya Technological University, Belagavi during the year 2021-2022. It is certified that all the corrections/suggestions indicated for internal assessment have been incorporated in the report deposited in the departmental library. The Project Report has been approved as it satisfies the academic requirements in respect of Project Work prescribed for the said degree.


Signature of the Guide
(Mr B H Vasudevamurthy)


Signature of the HOD
(Mr B H Vasudevamurthy)

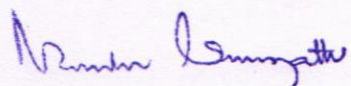
Signature of the Principal
(Dr. Narendra Vishwanath)

Sl.NO.	<u>Name of the Examiners</u>	<u>Signature with Date</u>
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ABSTRACT

Drone (Unmanned aerial vehicle) is an electronic device which is remote controlled based aircraft used to achieve vertical flight with stability using KK2.1.5 board and it can be used for live streaming and also for capturing images using camera and as technology advances increase the performance and reduce the cost of microcontroller so that general public can design their own drone. The main aim of this project is for live streaming and collecting images . This drone includes a frame,flight control board ,motors ,electronic speed controllers ,a transmitter,a receiver, lipo battery and camera interfaced with the kit.Individual components were tested and verified . Tuning and calibration of the PID controller were done to obtain stabilization on each axis.Currently ,the drone can properly stabilize itself .The aim of the project has been achieved ,resulting in stable and capturing images.



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