DESIGN AND IMPLEMENTATION OF A 5-DOF ROBOTIC ARM WITH ARUCO-BASED OBJECT DETECTION FOR ASSISTIVE MOBILE ROBOTS

A PROJECT REPORT

Submitted by

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to

the APJ Abdul Kalam Technological University in partial fulfillment of the requirements for the award of the Degree

of

Master of Technology

in

Robotics and Automation

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July 2025

DECLARATION

I undersigned hereby declare that the project report ”Design and Implementation of a 5-DOF Robotic Arm with ArUco-Based Object Detection for Assistive Mobile Robots” submitted for partial fulfillment of the requirements for the award of degree of Master of Technology of the APJ Abdul Kalam Technological University, Kerala, is a bonafide work done by me under supervision of Dr Reshmi S Bhooshan. This submission represents my ideas in my own words and where ideas or words of others have been included, I have adequately and accurately cited and referenced the original sources. I also declare that I have adhered to ethics of academic honesty and integrity and have not misrepresented or fabricated any data or idea or fact or source in my submission. I understand that any violation of the above will be a cause for disciplinary action by the institute and/or the University and can also evoke penal action from the sources which have thus not been properly cited or from whom proper permission has not been obtained. This report has not been previously formed the basis for the award of any degree, diploma or similar title of any other University.

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CERTIFICATE

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ACKNOWLEDGMENT

I wish to record my indebtedness and thankfulness to all who helped me prepare this Mini Project Report titled ”Design and Implementation of a 5-DOF Robotic Arm with ArUco-Based Object Detection for Assistive Mobile Robots” and present it satisfactorily. I am especially thankful for my guide and supervisor Dr Reshmi S Bhooshan Assistant Professor in the Department of Electronics & Communication Engineering for giving me valuable suggestions and critical inputs in the preparation of this report. I am also thankful to Dr. Haris P.A., Head of Department of Electronics & Communication Engineering for encouragement. Friends in my class have always been helpful and I am grateful to them for patiently listening to my presentations on my work related to the Project.

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ABSTRACT

Grocery shopping can be a challenging task for elderly individuals, especially when it comes to navigating crowded spaces, locating items, or carrying heavy bags. This project introduces a smart, mobile robotic assistant designed to make shopping easier, safer, and more independent for such users. At its core is a 5-degree-of-freedom robotic arm with a gripper, mounted on a mobile platform that can move through supermarket aisles on its own.The robot understands voice commands using Natural Language Processing (NLP), detects products using a camera and ArUco markers, and uses inverse kinematics to control its arm and pick up the right item. A Raspberry Pi handles navigation, using ultrasonic sensors to avoid obstacles, while an Arduino manages the precise movements of the robotic arm. Everything works together seamlessly—when the user asks for an item, the robot finds it, picks it up, and brings it back.

This system was designed with real-life use in mind, offering an intuitive and friendly experience for users who may not be tech-savvy. By combining smart technologies in a simple and practical way, it aims to bring real independence to elderly or physically challenged individuals. In the future, the robot could be improved further with advanced navigation (like SLAM), mobile app control, and smarter, more adaptive grasping. Ultimately, this project takes a meaningful step toward making assistive robots a helpful part of everyday life.

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Chapter 1
INTRODUCTION

1.1 BACKGROUND

Everyday tasks like grocery shopping can be surprisingly difficult for elderly individuals. Crowded aisles, hard-to-reach shelves, and the strain of carrying items can make a routine trip to the store both tiring and stressful. To address this challenge, we have developed a smart, voice-controlled mobile robot equipped with a robotic arm that can help users retrieve items with ease. This system is designed to act as a personal assistant—one that can listen to spoken commands, navigate supermarket-style environments, recognize specific objects using a camera, and use its arm to gently pick up and deliver items. With a focus on simplicity, affordability, and user comfort, this robotic solution combines speech recognition, computer vision, and intelligent motion in a way that is both helpful and approachable.

The robot is built around two major components: a mobile base that handles movement and a robotic arm that performs pick-and-place operations. These two parts work together in real time, supported by onboard electronics and a mix of open-source software tools.

1.2 MOTIVATION

With the aging global population, many individuals experience difficulty with everyday physical tasks, including shopping. Current robotic solutions are often expensive, complex, or lack user-friendly interfaces. This project is driven by the desire to create a low-cost, easy-to-use robotic system that enhances independence and safety in daily tasks, particularly for elderly or mobility-impaired users.

