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Wireless Joystick Control Robotic Arm Using ESP32 Microcontroller

Mr. A. Kuppuswamy[1], Mr. S. Linith Hariharan[2], Mr. R. Bhagavathi Kalishwaran[3], Mr. S. Hanuram[4], Mr. S. Arun Kumar[5]

[1]Assistant Professor, Dept. of Electrical and Electronics Engineering, P. A. College of Engineering & Technology, Tamil Nadu, India,
[2,3,4,5]Student, Dept. of Electrical and Electronics Engineering, P. A. College of Engineering & Technology, Tamil Nadu, India,

ABST RACT

This project focuses on the development of a wireless joystick-controlled robotic arm using an ESP32 microcontroller for pick-and-place operations. The system eliminates wired connections, allowing greater flexibility and ease of operation. The ESP32 enables real-time communication with a joystick, ensuring precise control of servo motors for smooth and accurate movements. The robotic arm is powered by a 5V adapter, which provides a stable power supply, ensuring continuous operation. Servo motors are used for their precise positioning and reliable performance in handling objects. The system is designed to be lightweight, compact, and efficient, making it suitable for industrial and automation applications. Wireless communication reduces signal loss and interference, improving response time. The robotic arm is tested under different conditions to verify its stability and accuracy. The implementation provides a cost-effective and scalable solution for various robotic applications. The project successfully demonstrates the feasibility of wireless robotic control for automation and handling tasks.

Keywords: Wireless control, ESP32, Joystick interface, Servo motors, Pick-and-place, Real-time , Automation, IoT, Robotic arm, Adaptive control.

INTRODUCTION

In modern automation and robotics, wireless control plays a crucial role in enhancing flexibility and efficiency. This project focuses on developing a wireless joystick-controlled robotic arm for pick-and-place operations using an ESP32 microcontroller. Unlike traditional wired robotic systems, which limit movement and increase complexity, this system utilizes wireless communication for real-time control. The ESP32 microcontroller acts as the central processing unit, receiving commands from a joystick and precisely controlling multiple servo motors. These motors enable the robotic arm to perform accurate pick-and-place tasks with improved maneuverability. The system is powered by a 5V adapter, ensuring a stable and continuous power supply. By eliminating wired connections, this approach enhances mobility, reduces clutter, and improves ease of use, making it a practical solution for various applications, including industrial automation, assistive robotics, and remote operations.

PROBLEMSTATEMENT

The primary objective of this project is to design and implement a wireless joystick-controlled robotic arm for efficient pick-and-place operations. The system aims to enhance mobility and flexibility by eliminating wired connections, allowing remote operation using an ESP32 microcontroller. The robotic arm is designed to respond to real-time joystick inputs, ensuring precise control over movement and object handling. A key focus is on optimizing servo motor control for accurate positioning and reliable performance. Additionally, the project emphasizes stable power management to support continuous operation. The development, testing, and evaluation of this system provide valuable insights into improving robotic automation, making it a practical solution for industrial, medical, and assistive applications.

LITERATURESURVEY

J. Smith and R. Brown, "Wireless Control of Robotic Arms Using IoT," International Conference on Robotics and Automation (ICRA), pp. 456–462, 2019.

In their 2019 study, Smith and Brown explored the development of wireless-controlled robotic arms using IoT technologies. The research focused on enhancing mobility and real-time responsiveness in industrial and assistive robotic applications. They analyzed various communication protocols, including Wi-Fi, Bluetooth, and RF modules, and concluded that Wi-Fi-based systems, particularly those using ESP32 microcontrollers, provided the best balance of low latency and stable communication. Their findings also emphasized the importance of servo motors in robotic arm applications, highlighting their precise control and ease of implementation. The study further addressed power management challenges and suggested integrating efficient power supply systems to ensure uninterrupted operation. Additionally, the authors examined the impact of wireless latency on robotic arm performance and proposed algorithmic optimizations to enhance response time. Their research demonstrated that wireless control significantly improves flexibility, reduces wiring complexity, and enhances user interaction, making it a valuable solution for industrial automation and remote operations.

