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**WEB CONTROLLED IOT BASED ROBOTIC ARM USING ESP32**

**A MINI PROJECT REPORT**

***Submitted by***

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***In partial fulfilment for the award of the degreeof***

# BACHELOR OF ENGINEERING

***in***

**ELECTRONICS AND COMMUNICATION ENGINEERING**

**AAA COLLEGE OF ENGINEERING AND TECHNOLOGY, SIVAKASI**

# ANNA UNIVERSITY: CHENNAI 600 025

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**Abstract**

This project introduces a novel application of Internet of Things (IoT) technology in the field of robotics, presenting the development and implementation of a web-controlled robotic arm utilizing the ESP32 microcontroller. The system allows users to remotely manipulate the robotic arm's movements and functions through a web interface, providing real-time control and feedback over the internet. By leveraging the capabilities of the ESP32, including its Wi-Fi connectivity and processing power, the robotic arm demonstrates versatility and responsiveness in executing various tasks. The project's design, construction, and software architecture are detailed, showcasing its potential applications in industries such as manufacturing, automation, and education. Through experimentation and evaluation, the effectiveness and performance of the web-controlled IoT-based robotic arm are assessed, highlighting its practicality and potential for future development in robotics and IoT integration.

**Introduction**

The integration of Internet of Things (IoT) technology with robotics has opened up new avenues for remote control and automation in various industries. In this project, we present a cutting-edge application that combines the power of IoT and robotics: the development of a web-controlled robotic arm utilizing the ESP32 microcontroller.

Robotic arms have long been integral to industries such as manufacturing, automation, and healthcare due to their precision and versatility. However, traditional control methods often require physical proximity or complex wiring setups, limiting their flexibility and accessibility. By harnessing the capabilities of the ESP32 microcontroller, equipped with Wi-Fi connectivity and powerful processing capabilities, we aim to overcome these limitations and enable remote control of the robotic arm through a simple web interface.

The project's primary objective is to design and implement a robust system that allows users to manipulate the movements and functions of the robotic arm in real-time over the internet. This not only enhances the flexibility and convenience of robotic arm operation but also opens up possibilities for remote monitoring and automation in various applications.

In this introduction, we provide an overview of the project's goals, methodology, and potential applications. We also highlight the significance of leveraging IoT technology, particularly the ESP32 microcontroller, in enabling seamless communication and control between the web interface and the robotic arm. Through this project, we aim to demonstrate the practicality and effectiveness of web-controlled IoT-based robotics and pave the way for further advancements in this exciting field.

**System Architecture:**

The system architecture consists of three main components:

**ESP32 Microcontroller:** Acts as the central processing unit and handles communication between the web interface and the robotic arm.

**Servo Motors:** Responsible for the movement of the robotic arm's joints.

**Web Interface:** Provides users with a graphical interface to control the robotic arm remotely via a web browser.

**Bread Board**: A breadboard, solderless breadboard, or protoboard is a construction base used to build semi-permanent prototypes of electronic circuits.

**Features:**

The web-controlled IoT-based robotic arm offers several features:

**Remote Control:** Users can control the robotic arm from anywhere with an internet connection.

**Real-time Feedback:** The web interface provides real-time feedback on the position and status of the robotic arm.

**Customizable Interface:** Users can customize the web interface according to their preferences.

**Scalability:** The system can be expanded to include additional features such as camera integration or automation.

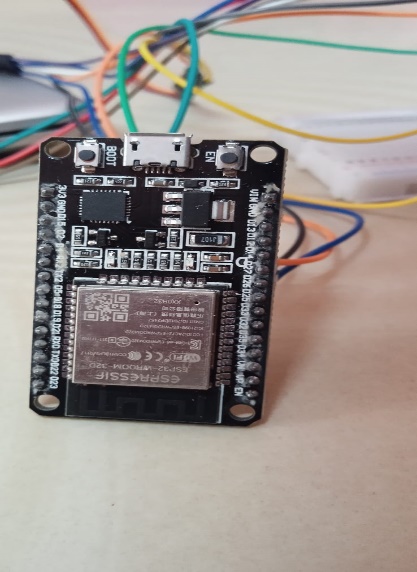
**Automation Capabilities:** With advanced programming and sensor integration, the robotic arm can perform automated tasks and sequences based on predefined parameters or user-defined commands, enabling autonomous operation in specific scenarios.

**Security Measures:** Robust security measures, such as encryption protocols, authentication mechanisms, and access control, safeguard the system against unauthorized access, ensuring data privacy and integrity.

**Fault Detection and Recovery:** The system includes mechanisms for fault detection and recovery, enabling it to identify anomalies, such as communication errors or sensor failures, and take corrective actions to mitigate disruptions and maintain operational continuity.

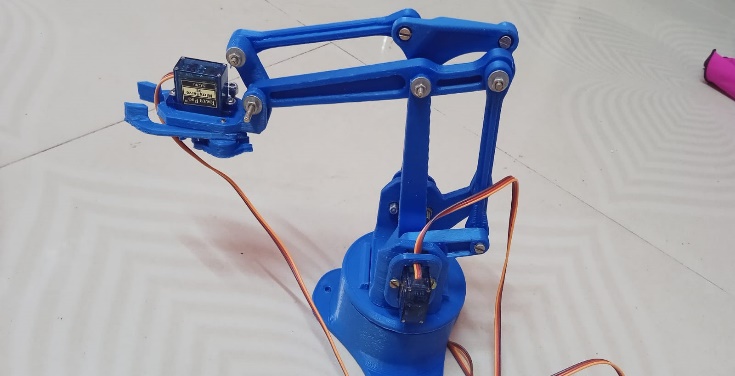
**ESP32 Microcontroller and Wi-Fi Connectivity**

The ESP32 microcontroller serves as the heart of the system, providing robust control capabilities with its built-in Wi-Fi connectivity. With its powerful processing capabilities, it facilitates seamless integration with the web interface, enabling remote control and monitoring of the robotic arm. The Wi-Fi connectivity allows for real-time data exchange, ensuring efficient communication between the user interface and the robotic arm. This enables users to manipulate the robotic arm's movements and functions remotely, expanding its versatility and usability in various applications.