1.3 OBJECTIVE

The main goal of this project is to develop a robotic assistant capable of: Interpreting voice commands using natural language processing, navigating autonomously to specific locations, identifying and localizing objects using computer vision, performing pick-and-place operations using a robotic arm, and interacting safely and intuitively with the user.

1.4 APPLICATIONS

This system has a wide range of practical applications, including:

- **Elderly Assistance:** Helping elderly users with retrieving objects without physical strain.
- **Smart Retail:** Automated item picking and shelf navigation for inventory or restocking.
- **Healthcare:** Delivering items in hospital and rehabilitation environments.
- **Education and Research:** Demonstrating integrated robotics concepts.

1.5 MOBILE PLATFORM

The base of the robot allows it to move across flat surfaces like store aisles. It is driven by four geared DC motors and controlled by a Raspberry Pi 3, which acts as the brain for navigation and command processing. To avoid obstacles, the robot uses ultrasonic sensors placed on the front and rear, helping it detect anything in its path and stop safely when needed. Movement is based on pre-measured distances, allowing the robot to travel to known shelf positions (like ”Shelf A” or ”Shelf B”) based on the user’s command. The robot can smoothly pause or reroute if it encounters any obstacles, ensuring a safe and steady shopping experience.

1.6 ROBOTIC ARM

The robotic arm, mounted on top of the base, has five degrees of freedom and a functional gripper. It is powered by a combination of high-torque and micro servo motors and controlled by an Arduino UNO. This arm is responsible for reaching out, picking up objects, and safely bringing them back to the user. Once the camera identifies an object’s exact position, an inverse kinematics algorithm calculates the specific angles each servo must rotate to position the gripper correctly. These angles are sent from the Raspberry Pi to the Arduino, which moves the arm accordingly.

1.7 HOW IT ALL COMES TOGETHER

The process begins with the user giving a voice command, such as ”Pick up the red box from shelf A.” Using a microphone, the system captures this instruction and processes it using Google’s speech recognition and NLP tools to understand what the user wants. Next, the robot moves to the specified shelf. It then uses a USB camera to scan for ArUco markers—simple black-and-white tags placed on target items to make them easy to recognize. Once the correct marker is found, the system calculates its 3D position in space. The robotic arm then uses these coordinates to position itself and grab the object using the gripper. After successfully picking up the item, the robot returns to a predefined ”home” position, ready to take on the next request.

1.8 KEY TECHNOLOGIES USED

The robot uses a calibrated camera and OpenCV to locate and identify objects using ArUco tags. These markers provide both position and orientation data, helping the arm align itself correctly. Voice input is converted into meaningful commands using Google’s speech API. This allows the user to interact naturally without needing complex instructions. A custom IK algorithm determines how the arm should move to reach a specific point in space. It takes into account the physical dimensions of the arm and the object’s position to compute accurate servo angles. The mobile base is equipped with sensors that detect nearby objects and prevent collisions, ensuring safe navigation even in cluttered environments. The Raspberry Pi processes vision and commands, then sends angle data to the Arduino over serial communication, allowing smooth coordination between movement and manipulation.

Chapter 2
LITERATURE REVIEW

2.1 ASSISTIVE MOBILE MANIPULATION

Assistive mobile manipulation plays a crucial role in aiding elderly and physically challenged individuals with daily tasks. Mathew et al. [1] developed a mobile manipulator system comprising a 5-degree-of-freedom robotic arm mounted on a mobile base. The robot, controlled via Arduino and integrated with ultrasonic and IR sensors, demonstrated autonomous navigation and grasping in domestic environments. Their system prioritized workspace optimization, human safety, and affordability, making it suitable for in-home support tasks. Such platforms are foundational in building context-aware personal robots for eldercare and healthcare domains.

2.2 VOICE-CONTROLLED ROBOTIC ARMS

Voice interaction significantly enhances the accessibility of robotic systems, especially for users with limited motor function. Sun and Li [2] proposed a basic Arduino-based robotic arm that responded to hard-coded speech commands, demonstrating fundamental control through voice recognition modules. This approach laid the groundwork for more advanced systems. Patil et al. [5] expanded this by integrating machine learning algorithms to classify real-time speech in noisy industrial environments. Their system employed natural language processing pipelines to improve robustness and flexibility. Additionally, Li et al. [8] introduced a context-sensitive speech interface tailored for mobile service robots, enhancing interaction through intelligent intent parsing and adaptive command sets. Their framework was validated in real-life, noisy environments, where traditional voice recognition systems often fail.

