**Arduino Code**

#define BLYNK\_PRINT Serial

#include <ESP8266WiFi.h>

#include <BlynkSimpleEsp8266.h>

#include <Ethernet.h>

#include<Servo.h>

char auth[] = "Pc-S\_gnIyzUznsuDxOzJRWkkfZ5Dh4EP";

char ssid[] = "wifi\_name";

char pass[] = "password";

Servo gripper;

Servo joint1;

Servo joint2;

Servo base;

const int m1a = D1;

const int m1b = D2;

const int m2a = D3;

const int m2b = D4;

int minRange = 312;

int maxRange = 712;

BLYNK\_WRITE(V0)

{

int x = param[0].asInt();

int y = param[1].asInt();

moveControl(x,y);

}

BLYNK\_WRITE(V4) //function to read from app's virtual pin

{

gripper.write(param.asInt()); //servo\_object.write(position)

}

BLYNK\_WRITE(V5) //function to read from app's virtual pin

{

joint1.write(param.asInt()); //servo\_object.write(position)

}

BLYNK\_WRITE(V6) //function to read from app's virtual pin

{

joint2.write(param.asInt()); //servo\_object.write(position)

}

BLYNK\_WRITE(V7) //function to read from app's virtual pin

{

base.write(param.asInt()); //servo\_object.write(position)

}

void forward()

{

digitalWrite(m1a, HIGH);

digitalWrite(m1b, LOW);

digitalWrite(m2a, HIGH);

digitalWrite(m2b, LOW);

Serial.print("for");

}

void backward()

{

digitalWrite(m1a, LOW);

digitalWrite(m1b, HIGH);

digitalWrite(m2a, LOW);

digitalWrite(m2b, HIGH);

Serial.print("bac");

}

void left()

{

digitalWrite(m1a, HIGH);

digitalWrite(m1b, LOW);

digitalWrite(m2a, LOW);

digitalWrite(m2b, HIGH);

Serial.print("lef");

}

void right()

{

digitalWrite(m1a, LOW);

digitalWrite(m1b, HIGH);

digitalWrite(m2a, HIGH);

digitalWrite(m2b, LOW);

Serial.print("rig");

}

void stopp()

{

digitalWrite(m1a, LOW);

digitalWrite(m1b, LOW);

digitalWrite(m2a, LOW);

digitalWrite(m2b, LOW);

Serial.print("stop");

}

void moveControl(int x, int y)

{

//Move Forward

if(y > maxRange && x > minRange && x< maxRange)

{

backward();

}

//Move Forward Right

else if(x > maxRange && y > maxRange)

{

left();

}

//Move Forward Left

else if(x < minRange && y > maxRange)

{

right();

}

//No Move

else if(y == 512 && x == 512)

{

stopp();

}

//Move Backward

else if(y < minRange && x > minRange && x < maxRange)

{

forward();

}

}

void setup()

{

Serial.begin(115200);

Blynk.begin(auth, ssid, pass);

joint2.attach(D5);

gripper.attach(D6);

base.attach(D7);

joint1.attach(D0);

pinMode(m1a, OUTPUT);

pinMode(m1b, OUTPUT);

pinMode(m2a, OUTPUT);

pinMode(m2b, OUTPUT);

}

void loop()

{

Blynk.run();

}