

Intelligent Automated Guided Vehicle (AGV) System for Optimized Material Handling

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Abstract

This project is the development of an Automated Guided Vehicle (AGV) system that has been developed to handle materials in the high-accuracy, reliability, and efficiency in industrial settings. The AGV is a combination of a blend of advanced technologies including sensor fusion, real-time path planning, and AI-based navigation to allow smooth and intelligent operation with minimal human intervention. The vehicle is able to efficiently identify, and evade obstacles by using a combination of sensors, such as RADAR sensors, computer vision systems and dynamically plan the most optimal routes in changing and uncertain environments. A hybrid control approach is adopted to increase adaptability and performance, which involves machine learning algorithms with a rule-based motion planning. This will enable the AGV to react intelligently to real time conditions and still retain stability and precision in its movements. The Internet of Things (IoT) capabilities further enhance the system by providing the possibility of remote monitoring, the ability to schedule preventative maintenance and the ability to centrally manage multiple AGVs in a networked industrial environment. The proposed system has several advantages in that it enhances speed in transportation of material, decreases reliance on human labor, minimizes human error, and lowers operational costs. It is especially useful in the manufacturing and warehouse setting where efficiency and consistency are very important. As experimental evidence shows, the developed AGV is capable of successfully carrying the payloads of up to 4 kg along the predetermined routes and maintaining the stable and reliable performance. It also displays good obstacle detection and avoidance systems as well as easy navigation during various surface conditions. The strength, adaptability, and scalability of the system has made it a prospective solution to the modern automated material handling programs.

Keywords: Automated guided vehicle, navigation, sensor integration, industrial automation, IoT, smart logistics, motion planning

INTRODUCTION

Automated Guided Vehicles are remote controlled machines made to help with moving materials around in industries, factories, warehouses, and other places. They use different types of navigation, such as optical sensors or built-in smart systems, that allow them to move accurately and efficiently

without human effort [1, 2]. With more and more industries going towards automation, AGVs are becoming an important part of the system. They help make things faster, reduce costs, and improve safety. AGVs are used in many areas, such as warehouses, electronic assembly lines, and even in risky places where it is not safe for people to work [3–6]. Large industries have started using AGVS to accelerate their production lines. As industries continue to grow and take on more difficult tasks, AGVs are becoming a reliable, efficient, and cost-effective way to handle the daily job of moving materials from one point to another.

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Received Date: January 13, 2026

Accepted Date: April 06, 2026

Published Date: June 13, 2026

Citation: Karan R. Wadalkar, Prasad V. Salunke, Pratik S. Satalkar, Sayli J. Tambe, Abhinandan Kondekar, Naveen Kumar. Intelligent Automated Guided Vehicle (AGV) System for Optimized Material Handling. Trends in Mechanical Engineering & Technology. 2026; 16(2): 1–7p.

Problem Definition

During our college days, we noticed something simple but interesting: some of the staff were constantly walking from one class to another just to move files. It's repetitive, and that's where the idea came to us: What if we had a small automated vehicle that could handle these tasks?

In many industries and even on campuses, moving materials from one place to another is still done mostly manually. Whether carrying files, tools, or raw materials, a considerable amount of human effort is involved. This not only takes up time but also causes delays and increases the chances of errors or accidents.

The problem becomes even bigger in large industries or warehouses, where depending on human efforts for such tasks can lead to [7–10]:

- Delays in deliveries.
- Risk of injuries from carrying loads
- Difficulty adapting to frequent layout changes in busy environments

GRAPHICAL DEVELOPMENT OF AGV

The AGV was designed using CAD Software. Github link contains Designs of AGV Parts, Including Dimension of parts, Assembly and 3D Design Images: <https://github.com/SayliTambe/AGV-Designs>

Laser Cutting of AGV Parts

- *Design of Components:* CAD Software was used to design the components of the AGV.
- *Selection of Material:* Acrylic Material Were Chosen for Their Properties.
- *File Conversion:* Designs were converted into DXF format for compatibility with laser cutting machines.
- *Laser Cutting Process:* Machine parameters, such as power, speed, and focus, were optimized for accurate cutting.
- *Post-Processing:* The cut parts were cleaned, and the smooth edges and holes/slots were verified for alignment. The laser-cut parts are shown in Figure 1.