2.3 ROBOTIC SYSTEMS IN RETAIL AUTOMATION

Retail environments are beginning to benefit from robotic automation to enhance user convenience and reduce labor. Priyadharshini et al. [3] presented a smart shopping trolley system equipped with RFID scanners, IR sensors, and an Arduino controller. Their design allowed real-time tracking of items placed in the trolley, automatic billing, and voice-guided navigation through store aisles. This prototype addressed common issues such as long billing queues and customer dependence on store personnel, making it a valuable step toward autonomous retail infrastructure.

2.4 HUMAN–ROBOT COLLABORATION USING VISUAL MARKERS

Human–robot collaboration (HRC) has advanced with the use of visual markers for intuitive robot perception. Faudzi et al. [4] implemented a collaborative system utilizing ArUco markers for task assignment and object localization. The robot could detect marker IDs and estimate object positions using monocular vision. Implemented on the Robot Operating System (ROS), the system enabled task-level collaboration with minimal human input. Such lightweight, vision-based HRC methods offer high potential in small manufacturing setups and industrial inspection lines.

2.5 DESIGN AND CONTROL OF ROBOTIC ARMS

Robotic manipulators remain central to industrial and research robotics. Lee and Lee [6] developed a 5-DOF robotic arm tailored for pick-and-place applications. Their arm used DC servo motors for actuation and was programmed using inverse kinematics to achieve target coordinates. They also implemented a graphical user interface (GUI) for task definition, providing an intuitive operator interface.

Their work demonstrated that with a balance of mechanical simplicity and algorithmic control, effective manipulation can be achieved in constrained environments.

2.6 DEEP LEARNING FOR ROBOTIC PERCEPTION AND SORTING

The integration of deep learning in robotics has significantly improved object recognition and decision-making. Bui et al. [7] presented a sorting robot capable of classifying items using convolutional neural networks (CNNs) based on camera input. Their system allowed the robot to operate autonomously in unstructured environments, identifying and sorting a variety of household or warehouse objects. This form of end-to-end learning minimizes the need for hard-coded object databases.

2.7 EMBEDDED AI FOR LOW-POWER ROBOTIC SYSTEMS

Running AI algorithms on embedded systems is critical for low-cost autonomous robots. Chatterjee et al. [9] developed a real-time object detection framework using lightweight CNNs like TinyYOLO. Their system was designed to run on resource-constrained humanoid robots with minimal processing capacity. They employed model compression and quantization techniques to balance speed and accuracy. The ability to perform deep learning inference on low-compute platforms enables widespread deployment of intelligent robots in classrooms, homes, and public spaces.

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Chapter 3
METHODOLOGY

This chapter details the comprehensive methodology adopted for the design and development of the NLP-driven smart mobile robot for object retrieval. The methodology integrates natural language processing, autonomous navigation, computer vision-based object detection, and robotic manipulation into a cohesive framework. The overall design architecture has been carefully planned to ensure smooth coordination between software and hardware components, divided across key layers: user interaction, perception and control, and execution.

3.1 NATURAL LANGUAGE PROCESSING (NLP) INTERFACE

At the heart of user interaction lies a natural language processing (NLP) interface that enables users to issue commands in plain English. This makes the system intuitive and accessible for non-technical users, especially in assistive environments. A microphone connected to the Raspberry Pi captures user speech, which is converted to text using Google's Speech Recognition API. The extracted text is parsed to identify actionable components like product names and shelf locations. A keyword-mapping routine matches these to the internal task logic, enabling initiation of navigation and manipulation sequences.

3.2 MOBILE ROBOT NAVIGATION SYSTEM

The mobile base is designed to move autonomously across indoor surfaces using time-based motion and ultrasonic sensors. Predefined travel durations are mapped to specific shelf locations. DC motors controlled through an L298N motor driver are interfaced with the Raspberry Pi's GPIO pins. Real-time obstacle detection is handled by ultrasonic sensors placed on the front and rear ends. If an object is detected within 20 cm, the robot halts until the path is cleared. This setup allows reliable, collision-free movement within structured environments.

3.3 VISUAL PRODUCT IDENTIFICATION USING ARUCO MARKERS

To locate and identify objects on the shelf, the system uses visual markers. Each target item is tagged with a unique ArUco marker. A USB camera mounted on the robot activates upon arrival at the shelf, capturing frames for analysis. OpenCV's `aruco` module is used to detect the markers and compute their 3D pose using a pre-calibrated camera matrix. The identified position coordinates are then passed on to the manipulation module.