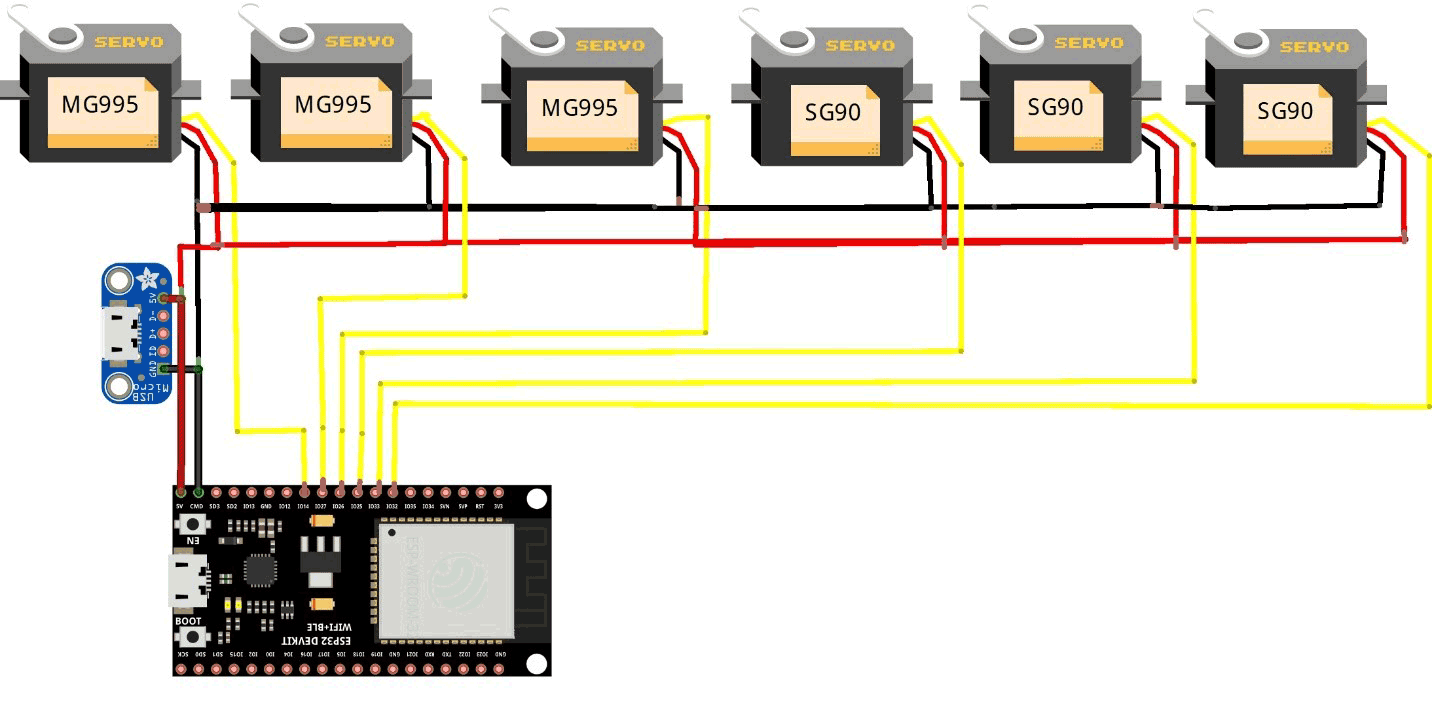


**Robotic Arm Design**

The robotic arm for the "Web-Controlled IoT-Based Robotic Arm Using ESP32" project is designed to be versatile, precise, and adaptable to various tasks. It consists of mechanical components such as joints, links, and actuators, allowing it to mimic the movements of a human arm. The design includes multiple degrees of freedom to enable complex movements and manipulation tasks. Actuators, such as servo motors or stepper motors, are used to control the motion of each joint, providing precise positioning and control. Optional sensors, such as proximity sensors or cameras, can be integrated into the robotic arm for feedback and monitoring purposes, enhancing its functionality and usability.