In this project, acrylic material was used. The properties of Acrylic material, such as tensile strength of material used, Speed and Temperature are provided in Table 1.



Figure 1. Laser cut parts.

Integration of AGV Parts

The steps followed are:

- Assemble the chassis of the AGV and mount the components securely onto it.
- Connect 12V motors to the motor driver, ensuring the polarity for forward and reverse motions.
- The motor driver was interfaced with the Arduino UNO Microcontroller. The pins are connected to Arduino's output pins to control the motors' direction and speed using PWM signals. The pin-out is briefly provided in Table 2.
- The Pixhawk 2.4.8 was mounted centrally and configured for high-level navigation control. It interfaces with the GPS and other sensors to determine the path and orientation.
- The M8N GPS module was connected to the Pixhawk for real-time location tracking and path following.
- The ESP8266 Wi-Fi module was integrated with Arduino UNO to enable wireless communication and monitoring.
- Power is supplied using a Lead-Acid Battery and voltage regulators are used to supply 5V and 3.3V where it is needed.
- Connect the TFLuna Radar Sensor for obstacle detection and distance measurement.
- The Buzzer was used as an alert to indicate low battery warnings or obstacle detection.
- The Flysky RC is used for Human control and override during testing.
- All grounds (GND) of components are connected to a common ground to maintain a stable reference and prevent erratic behavior.

Mission Planner Software (ArduPilot)–Usage in AGV Project

Mission Planner is a more powerful ground control software that is used for configuring, planning, and controlling autonomous vehicles, such as AGVs and drones, with the help of GPS tracking. In this project, it was used to define points, configure parameters, and simulate the path of AGV on a real-world map. The mission planner software is shown in Figure 2.

Table 1. Properties of acrylic material.

Properties	Value
Tensile strength of acrylic material	Around 60–80 MPa
Flexural strength of acrylic material	Range of 100–120 MPa
Elongation at break	Around 2–5%
Density	Approx. 1.18 g/cm ³
Glass transition temperature (T _g)	Around 105°C
Laser cutting speed	Varies based on thickness
Melting temperature	Between 130–140°C
Coefficient of thermal expansion	Approx. 70–80x 10 ⁻⁶ /°C

Table 2. Connection of components with arduino/pixhawk.

Component	Connected to	Pin number/port
L298N motor driver	Arduino UNO	IN1 → D7, IN2 → D8, IN3 → D9, IN4 → D10
GPS M8N module	Pixhawk 2.4.8	GPS Port
ESP8266 Wi-Fi module	Arduino UNO	TX → D2, RX → D3
TFLuna radar sensor	Arduino UNO / Pixhawk	UART (TX/RX)
Buzzer	Arduino UNO	D12
12V motor	L298N Motor Driver	Motor output
Lead acid battery	Power supply	12V Input
FlySky RC receiver	Pixhawk 2.4.8	RC Input port