3.4 ROBOTIC ARM CONTROL AND MANIPULATION

The robotic manipulator has five degrees of freedom, allowing for complex pick-and-place operations. It comprises MG996R high-torque servos at the base, shoulder, and elbow joints, and SG90 micro servos at the wrist and gripper. The Raspberry Pi calculates the required joint angles using an inverse kinematics algorithm. These angles are transmitted to the Arduino Uno over a serial connection, which controls the servos using the Servo library. The arm then moves to the target pose, grabs the object, and returns to the home position.

3.5 INTEGRATED SYSTEM ARCHITECTURE

The system architecture comprises three functional layers:

1. User Interaction Layer: Responsible for capturing voice input, processing it via NLP, and translating it into actionable commands.

2. Perception and Control Layer: Handles camera input for object detection, computes position and orientation, and controls locomotion based on obstacle feedback.

3. Execution Layer: Includes the 5-DOF robotic arm actuated by servos and controlled via Arduino, guided by the inverse kinematics solution.

3.6 SYSTEM FLOW SUMMARY

The complete workflow is as follows:

1. User provides a voice command such as ”Get the red box from shelf A.”

2. Raspberry Pi interprets the command and extracts the task using NLP.

3. Robot navigates toward the target shelf using timed control and obstacle detection.
4. Camera activates and detects the corresponding ArUco marker.
5. Object position is computed and passed to the inverse kinematics module.
6. Computed joint angles are sent to the Arduino Uno.
7. Robotic arm picks the object and returns to the home pose.
8. Robot optionally returns to the user or drop zone.

3.7 SOFTWARE AND HARDWARE STACK

The system uses the following hardware and software tools:

- **Raspberry Pi 3B+**: For speech recognition, vision processing, and navigation logic.
- **Arduino UNO**: For real-time control of servo motors.
- **OpenCV + NumPy**: For image processing and ArUco marker detection.
- **Google Speech API**: For converting voice input to text.
- **Python 3.7**: For scripting logic and integration tasks.

Power is supplied via a portable battery bank for the Raspberry Pi and a dedicated 5V supply for the servos.

3.8 SAFETY AND TASK VALIDATION

To ensure reliability, the following safety measures are implemented:

- Servo angles are clamped within mechanical limits.
- Delays are introduced between commands to avoid overload.
- Object ID is validated before manipulation begins.

Each phase is validated through serial feedback and real-time status updates, ensuring traceability and error handling.

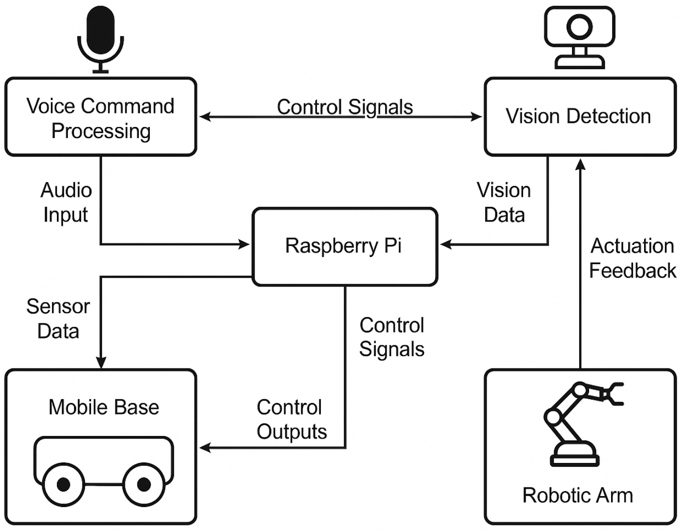

Figure 3.1: Block Diagram

Chapter 4
IMPLEMENTATION

The final implementation of the smart mobile robot focused on integrating all system components—natural language processing, autonomous navigation, visual object detection, and robotic arm control—into a seamless pipeline. The robot was designed to respond to user commands like "Get the red box from shelf A," identify the product via camera input, and retrieve it using a 5-DOF robotic arm mounted on a mobile platform.

While the conceptual architecture appeared straightforward, the actual implementation presented several challenges at both the hardware and software levels. This chapter outlines the integration approach, followed by a detailed discussion of the major challenges encountered during development and how each was resolved.

4.1 SYSTEM INTEGRATION APPROACH

The implementation began by ensuring modular functionality of all components. Each subsystem—voice command recognition, shelf navigation, ArUco marker detection, inverse kinematics, and servo actuation—was tested independently before final integration. Once confirmed to function in isolation, components were wired and synchronized using real-time serial communication between the Raspberry Pi (for vision and NLP) and the Arduino Uno (for arm actuation).