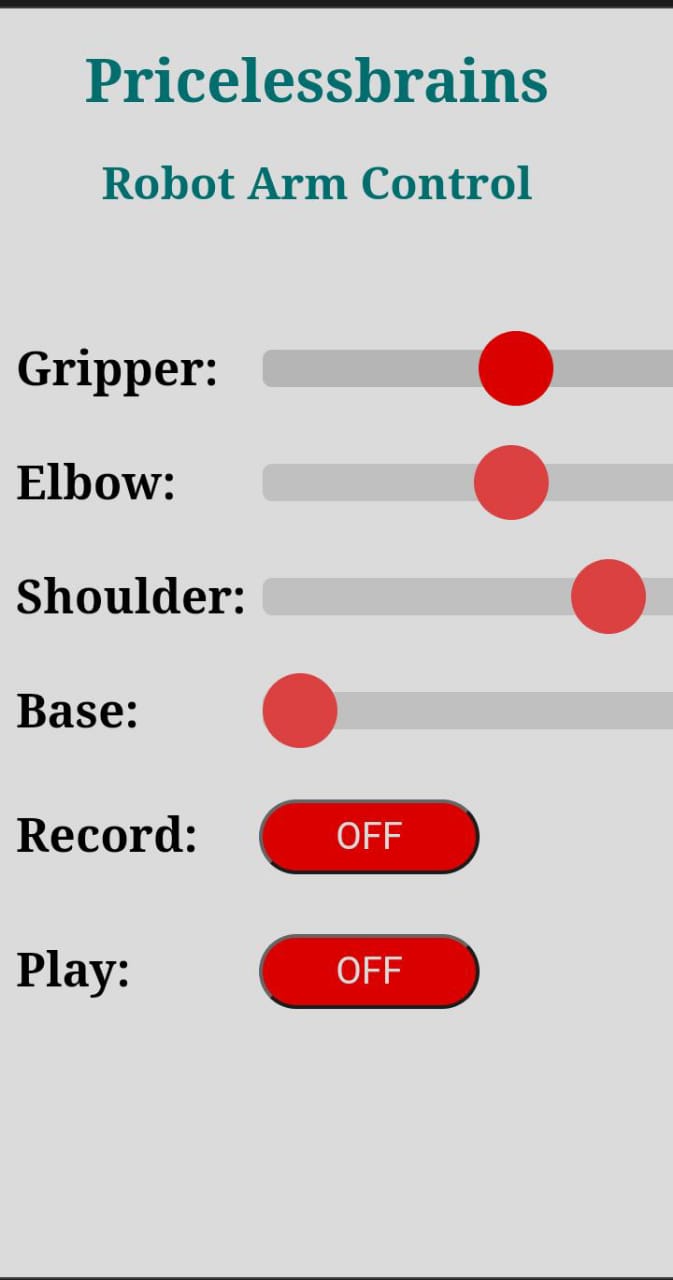


**Circuit Diagram:**

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**Website Designing:**

In designing your website, it's essential to consider both form and function. Visually, your site should reflect the modern, cutting-edge nature of your project. Clean lines, minimalist design, and high-quality imagery of the robotic arm in action can captivate visitors and highlight its features.



**Real Time Monitoring:**

Real-time monitoring in the web-controlled IoT-based robotic arm using ESP32 involves continuous observation of the arm's movements, sensor readings, and operational status. Through the ESP32 microcontroller, users receive instantaneous updates on the arm's position, allowing precise control and visualization. Sensor data, such as proximity, force, and temperature readings, is streamed in real-time to the web interface, enabling users to monitor and analyze environmental conditions and arm performance without delay. This real-time monitoring capability enhances the system's responsiveness, facilitating efficient remote operation and decision-making.

**IOT Implementation:**

Implementing IoT in the context of a web-controlled robotic arm using ESP32 involves several key steps. Initially, the hardware setup must be established, incorporating components such as the ESP32 microcontroller, servo motors for the robotic arm, and any requisite sensors or actuators, with a focus on ensuring proper wiring and connections. Subsequently, software development entails creating firmware for the ESP32 to manage Wi-Fi connectivity and communication with the web interface. This involves leveraging compatible libraries and frameworks such as Arduino or ESP-IDF. Concurrently, a web server must be implemented on the ESP32 to serve the web interface and handle HTTP requests from the client browser, utilizing frameworks like ESPAsyncWebServer or HTTPAsyncClient for efficient communication. Sensor integration is integral, requiring the incorporation of sensor libraries into the firmware to retrieve data from sensors connected to the ESP32, along with the implementation of logic to process this data.

