

A photograph of a red Citroën 2CV car parked on a street at dusk. The car is in the foreground, angled slightly towards the left. It has a black roof rack and a license plate that reads 'YD26 272'. In the background is a large, multi-story brick building with several large arched windows. Some windows are illuminated from within, and a street lamp is visible. The sky is a pale blue-grey. The overall mood is nostalgic and urban.

ByteRider

Version

Table of Contents

INTRODUCTION	4
HOW DOES IT WORK?	5
• Reserved Pins & GPIOs	5
• Fusion of Software with Hardware	8
• Schematic	10
DATA STRUCT	11
• Data Payload	11
TRANSMITTER	13
• Configuration Variables	13
• Sending & Encapsulating Data	13
• Main Function	13
RECEIVER	15
• Configuration Variables	13
• Receiving & De-Encapsulating Data	15
• Main Function	13
WORK-IN-PROGRESS WALK THROUGH	17
• Finished Work	17
• Chassis	18
• Wiring	19
• Motor Wires Harness	20

ByteRider documentation



INTRODUCTION

HOW DOES IT WORK?

The BitByteRider RC car is powered by ESP32-C3 Breadboard & Power adapter development board.

Reserved Pins & GPIOs

The following table summarizes GPIOs and pins reserved for operations purposes.

The GPIO numbers correspond to those on the ESP32-C3 WROOM microcontroller. The Pin number corresponds to the pin on the Breadboard and Power adapter development board.

x- and y- axis

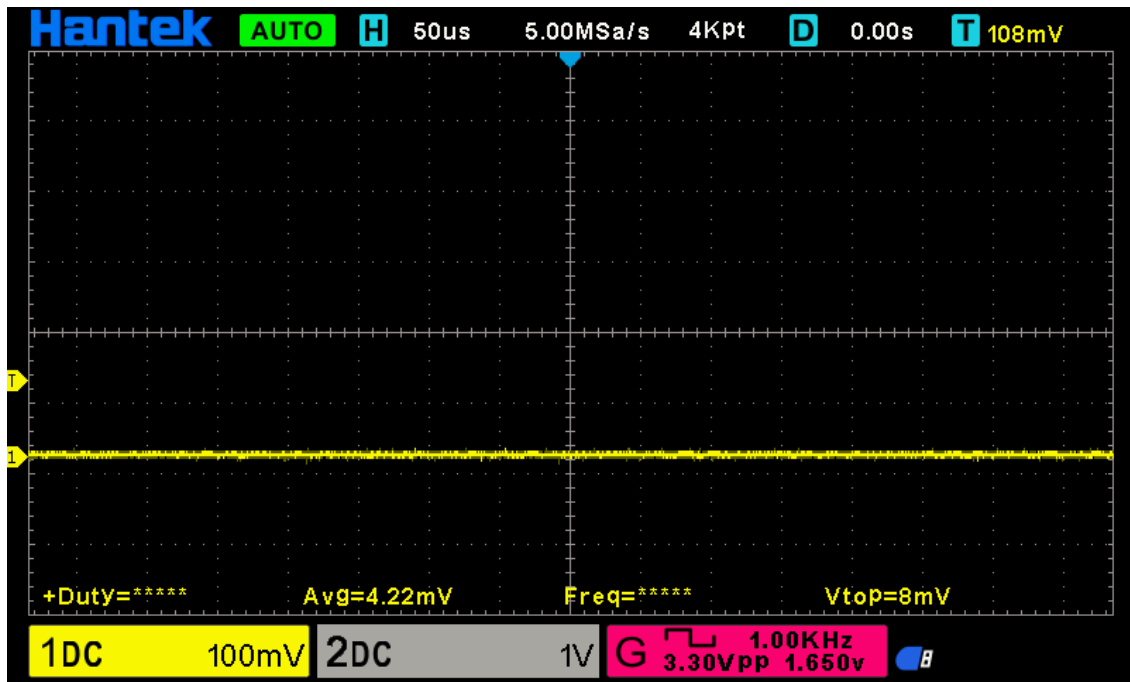
The **GPIO0** and **GPIO1** assigned to measuring the voltage of x- and y- axis of the Joystick. Lastly, there is a group of GPIO pairs responsible for PWM for DC motors.