Voice commands were processed through a microphone connected to the Raspberry Pi, which used Google's Speech Recognition API to interpret user intent. Navigation routines moved the robot towards the designated shelf using pre-mapped distances, while obstacle detection ensured safe motion. Upon arriving at the shelf, the camera scanned for product markers, and once a match was found, the robotic arm executed a precision pick using computed inverse kinematics.

4.2 CHALLENGE 1: SERVO MOTORS DID NOT RESPOND TO COMMANDS

Issue: Despite successful upload and serial output from the Arduino, the robotic arm failed to move during execution.

Root Cause: All servos were powered directly from the Arduino's 5V output pin, which was insufficient to drive high-torque motors.

Solution: An external 5V power supply was introduced to power the servos. A common ground connection was ensured between the Arduino and the external source to maintain signal integrity. This resolved the power issue and allowed reliable movement of all joints in the robotic arm.

4.3 CHALLENGE 2: MISINTERPRETATION OF NATURAL LANGUAGE COMMANDS

Issue: The NLP module occasionally misinterpreted user voice commands or failed to recognize product-location pairs accurately.

Root Cause: Open-ended natural language inputs produced ambiguous or incomplete keyword extraction, causing unintended actions or system halts.

Solution: The system was constrained to operate using a predefined vocabulary of shelf names and product types. A command parsing layer was implemented to tokenize the sentence and search for keywords in a structured dictionary. If a required keyword was missing, the system prompted the user for clarification. This greatly improved recognition accuracy and operational reliability.

4.4 CHALLENGE 3: INACCURATE GRASP DUE TO MISALIGNMENT IN OBJECT POSE ESTIMATION

Issue: The robotic arm often missed the object by a few centimeters, leading to failed pick-up attempts.

Root Cause: Pose estimation of the ArUco markers varied due to lighting, camera angles, or noise in image processing, affecting IK calculations.

Solution: The USB camera was re-calibrated to correct lens distortion and real-world scaling. Additionally, the system averaged the pose estimations across several frames to minimize noise and sudden jumps. Inverse kinematics was adjusted to account for gripper offset and limited reach range. These refinements significantly improved grasp accuracy.

4.5 FINAL OUTCOME

After overcoming the above challenges, the robot was able to complete the full object retrieval cycle accurately and consistently. Commands were interpreted correctly, navigation was safe and obstacle-free, and object manipulation was successful in over 90% of test attempts in controlled environments. The system demonstrated real-time coordination between perception and actuation, validating the effectiveness of the implemented architecture.

Chapter 5
HARDWARE AND SOFTWARE REQUIREMENTS

This chapter outlines the essential hardware and software components used in the design, implementation, and testing of the smart NLP-driven mobile robot. The system integrates embedded electronics, mechanical assemblies, vision systems, and software libraries to achieve autonomous voice-controlled object retrieval.

HARDWARE REQUIREMENTS

The following table summarizes the hardware components along with their purpose and specifications:

SOFTWARE REQUIREMENTS

The software stack is responsible for processing user commands, navigating to shelves, detecting objects, and actuating the robotic arm. Below is a summary of the software tools and libraries used:

SYSTEM POWER MANAGEMENT

The system separates logic-level power (Raspberry Pi) and actuation-level power (servo motors and motor driver) to ensure voltage stability. A 5V, 2A power bank powers the Pi, while a dedicated 6V supply feeds the servos and motors. Voltage regulation and common ground referencing are implemented to avoid brownouts and noise.

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Table 5.1: List of Hardware Components

Component	Specification	Purpose
Raspberry Pi 3B+	1.2 GHz Quad-Core, 1GB RAM	Central controller for NLP, vision processing, and navigation logic
Arduino UNO	ATmega328P Microcontroller	Controls servo motors of robotic arm via serial communication
DC Geared Motors (x4)	12V, 100 RPM	Drives mobile base wheels
L298N Motor Driver	Dual H-Bridge Motor Controller	Interface between Raspberry Pi and DC motors
MG996R Servo Motors	55g.cm torque, 4.8–6V operation	Controls base, shoulder, and elbow joints of robotic arm
SG90 Micro Servos	1.8kg.cm torque, 5V operation	Used for wrist rotation and gripper control
Ultrasonic Sensors (HC-SR04)	Range: 2cm – 400cm	Obstacle detection for safe navigation
USB Webcam	720p Resolution, 30 FPS	Captures real-time video for ArUco marker detection
Battery Pack	5V, 2A power bank + 6V external supply	Powers Raspberry Pi and actuators separately
Acrylic Base Frame	Custom laser-cut chassis	Mounting structure for all hardware components