**Methodology:**

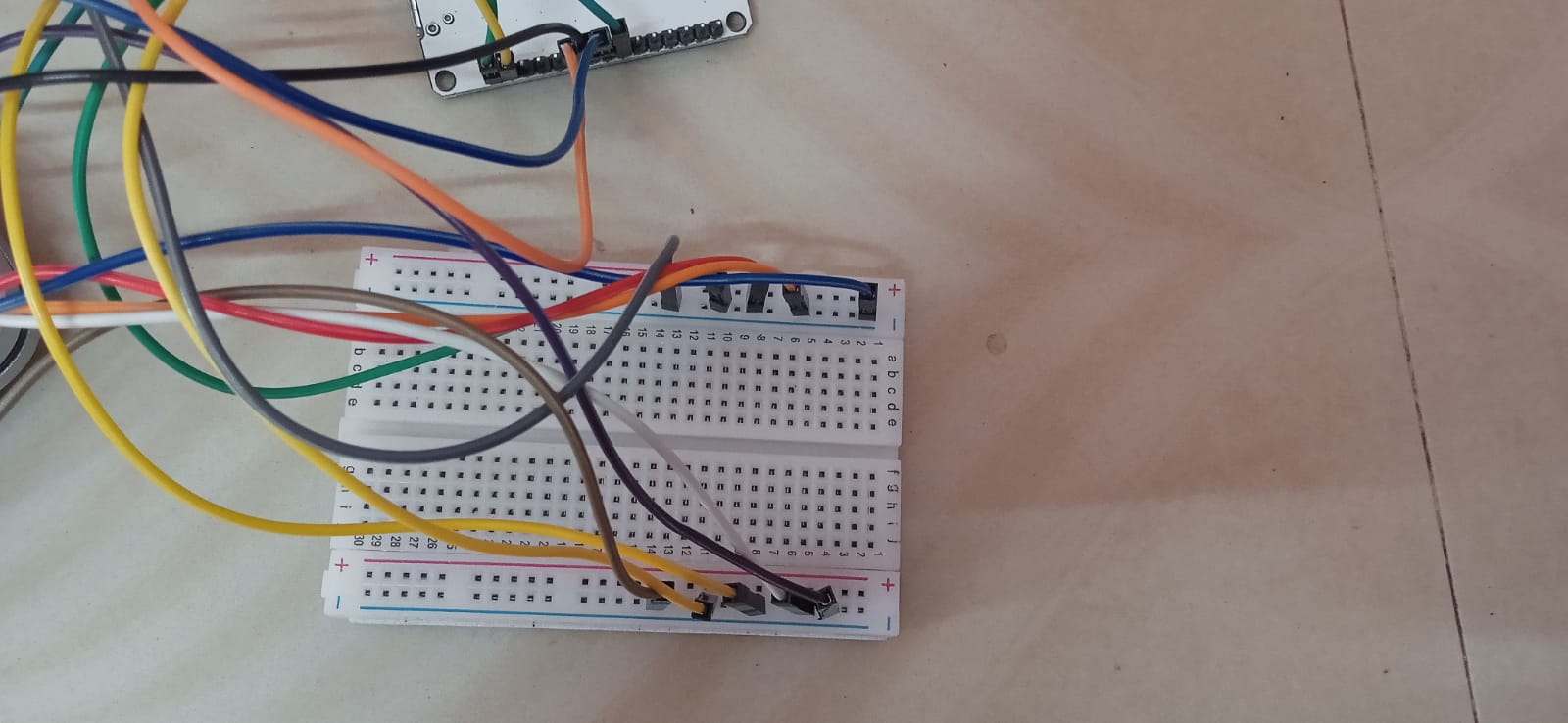
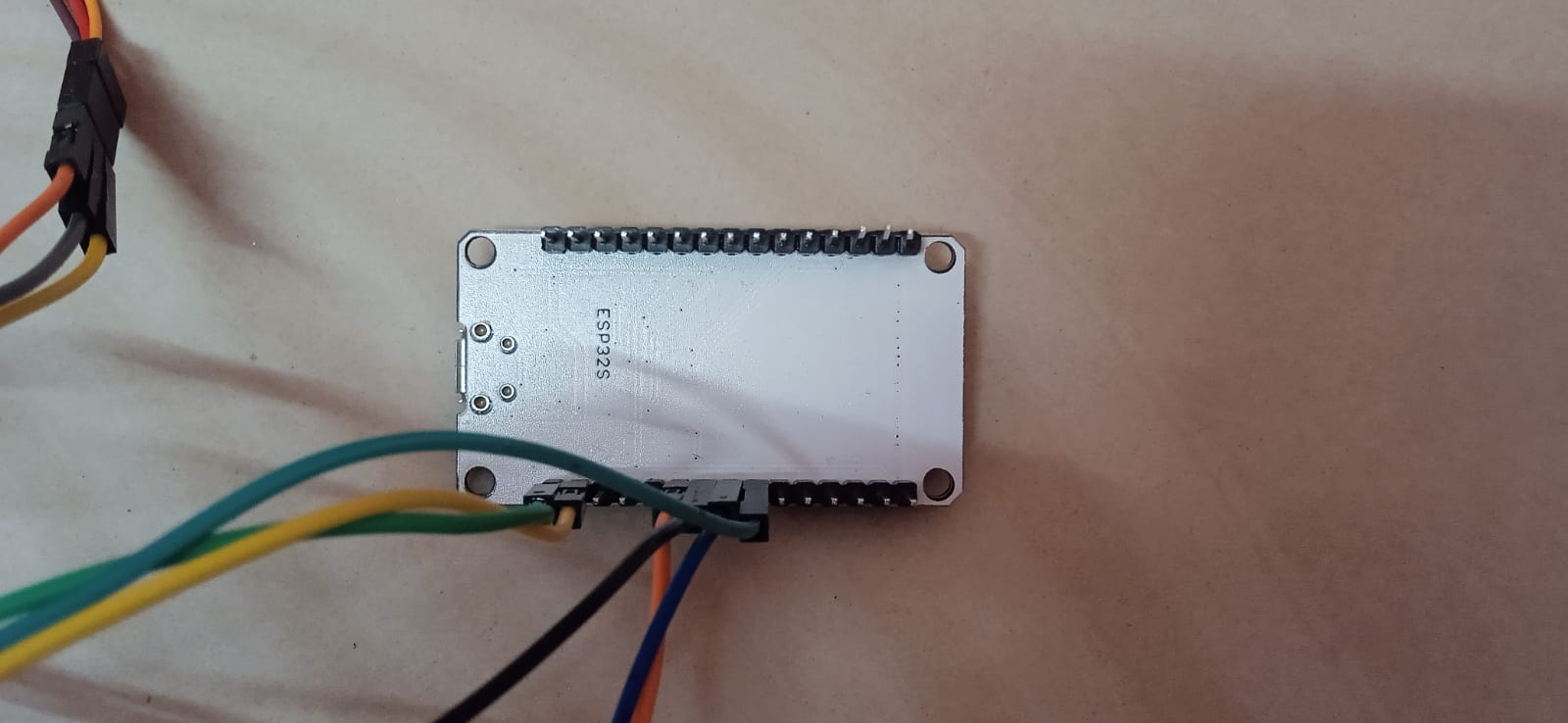
**Hardware Setup:** Configure the ESP32 microcontroller with motor drivers and sensors required for the robotic arm's operation.