Direction and Speed

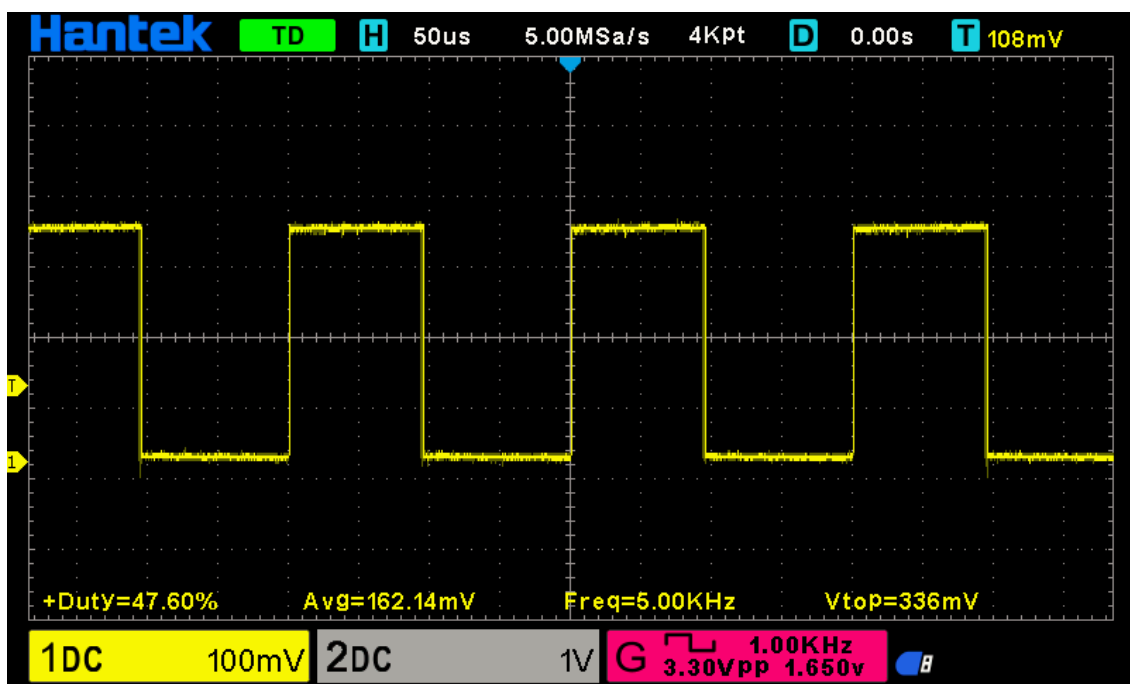
The pairs of DC motors on the left side are wired to the dedicated PWM channels. This means that *ESP32-C3 Breadboard DevBoard* can control rotation speed and direction of DC motors in pairs only (i.e. left and right side). Consequently, only four PWM channels are sufficient for controlling the direction of the RC car. Based on this constraint, the RC car can only move front, back, and turn/rotate left and right. Any other movements are not possible (i.e. diagonal or sideways).

A pair of PWM channels are required for defining rotation speed and direction of the DC motors on each side. In particular, **GPIO6** and **GPIO5** provide PWM to the left- and right- side DC motors to rotate in a **clockwise** direction. Similarly, **GPIO4** and **GPIO7** provide PWM to the left- and right- side DC motors to rotate in a **counter-clockwise** direction. Changing PWM on each channel determines the speed and direction of the RC car.