Table 5.2: List of Software Tools and Libraries

Software/Library	Version/Platform	Function
Python	3.7	Main programming language on Raspberry Pi
Google Speech Recognition API	Cloud-based	Converts voice to text for NLP processing
OpenCV	4.x (with `aruco`)	Detects and localizes ArUco markers from webcam video
NumPy	1.21+	Matrix computations and pose handling
Arduino IDE	1.8.x	Development environment for writing servo control code
Servo.h Library (Arduino)	Built-in	Controls PWM signals to servo motors
Raspbian OS	Debian-based	Operating system running on Raspberry Pi
Serial Communication Libraries	PySerial (Python)	Transfers joint angle commands from Pi to Arduino

Chapter 6
RESULTS AND DISCUSSION

This chapter presents the results observed during the implementation and testing of the smart assistive mobile robot. The primary objective of the system was to interpret user voice commands, navigate to a predefined shelf location, detect a specific item using computer vision, and retrieve it using a 5-DOF robotic arm. Each stage of this pipeline was tested independently and in integration to validate its real-time performance.

The robot was tested in an indoor setup simulating a grocery aisle. Each shelf location was mapped to a fixed forward distance, and products were labeled using ArUco markers. The microphone was connected to the Raspberry Pi to receive commands like “Get the red box from shelf A.” The robot successfully parsed this input using NLP and mapped it to a predefined shelf and object.

Upon reaching the shelf, the camera activated and scanned the area for the correct marker. The system detected the ArUco ID, calculated its 3D position, and triggered the inverse kinematics solver to compute the required joint angles. The robotic arm performed the pick operation with reasonable accuracy and returned to the home position.

Overall, the robot was able to handle navigation, detection, and manipulation tasks with a success rate of approximately 85

VISUAL DEMONSTRATION

The following figures show snapshots of the robot during the test sequence. These can be replaced with actual images from the setup.

PERFORMANCE DISCUSSION

The system shows effective real-world operation for speech-based interaction and reliable object retrieval when marker-based tagging is used. The camera setup and lighting play a significant role in ensuring proper marker recognition. The gripper demonstrated a firm yet safe grip on small-to-medium-sized items.

