

BALANCING BOAT

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We, Muhammad Aizat Bin Mazli and Muhammad Asri Bin Jumali hereby declare that the thesis is based on our original work except for quotations and citations which have been duly acknowledged. I also declare that it has not been previously or concurrently submitted for any other degree at UiTM or other institutions.

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## **ABSTRACT**

This paper presents a Peripheral Interface Controller that has been implanted to control the stability of water transport like boat. In this project, it has 2 parts which are input and output. This device uses sensor to detect the presence of angle that approach specified value as an input while the servomotor that control the stability of the boat as the output. The Peripheral Interface Controller (PIC) is the main part of this device that placed between input and output. The idea to design this device are comes from the primary challenges for a fisherman when they need to handle the boat. From that, it caused about many young generations nowadays does not choose fisherman as their job. The concept of this device is if the sensor detects a certain degrees on the left or right of the boat, the output part which is servomotor will automatically rotate to certain position to stabilize the boat.

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