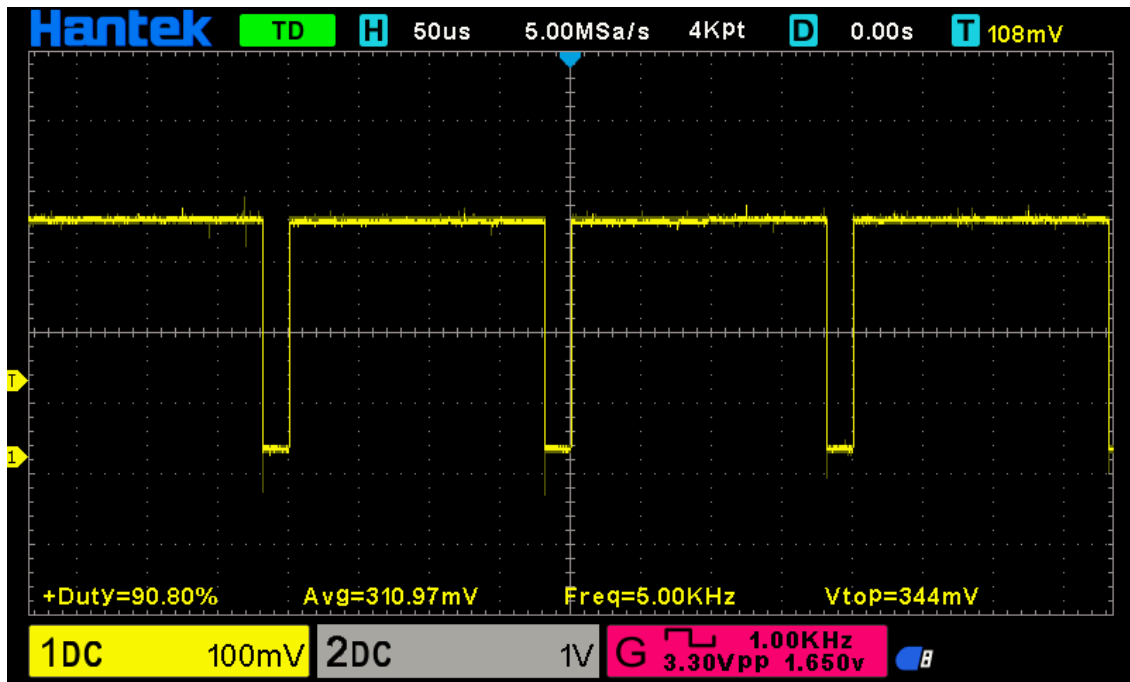
The following images illustrate various PWM duty cycles registered by oscilloscope (duty cycles 0%, 48% and 91%, resp.).



DC Motor PWM duty cycle 0%



DC Motor PWM duty cycle 47.6%



DC Motor PWM duty cycle 90.8%

GPIO	Pin	Function	Notes
0	16	Joystick x-axis	ADC1_CH0
1	15	Joystick y-axis	ADC1_CH1
8	5	Joystick push button	
6	4	PWM for clockwise rotation of left-side motors	LEDC_CHANNEL_1
5	3	PWM for clockwise rotation of right-side motors	LEDC_CHANNEL_0
4	2	PWM for counter-clockwise rotation of right-side motors	LEDC_CHANNEL_2
7	6	PWM for counter-clockwise rotation of left-side motors	LEDC_CHANNEL_3

Fusion of Software with Hardware

The *struct* for storing motors PWM values.

```
struct motors_rpm {  
    int motor1_rpm_pwm;  
    int motor2_rpm_pwm;  
    int motor3_rpm_pwm;  
    int motor4_rpm_pwm;  
};
```

The function for updating motors' PWM values.

```
// Function to send data to the receiver  
void sendData (void) {  
    sensors_data_t buffer;                // Declare data struct  
  
    buffer.crc = 0;  
    buffer.x_axis = 0;  
    buffer.y_axis = 0;  
    buffer.nav_btn = 0;  
    buffer.motor1_rpm_pwm = 0;  
    buffer.motor2_rpm_pwm = 0;  
    buffer.motor3_rpm_pwm = 0;  
    buffer.motor4_rpm_pwm = 0;  
  
    // Display brief summary of data being sent.  
    ESP_LOGI(TAG, "Joystick (x,y) position ( 0x%04X, 0x%04X )",  
(uint8_t)buffer.x_axis, (uint8_t)buffer.y_axis);  
    ESP_LOGI(TAG, "pwm 1, pwm 2 [ 0x%04X, 0x%04X ]",  
(uint8_t)buffer.pwm, (uint8_t)buffer.pwm);  
    ESP_LOGI(TAG, "pwm 3, pwm 4 [ 0x%04X, 0x%04X ]",  
(uint8_t)buffer.pwm, (uint8_t)buffer.pwm);  
  
    // Call ESP-NOW function to send data (MAC address of receiver,  
    // pointer to the memory holding data & data length)  
    uint8_t result = esp_now_send(receiver_mac, &buffer,  
sizeof(buffer));  
  
    // If status is NOT OK, display error message and error code (in  
    // hexadecimal).  
    if (result != 0) {  
        ESP_LOGE("ESP-NOW", "Error sending data! Error code:  
0x%04X", result);  
        deletePeer();  
    }  
    else
```



```

    ESP_LOGW("ESP-NOW", "Data was sent.");
}