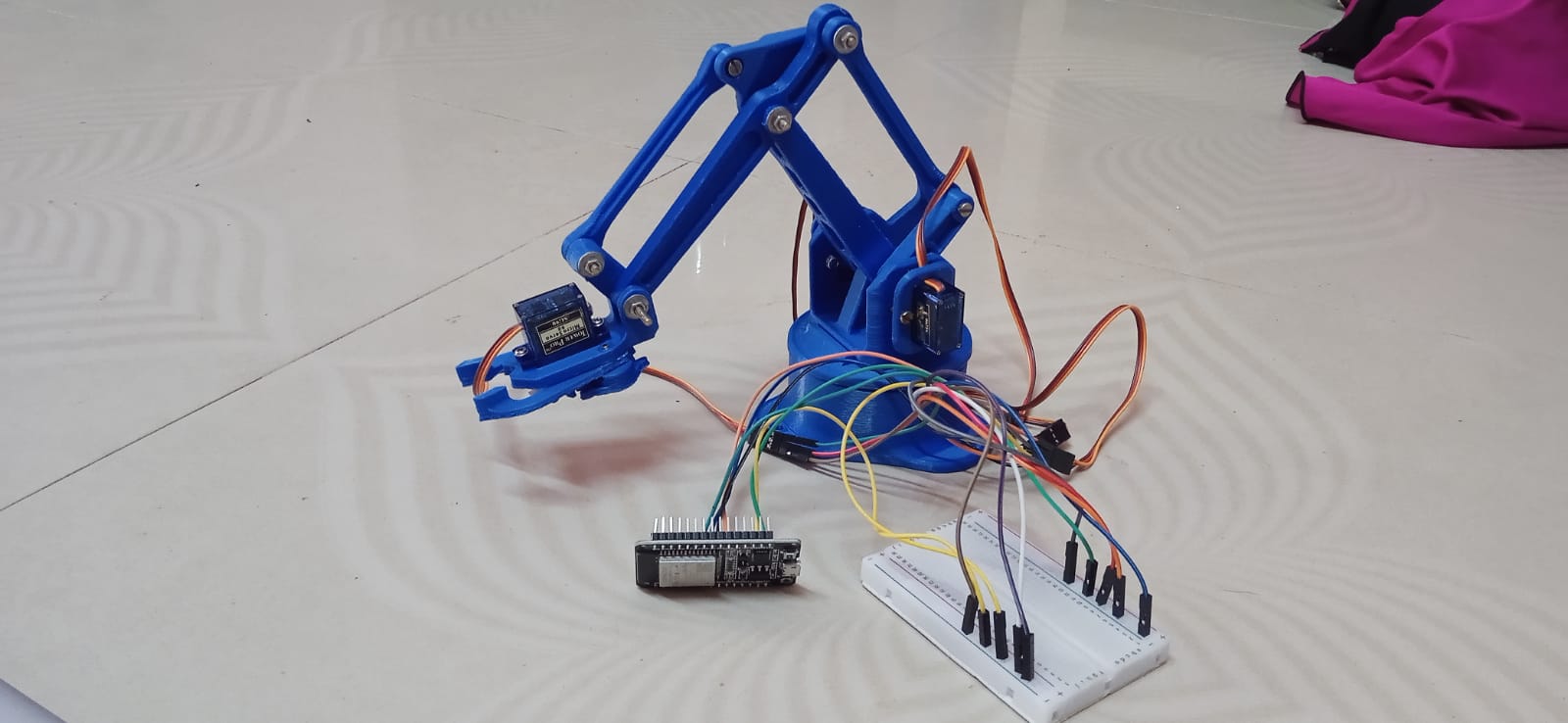
**Software Development:** Develop firmware for the ESP32 microcontroller to control motor movements and communicate with the web interface.

**Web Interface Design:** Create a user-friendly web interface using HTML, CSS, and JavaScript to allow users to control the robotic arm remotely.

**Integration and Testing:** Integrate the hardware and software components, perform rigorous testing to ensure functionality, reliability, and security.

**Documentation and Reporting:** Document the design, implementation, and testing processes, including user manuals and technical specifications.





**Code:**

#include <Arduino.h>

#include <WiFi.h>

#include <AsyncTCP.h>

#include <ESPAsyncWebServer.h>

#include <ESP32Servo.h>

#include <iostream>

#include <sstream>

struct ServoPins

{

Servo servo;

int servoPin;

String servoName;

int initialPosition;

};

std::vector<ServoPins> servoPins =

{

{ Servo(), 27 , "Base", 90},

{ Servo(), 26 , "Shoulder", 90},

{ Servo(), 25 , "Elbow", 90},

{ Servo(), 33 , "Gripper", 90},

};

struct RecordedStep

{

int servoIndex;

int value;

int delayInStep;

};

std::vector<RecordedStep> recordedSteps;

bool recordSteps = false;

bool playRecordedSteps = false;

unsigned long previousTimeInMilli = millis();

const char\* ssid = "RobotArm";

const char\* password = "12345678";

AsyncWebServer server(80);

AsyncWebSocket wsRobotArmInput("/RobotArmInput");

const char\* htmlHomePage PROGMEM = R"HTMLHOMEPAGE(

<!DOCTYPE html>

<html>

<head>

<meta name="viewport" content="width=device-width, initial-scale=1, maximum-scale=1, user-scalable=no">

<style>

input[type=button]

{

background-color:red;color:white;border-radius:30px;width:100%;height:40px;font-size:20px;text-align:center;

}

.noselect {

-webkit-touch-callout: none; /\* iOS Safari \*/

-webkit-user-select: none; /\* Safari \*/

-khtml-user-select: none; /\* Konqueror HTML \*/

-moz-user-select: none; /\* Firefox \*/

-ms-user-select: none; /\* Internet Explorer/Edge \*/

user-select: none; /\* Non-prefixed version, currently

supported by Chrome and Opera \*/

}

.slidecontainer {

width: 100%;

}

.slider {

-webkit-appearance: none;

width: 100%;

height: 20px;

border-radius: 5px;

background: #d3d3d3;

outline: none;

opacity: 0.7;

-webkit-transition: .2s;

transition: opacity .2s;

}

.slider:hover {

opacity: 1;

}

.slider::-webkit-slider-thumb {

-webkit-appearance: none;

appearance: none;

width: 40px;

height: 40px;

border-radius: 50%;

background: red;

cursor: pointer;

}

.slider::-moz-range-thumb {

width: 40px;

height: 40px;

border-radius: 50%;

background: red;

cursor: pointer;