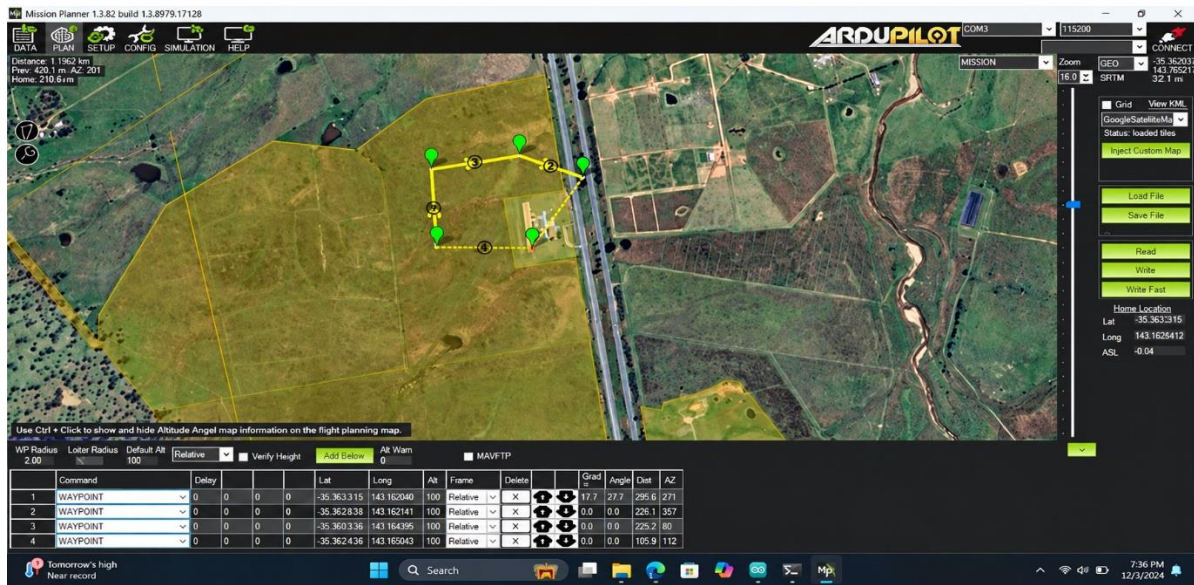


Figure 2. Mission planner software.

Key Features Used

- Live telemetry of the vehicle with simulation
- Real-world path planning.

Circuit Diagram for AGV using Pixhawk and Arduino

Circuit Diagram Overview

- The AGV is powered by a 12V Lead Acid Battery and a LiPo battery, regulated via a power module.
- Pixhawk 2.4.8 acted as the main controller, managing all the motor controllers and GPS data.
- Arduino Uno is used for sensor integration or logic support.
- L298N Motor Driver controls DC motors based on signals from Pixhawk.
- GPS module with compass provides real-time navigation data.
- All components were properly connected to ensure smooth power flow and communication. The software circuit integration is shown in Figure 3.

KINEMATICS OF AGV

The motion of an Automated Guided Vehicle (AGV) can be analyzed using differential drive kinematics. The Movement of AGV depends on the velocity of the wheels on both sides.

Let:

v = Linear velocity of the AGV

w = Angular velocity of the AGV

r = Wheel Radius

L = Distance between left and right wheels

w_L = Left wheel Speed of AGV

w_R = Right wheel Speed of AGV

The equations for the AGV's motion are:

$$v = (r / 2) * (w_R + w_L)$$

$$w = (r / L) * (w_R - w_L)$$

These equations allow us to compute the Linear and Angular motion of the AGV. By varying the speed of all wheels, AGVs can move softly or turn in a specific direction.