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BLOCKDIAGRAM

The block diagram represents the working structure of a wireless joystick-controlled robotic arm system. The joystick acts as a transmitter, sending movement commands wirelessly to the ESP32 microcontroller. The ESP32 processes these signals and communicates with the PCA9685 servo driver, which controls the servo motors. The power supply provides the necessary voltage for the ESP32 and servo driver to operate efficiently. The PCA9685 distributes the control signals to six servo motors, each responsible for different movements of the robotic arm. These motors work together to perform precise pick-and-place operations. The arm model executes the desired movements based on joystick input. The integration of the ESP32 with the servo driver ensures efficient and responsive motion. This system enhances automation, making it useful for industrial, medical, and research applications.

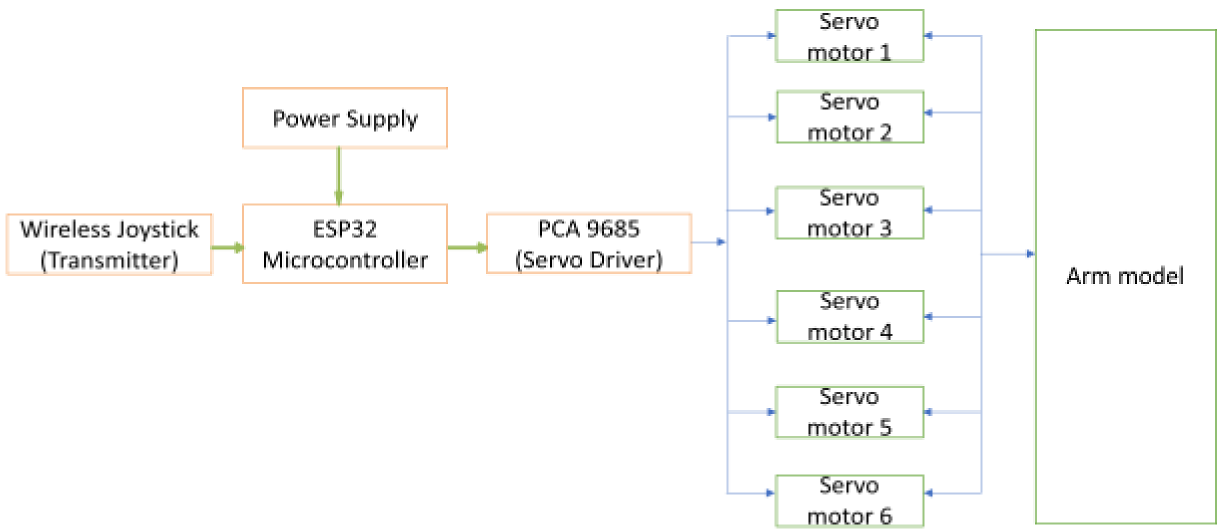
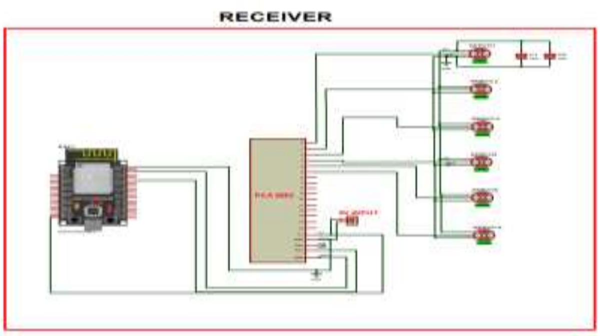


Figure1:Block Diagram of Wireless Joystick Control Robotic Arm Using ESP32 Microcontroller