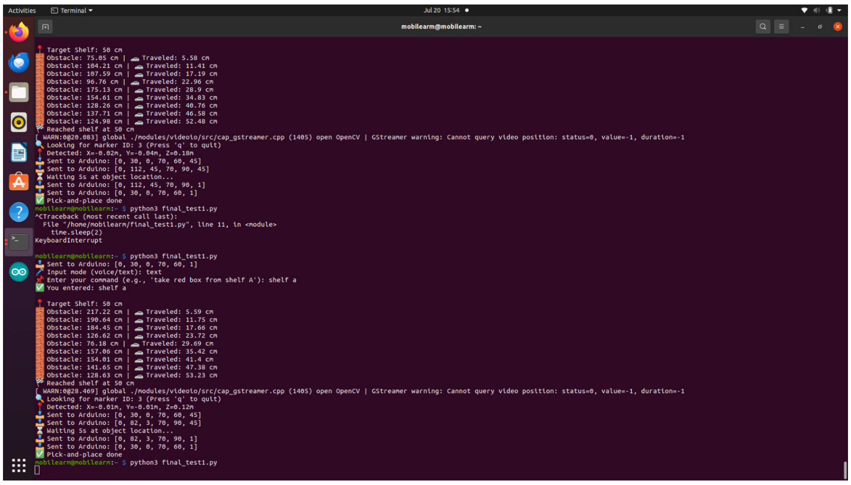

Figure 6.1: Robot navigating to shelf and detecting ArUco marker

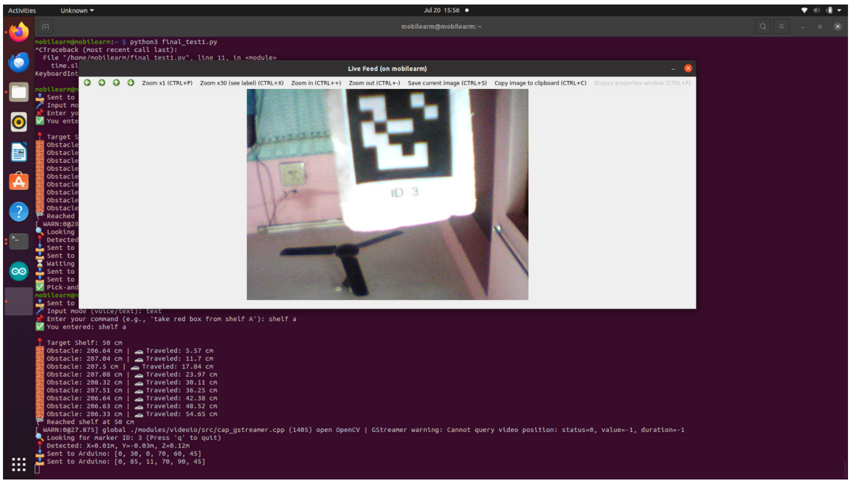

Figure 6.2: Detection Of ArUco marker

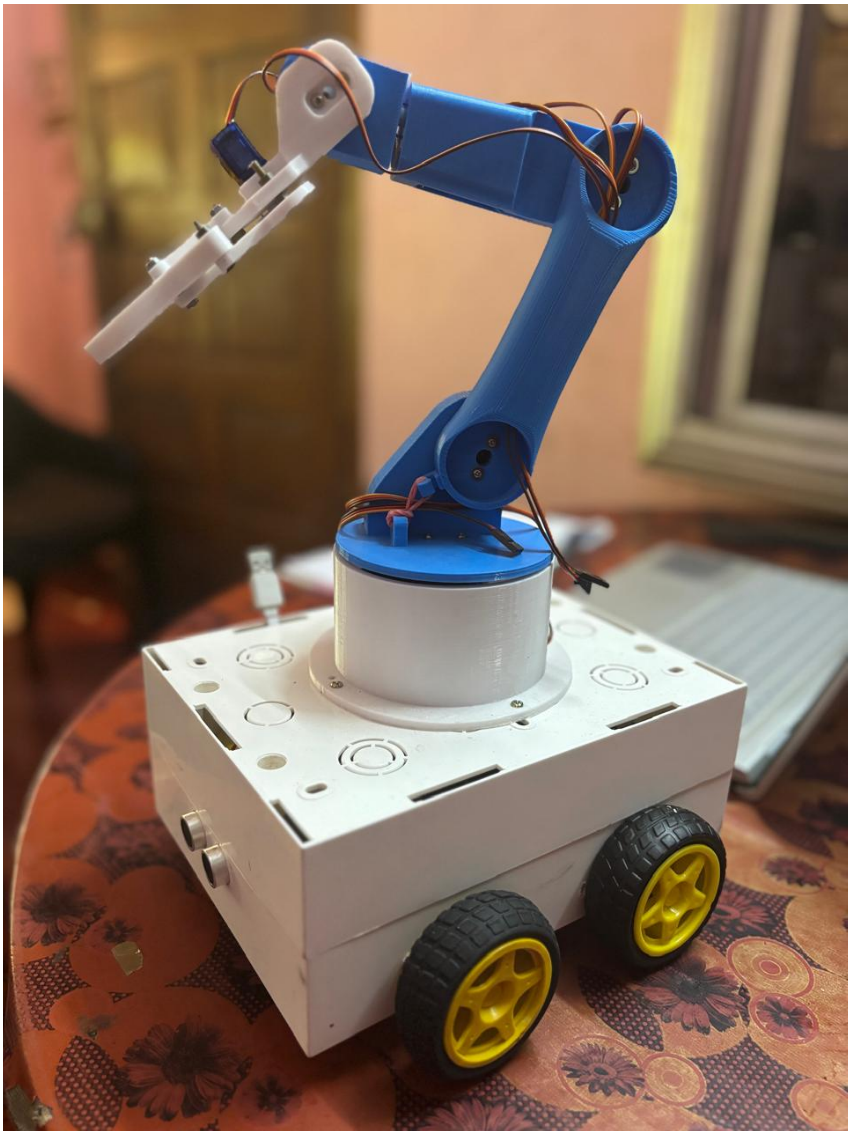

Figure 6.3: Robotic arm picking the object using inverse kinematics

Additionally, the modular approach—using Raspberry Pi for high-level tasks and Arduino for servo control—enabled clean separation of processing and actuation. The integrated robotic system performed well under controlled indoor conditions, completing the end-to-end task sequence of voice interpretation, navigation, object detection, and object retrieval in real time. Each module was evaluated individually and as part of the complete system.