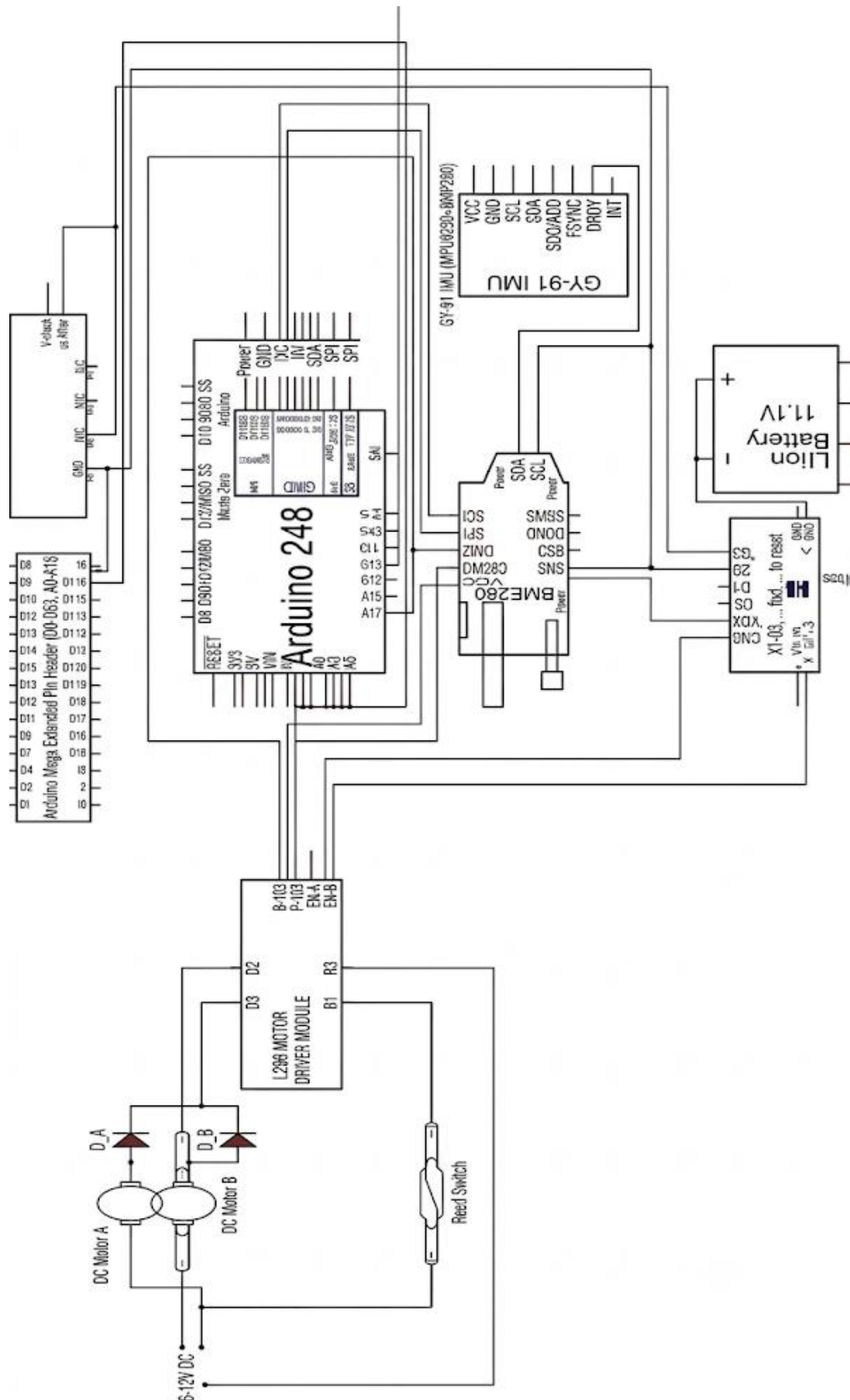


Figure 3. Software circuit integration.

RESULTS AND OBSERVATIONS

The Created AGV successfully demonstrated movement and obstacle detection using a radar sensor. Whenever an obstacle is detected, it is used to stop or turn using a radar sensor when the destination is reached. It receives the signal from the receiver and transmits it to the AGV for path detection. The structure of the AGV is built using acrylic sheets, which are lightweight, so that the AGV can smoothly move in the forward and backward directions.

The power supply through the battery, motor drivers, Pixhawk microcontroller, and all the components was stable throughout the testing. The system operated efficiently.

Performance Metrics

Performance metrics are shown in Table 3.

Comparative Analysis

Comparative Analysis is shown in Table 4.

Advantages of AGVs

- Reduces manual labor
- Increases efficiency and safety

Disadvantages of AGVs

- High initial cost
- Difficult for maintenance

Future Scope

- Uses a RADAR Sensor for obstacle avoidance
- It improves battery life and self-charging Devices

CONCLUSION

In this project, an Automated Guided Vehicle (AGV) designed for material handling was built and tested successfully, demonstrating the power of automation in modern industrial settings. The main goal of this project was to create an AGV that could move materials along set paths with minimal human help using a combination of smart electronics and strong mechanical components.

Pixhawk microcontroller and RADAR sensor enabled smooth and adaptive operation, even in changing or dynamic environments.

Table 3. Performance metrics.

Parameter	Value
Average speed	0.6 m/s
Load capacity	Upto 4kg
Obstacle detection range	Approx. 1.5 meters (Radar)
Accuracy in navigation	93% route-following accuracy
Charging time	4 hours (Lead Acid Battery)
Battery backup	~3 hours

Table 4. Comparative analysis.

Feature	Existing AGV 1	Existing AGV 2	Proposed AGV
Navigation type	Line following	RFID based	GPS + Radar
Obstacle avoidance	Basic (IR only)	None	Radar sensor
IoT integration	Not available	Not available	Yes
Load capacity	2–3 Kg	3 Kg	4 Kg
Battery backup	1.5–2 hours	2 hours	~3 hours

The AGV features a robust frame structure, allowing it to move efficiently over various and uneven surface types.

- It can transport payloads up to 4 kg consistently along a predefined route.
- The system maintains stability and performance without compromise, regardless of terrain.
- Owing to its efficiency, compact design, and autonomous operation, AGV are well-suited for integration into industrial settings, warehousing systems, and automated production lines.
- This presents a cost-effective and scalable solution for smart material handling and logistics.

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