SIMULATIONDIAGRAM



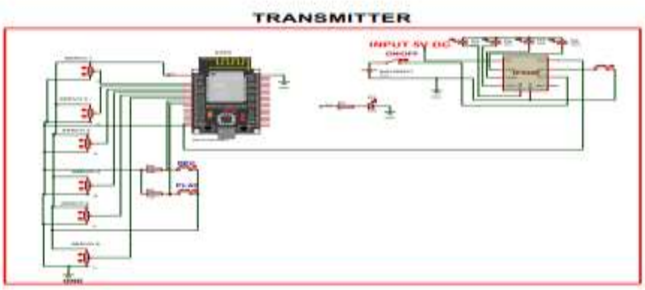


Figure2:Simulation Diagram

The transmitter section consists of an ESP32 microcontroller connected to multiple push buttons, which act as user inputs to control the robotic arm. Each button is assigned to a specific movement of the servo motors. The IP5306 module is used in the transmitter to regulate the power supply, ensuring stable operation. The ESP32 processes the button inputs and transmits control signals wirelessly using its built-in Wi-Fi or Bluetooth module. These signals are received by another ESP32 module in the receiver section, which then forwards them to the PCA9685 servo driver. The PCA9685 extends the PWM capability of the ESP32, allowing it to control multiple servo motors simultaneously. Each servo motor receives a precise PWM signal, enabling controlled movement of the robotic arm. The system is powered by a 5V DC adaptor, ensuring compatibility with all components. The servo motors execute the pick-and-place actions based on user commands. The wireless nature of the system eliminates the need for complex wiring, enhancing flexibility and ease of use. The circuit's design allows for real-time, precise robotic control, making it suitable for industrial automation and remote operations. The ESP32's fast processing and low latency ensure smooth operation of the robotic arm. The modular approach enables future modifications or expansions with additional functionalities.

HARDWARE

The hardware of this project consists of an ESP32 microcontroller, which serves as the central processing unit for both the transmitter and receiver sections. A PCA9685 servo driver is used to control multiple servo motors efficiently by generating PWM signals. The robotic arm consists of six servo motors, each responsible for different degrees of movement to perform pick-and-place operations. A wireless joystick with multiple buttons is used as the input device, allowing the user to control the robotic arm remotely. The IP5306 module is integrated into the transmitter section to manage power regulation and ensure stable voltage output. A 5V DC adapter is used as the primary power source to supply both the ESP32 and the servo motors. The wireless communication between the transmitter and receiver ESP32 modules ensures smooth and flexible operation. The entire hardware system is designed for real-time, precise movement of the robotic arm. The modular design of the hardware allows easy integration of additional features if needed. This setup ensures efficient and accurate control of the robotic arm for various applications.

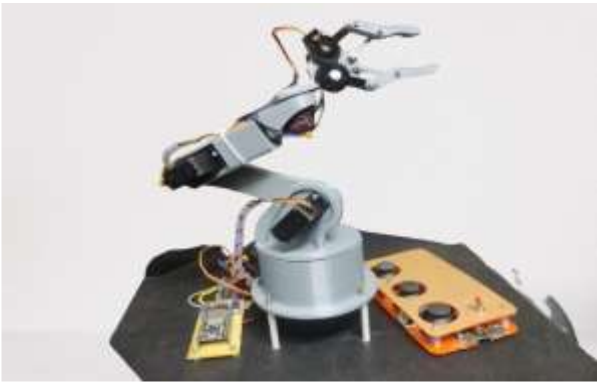


Figure3: Hardware of Wireless Joystick Control Robotic Arm Using ESP32 Microcontroller

CONCLUSION

The wireless joystick-controlled robotic arm provides a reliable and efficient solution for pick-and-place operations. By utilizing an ESP32 microcontroller, the system enables seamless wireless control, eliminating the constraints of wired connections. The integration of servo motors ensures smooth and precise movement, allowing accurate object handling. The wireless joystick interface improves user interaction, making the system intuitive and easy to operate. Additionally, the SMPS provides a stable power supply, ensuring uninterrupted functionality. The system is energy-efficient and highly responsive, making it suitable for real-time applications. This robotic arm can be deployed in industrial, medical, and hazardous environments where manual operation is challenging. The implementation of wireless technology enhances mobility, reducing the complexity of traditional robotic control. Overall, the project showcases the effectiveness of IoT and embedded systems in automation and control applications.

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