}

</style>

</head>

<body class="noselect" align="center" style="background-color:white">

<h1 style="color: teal;text-align:center;">Hash Include Electronics</h1>

<h2 style="color: teal;text-align:center;">Robot Arm Control</h2>

<table id="mainTable" style="width:400px;margin:auto;table-layout:fixed" CELLSPACING=10>

<tr/><tr/>

<tr/><tr/>

<tr>

<td style="text-align:left;font-size:25px"><b>Gripper:</b></td>

<td colspan=2>

<div class="slidecontainer">

<input type="range" min="0" max="180" value="90" class="slider" id="Gripper" oninput='sendButtonInput("Gripper",value)'>

</div>

</td>

</tr>

<tr/><tr/>

<tr>

<td style="text-align:left;font-size:25px"><b>Elbow:</b></td>

<td colspan=2>

<div class="slidecontainer">

<input type="range" min="0" max="180" value="90" class="slider" id="Elbow" oninput='sendButtonInput("Elbow",value)'>

</div>

</td>

</tr>

<tr/><tr/>

<tr>

<td style="text-align:left;font-size:25px"><b>Shoulder:</b></td>

<td colspan=2>

<div class="slidecontainer">

<input type="range" min="0" max="180" value="90" class="slider" id="Shoulder" oninput='sendButtonInput("Shoulder",value)'>

</div>

</td>

</tr>

<tr/><tr/>

<tr>

<td style="text-align:left;font-size:25px"><b>Base:</b></td>

<td colspan=2>

<div class="slidecontainer">

<input type="range" min="0" max="180" value="90" class="slider" id="Base" oninput='sendButtonInput("Base",value)'>

</div>

</td>

</tr>

<tr/><tr/>

<tr>

<td style="text-align:left;font-size:25px"><b>Record:</b></td>

<td><input type="button" id="Record" value="OFF" ontouchend='onclickButton(this)'></td>

<td></td>

</tr>

<tr/><tr/>

<tr>

<td style="text-align:left;font-size:25px"><b>Play:</b></td>

<td><input type="button" id="Play" value="OFF" ontouchend='onclickButton(this)'></td>

<td></td>

</tr>

</table>

<script>

var webSocketRobotArmInputUrl = "ws:\/\/" + window.location.hostname + "/RobotArmInput";

var websocketRobotArmInput;

function initRobotArmInputWebSocket()

{

websocketRobotArmInput = new WebSocket(webSocketRobotArmInputUrl);

websocketRobotArmInput.onopen = function(event){};

websocketRobotArmInput.onclose = function(event){setTimeout(initRobotArmInputWebSocket, 2000);};

websocketRobotArmInput.onmessage = function(event)

{

var keyValue = event.data.split(",");

var button = document.getElementById(keyValue[0]);

button.value = keyValue[1];

if (button.id == "Record" || button.id == "Play")

{

button.style.backgroundColor = (button.value == "ON" ? "green" : "red");

enableDisableButtonsSliders(button);

}

};

}

function sendButtonInput(key, value)

{

var data = key + "," + value;

websocketRobotArmInput.send(data);

}

function onclickButton(button)

{

button.value = (button.value == "ON") ? "OFF" : "ON" ;

button.style.backgroundColor = (button.value == "ON" ? "green" : "red");

var value = (button.value == "ON") ? 1 : 0 ;

sendButtonInput(button.id, value);

enableDisableButtonsSliders(button);

}

function enableDisableButtonsSliders(button)

{

if(button.id == "Play")

{

var disabled = "auto";

if (button.value == "ON")

{

disabled = "none";

}

document.getElementById("Gripper").style.pointerEvents = disabled;

document.getElementById("Elbow").style.pointerEvents = disabled;

document.getElementById("Shoulder").style.pointerEvents = disabled;

document.getElementById("Base").style.pointerEvents = disabled;

document.getElementById("Record").style.pointerEvents = disabled;

}

if(button.id == "Record")

{

var disabled = "auto";

if (button.value == "ON")

{

disabled = "none";

}

document.getElementById("Play").style.pointerEvents = disabled;

}

}

window.onload = initRobotArmInputWebSocket;

document.getElementById("mainTable").addEventListener("touchend", function(event){

event.preventDefault()

});

</script>

</body>

</html>

)HTMLHOMEPAGE";

void handleRoot(AsyncWebServerRequest \*request)

{

request->send\_P(200, "text/html", htmlHomePage);

}

void handleNotFound(AsyncWebServerRequest \*request)

{

request->send(404, "text/plain", "File Not Found");

}

void onRobotArmInputWebSocketEvent(AsyncWebSocket \*server,

AsyncWebSocketClient \*client,

AwsEventType type,

void \*arg,

uint8\_t \*data,

size\_t len)

{

switch (type)

{

case WS\_EVT\_CONNECT:

Serial.printf("WebSocket client #%u connected from %s\n", client->id(), client->remoteIP().toString().c\_str());

sendCurrentRobotArmState();

break;

case WS\_EVT\_DISCONNECT:

Serial.printf("WebSocket client #%u disconnected\n", client->id());

break;

case WS\_EVT\_DATA:

AwsFrameInfo \*info;

info = (AwsFrameInfo\*)arg;

if (info->final && info->index == 0 && info->len == len && info->opcode == WS\_TEXT)

{

std::string myData = "";

myData.assign((char \*)data, len);

std::istringstream ss(myData);

std::string key, value;

std::getline(ss, key, ',');

std::getline(ss, value, ',');

Serial.printf("Key [%s] Value[%s]\n", key.c\_str(), value.c\_str());

int valueInt = atoi(value.c\_str());

if (key == "Record")

{

recordSteps = valueInt;

if (recordSteps)

{

recordedSteps.clear();

previousTimeInMilli = millis();