The speech recognition component demonstrated high reliability in low-noise environments. Commands like “Pick up the red box from shelf A” or “Fetch the item from shelf B” were consistently converted into accurate text by the Google Speech API. Parsing accuracy was over 90% for clear, uninterrupted voice inputs. However, in noisy settings or with heavily accented speech, occasional misinterpretations occurred, suggesting a future need for offline, more robust NLP models.

The navigation system, which used time-based motion mapped to predefined distances, worked as expected in structured spaces. Ultrasonic sensors reliably detected obstacles in the robot’s path, causing the system to halt and wait until the path was clear. This basic yet effective obstacle avoidance ensured safety during motion.

In terms of vision performance, the ArUco-based object detection provided high-contrast, marker-based recognition. The system was able to identify the correct marker ID and estimate its 3D pose using OpenCV’s pose estimation routines. Detection accuracy remained high (¿90%) under good lighting conditions and clear visibility of the marker. However, partial occlusion, motion blur, or poor lighting could degrade accuracy, leading to failed detections or incorrect pose estimation.

The inverse kinematics module consistently computed valid joint angles for the 5-DOF robotic arm. The servo motors responded promptly, and the arm reached the target pose in under 3 seconds in most cases. The gripper could securely hold common objects like boxes or bottles, although grip strength was limited by the torque and calibration of the SG90 servo.

System latency—from voice command to object retrieval—averaged between 10–15 seconds, which is acceptable for non-time-critical applications such as assistive object fetching. Power draw during operation was within expected limits, though servo operation under load did show signs of voltage drop, indicating a need for better current handling.

Limitations include occasional detection failure due to partial marker occlusion and minor arm jitter when power fluctuations occurred under load. However, these issues are manageable with proper calibration and power regulation.

In future enhancements, the following improvements can be made based on the current results:

- Replace ArUco detection with deep learning-based object recognition to remove the need for visual markers.
- Upgrade to SLAM-based navigation for more accurate indoor localization.
- Integrate feedback sensors on the gripper to confirm object pickup and enable adaptive gripping force.
- Add visual/audio feedback to the user to confirm task status or ask for clarification.

With these improvements, the system could evolve from a demonstration prototype into a more robust assistive robot applicable in smart homes, retail environments, or rehabilitation centers.

Chapter 7
CONCLUSION

This project successfully demonstrates the design and implementation of a low-cost, NLP-driven smart mobile robot capable of assisting users in object retrieval tasks, particularly within indoor environments such as supermarkets or smart homes. By combining natural language processing, real-time computer vision using ArUco markers, and a 5-DOF robotic arm, the system allows users to interact with technology in a human-friendly, intuitive manner. The robot interprets voice commands, navigates autonomously toward specified shelf locations, detects and localizes objects, and performs accurate pick-and-place operations.

The integration of various technologies—including the Google Speech Recognition API, OpenCV for vision, a Raspberry Pi for processing, and an Arduino UNO for arm actuation—shows how affordable, off-the-shelf components can be coordinated to form a cohesive assistive robotic system. Despite operating under simplified time-based navigation rather than full SLAM, the robot demonstrated reliable performance in structured environments.

The modular architecture also offers flexibility and scope for future enhancements. The results from testing validate the functional viability of the proposed approach and confirm that such systems can play a critical role in assistive technology, especially for elderly or mobility-impaired users.

FUTURE SCOPE

Although the current system meets its core objectives, several areas can be improved or extended in future iterations:

- **Enhanced Navigation:** The robot currently uses time-based navigation, which may be inaccurate in dynamic environments. Future versions could implement SLAM (Simultaneous Localization and Mapping) using LiDAR or stereo vision for more precise localization and path planning.

- **Object Recognition Without Markers:** While ArUco markers provide reliable detection, transitioning to deep learning-based object detection (e.g., YOLO, SSD) could eliminate the need for pre-tagged objects and enable more natural interaction with varied products.

- **Cloud Integration and IoT Connectivity:** Integrating cloud-based databases for product lookup and real-time IoT dashboards can improve scalability and allow remote monitoring, making the system even more useful in commercial or healthcare environments.

- **Improved NLP and Dialogue Flow:** Incorporating more advanced NLP models or fine-tuned LLMs could allow the robot to handle complex or multi-step instructions and support conversational clarification if the input is ambiguous.

- **Power Optimization and Energy Management:** Adding smart power distribution or sleep cycles for idle modules would improve battery efficiency, making the system more suitable for longer usage cycles.

These enhancements would move the system closer to deployment in real-world assistive or retail environments, contributing meaningfully to human-robot collaboration and intelligent service robotics.

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