

Robot Arm control procedure

1. Turn on the ESP32 Board
2. Connect to wifi– SSID: Eric_Arm Password:12345678
3. Open browser(chrome/edge) and visit 192.168.4.1
4. Turn on the gampad, connect to the pc, press any botton, then a visualization of the gamepad will show up on the bottom of the webpage, indicate successful connect.
5. Can start to control the robot arm using gamepad

Move to Default pos
(Init Pos)

STANDARD GAMEPAD

Wrist up/down

Gripper Spin

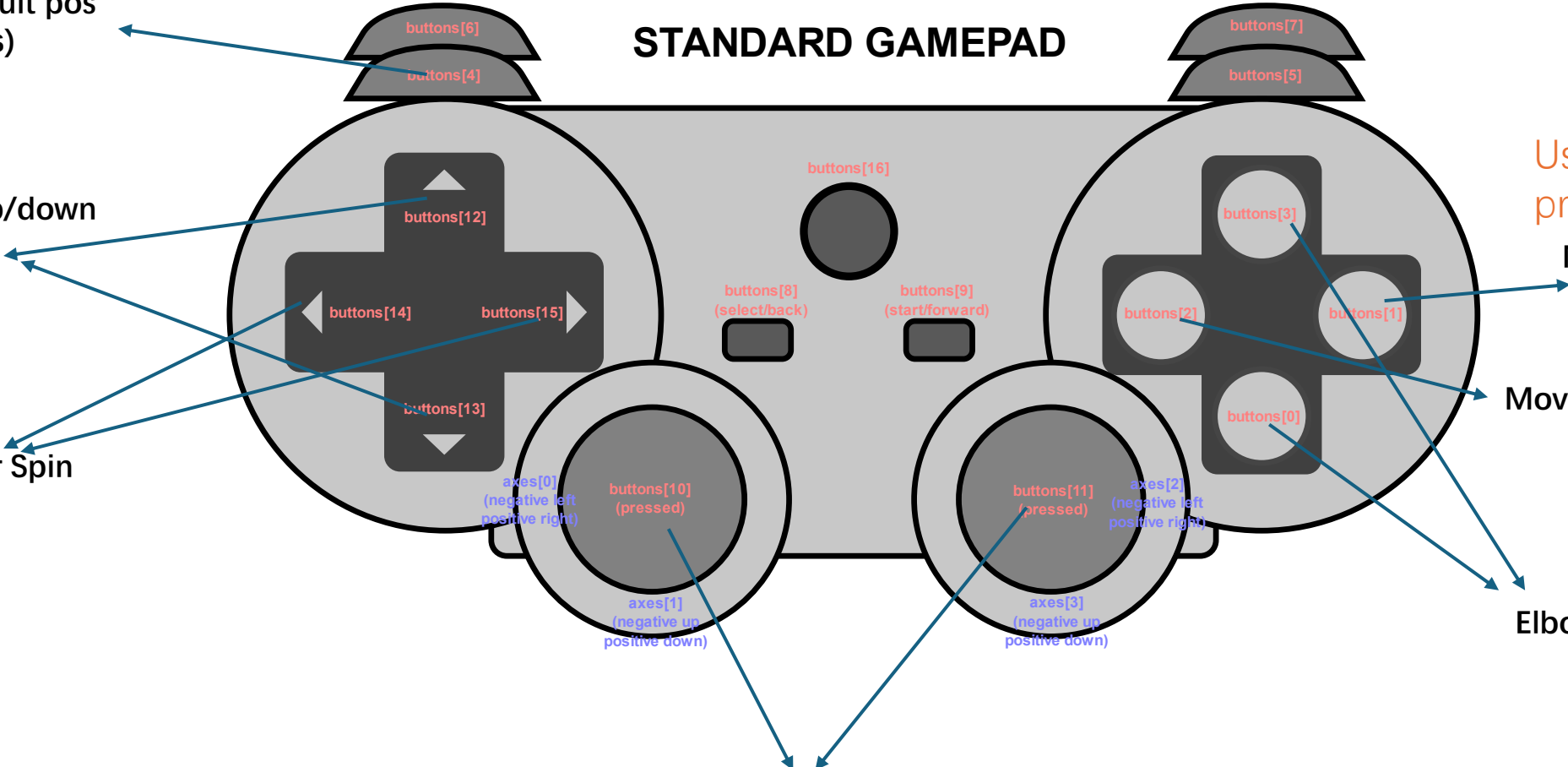
Use webpage to
preset the positions

Move to Preset Pos 1

Move to Preset Pos 2

Elbow up/down

Gripper open/close



Web page:

ERIC ARM

STATUS

ELBOW
Single servo infomation.

WRIST
Single servo infomation.

HAND
Single servo infomation.

WRIST_2
Single servo infomation.

WHOLE BODY CONTROL

SEARCHING SERVOS.

Start Searching

SET/MOVE TO DESIRED POSITION

Set pos

POS TO SET: NONE

TOTAL CURRENT: -- A

TORQUE ON/OFF

On

Off

SELECT DISPLAY PART(NONE)

Next

Former

SET CURRENT POS AS MID

Set Mid

SAVE DESIRED SPEED & ACC & MODE

Save Param

SAVE CURRENT POS AS INITIALIZE POS

Save Cur Pos

SAVE GRAB POS

Save Grab Pos

SAVE LAND POS

Save Land Pos