}

}

else if (key == "Play")

{

playRecordedSteps = valueInt;

}

else if (key == "Base")

{

writeServoValues(0, valueInt);

}

else if (key == "Shoulder")

{

writeServoValues(1, valueInt);

}

else if (key == "Elbow")

{

writeServoValues(2, valueInt);

}

else if (key == "Gripper")

{

writeServoValues(3, valueInt);

}

}

break;

case WS\_EVT\_PONG:

case WS\_EVT\_ERROR:

break;

default:

break;

}

}

void sendCurrentRobotArmState()

{

for (int i = 0; i < servoPins.size(); i++)

{

wsRobotArmInput.textAll(servoPins[i].servoName + "," + servoPins[i].servo.read());

}

wsRobotArmInput.textAll(String("Record,") + (recordSteps ? "ON" : "OFF"));

wsRobotArmInput.textAll(String("Play,") + (playRecordedSteps ? "ON" : "OFF"));

}

void writeServoValues(int servoIndex, int value)

{

if (recordSteps)

{

RecordedStep recordedStep;

if (recordedSteps.size() == 0) // We will first record initial position of all servos.

{

for (int i = 0; i < servoPins.size(); i++)

{

recordedStep.servoIndex = i;

recordedStep.value = servoPins[i].servo.read();

recordedStep.delayInStep = 0;

recordedSteps.push\_back(recordedStep);

}

}

unsigned long currentTime = millis();

recordedStep.servoIndex = servoIndex;

recordedStep.value = value;

recordedStep.delayInStep = currentTime - previousTimeInMilli;

recordedSteps.push\_back(recordedStep);

previousTimeInMilli = currentTime;

}

servoPins[servoIndex].servo.write(value);

}

void playRecordedRobotArmSteps()

{

if (recordedSteps.size() == 0)

{

return;

}

//This is to move servo to initial position slowly. First 4 steps are initial position

for (int i = 0; i < 4 && playRecordedSteps; i++)

{

RecordedStep &recordedStep = recordedSteps[i];

int currentServoPosition = servoPins[recordedStep.servoIndex].servo.read();

while (currentServoPosition != recordedStep.value && playRecordedSteps)

{

currentServoPosition = (currentServoPosition > recordedStep.value ? currentServoPosition - 1 : currentServoPosition + 1);

servoPins[recordedStep.servoIndex].servo.write(currentServoPosition);

wsRobotArmInput.textAll(servoPins[recordedStep.servoIndex].servoName + "," + currentServoPosition);

delay(50);

}

}

delay(2000); // Delay before starting the actual steps.

for (int i = 4; i < recordedSteps.size() && playRecordedSteps ; i++)

{

RecordedStep &recordedStep = recordedSteps[i];

delay(recordedStep.delayInStep);

servoPins[recordedStep.servoIndex].servo.write(recordedStep.value);

wsRobotArmInput.textAll(servoPins[recordedStep.servoIndex].servoName + "," + recordedStep.value);

}

}

void setUpPinModes()

{

for (int i = 0; i < servoPins.size(); i++)

{

servoPins[i].servo.attach(servoPins[i].servoPin);

servoPins[i].servo.write(servoPins[i].initialPosition);

}

}

void setup(void)

{

setUpPinModes();

Serial.begin(115200);

WiFi.softAP(ssid, password);

IPAddress IP = WiFi.softAPIP();

Serial.print("AP IP address: ");

Serial.println(IP);

server.on("/", HTTP\_GET, handleRoot);

server.onNotFound(handleNotFound);

wsRobotArmInput.onEvent(onRobotArmInputWebSocketEvent);

server.addHandler(&wsRobotArmInput);

server.begin();

Serial.println("HTTP server started");

}

void loop()

{

wsRobotArmInput.cleanupClients();

if (playRecordedSteps)

{

playRecordedRobotArmSteps();

}

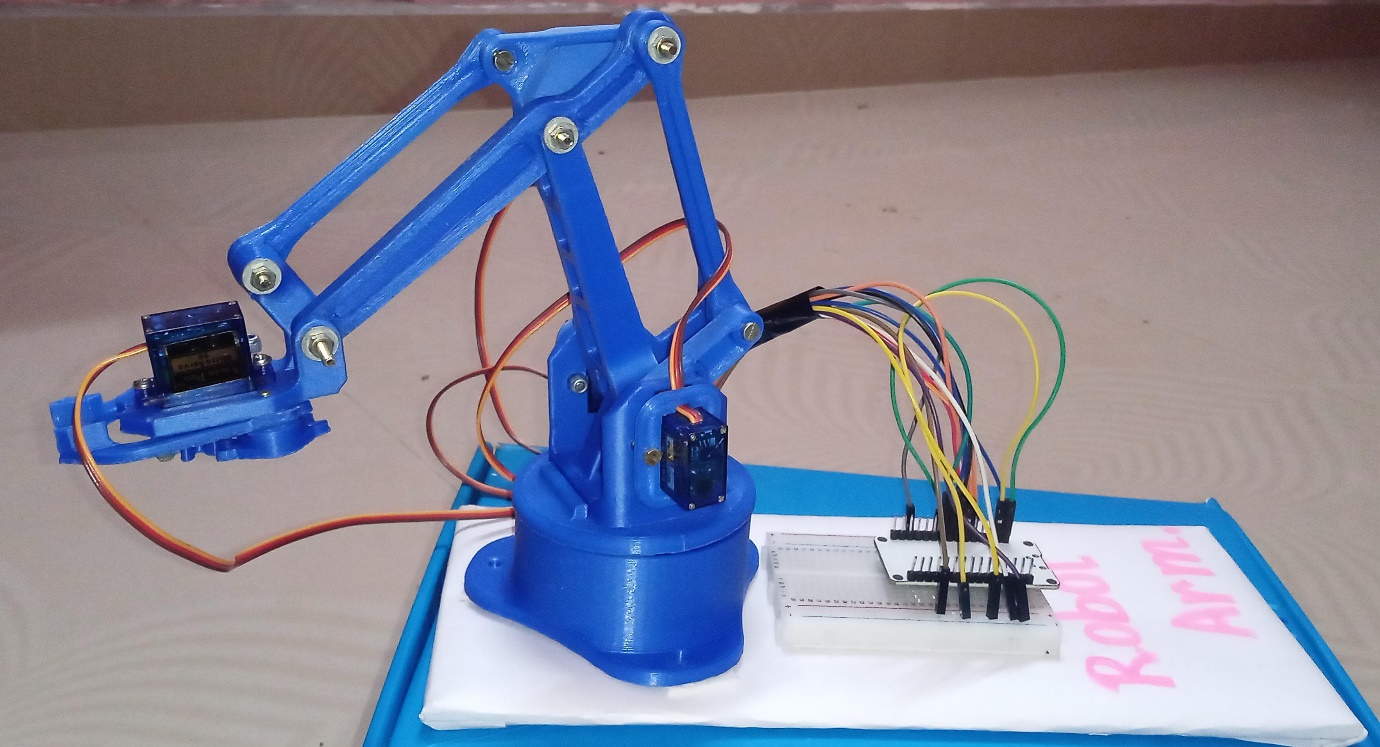
}

**Background:**

The ESP32 microcontroller, renowned for its robust Wi-Fi and Bluetooth connectivity, serves as the cornerstone of this project. By harnessing its capabilities, a web-based interface is crafted to remotely command and supervise a robotic arm over the internet. The robotic arm's articulation is orchestrated by servo motors, with directives transmitted wirelessly from a web browser to the ESP32 board.

In the domain of robotics, the integration of Internet of Things (IoT) technologies has ushered in a new era of connectivity, control, and automation. The background of implementing IoT in a web-controlled robotic arm using ESP32 revolves around harnessing the power of the ESP32 microcontroller, renowned for its versatility and connectivity capabilities. With robust Wi-Fi and Bluetooth functionalities, the ESP32 serves as the backbone of the project, facilitating seamless communication between the web interface and the robotic arm.

This integration empowers users with the ability to remotely control and monitor the robotic arm's movements and performance through a web-based interface accessible from any internet-enabled device. The incorporation of IoT principles allows for real-time monitoring, sensor integration, and scalability, laying the foundation for intelligent and adaptive robotic systems. By leveraging the ESP32's capabilities and integrating IoT technologies, the project aims to enhance the functionality, versatility, and accessibility of the robotic arm, opening up new possibilities for automation, remote operation, and intelligent control in various applications and industries.



**Application of the project "Web-Controlled IoT-Based Robotic Arm Using ESP32":**

**1. Warehousing and Logistics:** In warehouse environments, the robotic arm can streamline order fulfillment processes by picking and packing items for shipment.

**2. Healthcare:** The robotic arm can be used in healthcare settings for tasks such as medication dispensing, patient assistance, and medical instrument handling.

**3. Education and Research:** The project can be used as an educational tool for teaching robotics and IoT concepts.

**4. Home Automation:** Users can remotely control the robotic arm to perform tasks such as adjusting thermostats, turning lights on/off, or even feeding pets.

**5. Agriculture:** In agricultural settings, the robotic arm can be used for tasks such as planting, harvesting, and crop monitoring.

**Challenges of Web-Controlled IoT-Based Robotic Arm Using ESP32:**

**1. Latency and Connectivity:** Ensuring low latency and stable connectivity between web interface and ESP32 for real-time control.

**2. Security**: Implementing robust authentication and encryption to prevent unauthorized access and ensure data integrity.

**3. Compatibility:** Ensuring interoperability between hardware and software components from different vendors.

**4. Power Management:** Optimizing power consumption for prolonged operation, especially in battery-powered scenarios.

**5. User Interface Design**: Balancing simplicity and functionality in the web interface across various devices.

**Future Directions for "Web-Controlled IoT-Based Robotic Arm Using ESP32":**

**1. Enhanced Control:** Implement advanced control algorithms for autonomous behavior.

**2.** **AR Integration:** Explore augmented reality for immersive interaction.

**3. Cloud Solutions:** Integrate cloud for scalability and data analytics.

**4. Sensor Fusion:** Incorporate diverse sensors for comprehensive feedback.

**5. Industry-Specific Applications:** Tailor for healthcare, agriculture.

**Conclusion:**

In summary, the development of our web-based IoT robotic arm utilizing ESP32 represents a significant step forward in robotics and IoT integration. Through a user-friendly web interface, we've enabled remote control and monitoring, showcasing the potential for automation and smart manufacturing. With its modular design and open-source nature, the project lays a foundation for further innovation in sensor integration, autonomous decision-making, and user interaction. This project paves the way for a more connected and efficient future in both industrial and domestic environments.

The integration of real-time monitoring features not only enhances the functionality of the robotic arm but also improves user experience by providing instantaneous feedback and insights. It enables seamless interaction between operators and the robotic arm, fostering efficient collaboration and control. Moreover, the scalability and flexibility of the system allow for future enhancements and integrations, ensuring its relevance and adaptability in dynamic environments.

In essence, real-time monitoring in the web-controlled IoT-based robotic arm using ESP32 empowers users with unprecedented visibility and control over robotic operations. It signifies a step forward in the evolution of robotics technology, driving innovation and opening up new possibilities for automation, efficiency, and safety across various industries and applications. As advancements in IoT and robotics continue to unfold, real-time monitoring will play an increasingly pivotal role in shaping the future of intelligent robotic systems.

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