```

The `onDataReceived()` and `onDataSent()` are two call-back functions that get evoked on each corresponding event.

```

// Call-back for the event when data is being received
void onDataReceived (uint8_t *mac_addr, uint8_t *data, uint8_t
data_len) {

    buf = (sensors_data_t*)data;                                //
    Allocate memory for buffer to store data being received
    ESP_LOGW(TAG, "Data was received");
    ESP_LOGI(TAG, "x-axis: 0x%04x", buf->x_axis);
    ESP_LOGI(TAG, "y-axis: 0x%04x", buf->y_axis);
    ESP_LOGI(TAG, "PWM 1: 0x%04x", buf->motor1_rpm_pwm);
}

// Call-back for the event when data is being sent
void onDataSent (uint8_t *mac_addr, esp_now_send_status_t status) {
    ESP_LOGW(TAG, "Packet send status: 0x%04X", status);
}

```

The `rc_send_data_task()` function runs every 0.1 second to transmit the data to the receiver.

```

// Continous, periodic task that sends data.
static void rc_send_data_task (void *arg) {

    while (true) {
        if (esp_now_is_peer_exist(receiver_mac))
            sendData();
        vTaskDelay (100 / portTICK_PERIOD_MS);
    }
}

```

Schematic



DATA STRUCT

The struct serves as the data payload for sending control signals from transmitting device to the receiver using ESP-NOW. In addition, it may contain additional data such as telemetry, battery status, etc.

The *sensors_data_t* struct is designed as a data payload that encapsulates all control commands and sensor states relevant to the vehicle's operation. It's intended to be sent from a transmitting device (like a remote control or master controller) to a receiver (such as a microcontroller onboard the vehicle).

```
typedef struct {  
    int      x_axis;           // Joystick x-position  
    int      y_axis;           // Joystick y-position  
    bool     nav_btn;          // Joystick push button  
    bool     led;              // LED ON/OFF state  
    uint8_t  motor1_rpm_pwm;    // PWMs for 4 DC motors  
    uint8_t  motor2_rpm_pwm;  
    uint8_t  motor3_rpm_pwm;  
    uint8_t  motor4_rpm_pwm;  
} __attribute__((packed)) sensors_data_t;
```

When used with communication protocols like ESP-NOW, this struct is **encoded** into a byte stream, then **transmitted** at regular intervals or in response to user input, and finally **decoded** on the receiving end to control hardware.

Data Payload

x_axis and *y_axis* fields capture analog input from a joystick, determining direction and speed. *nav_btn* represents a joystick push-button.

led allows the transmitter to toggle an onboard LED and is used for status indication (e.g. pairing, battery warning, etc).

motor1_rpm_pwm to *motor4_rpm_pwm* provide individual PWM signals to four DC motors. This enables fine-grained speed control, supports differential drive configurations, and even allows for maneuvering in multi-directional platforms like omni-wheel robots.

Why use `__attribute__((packed))`?

ESP-NOW uses fixed-size data packets (up to 250 bytes). The `__attribute__((packed))` removes compiler-added padding for precise byte alignment.

As *packed* attribute tells the compiler not to add any padding between fields in memory, this makes the struct:

- Compact
- Predictable for serialization over protocols like UART or ESP-NOW
- Ideal for low-latency transmission in embedded systems

This ensures the receiver interprets the exact byte layout you expect, minimizing bandwidth and maximizing compatibility across platforms.

TRANSMITTER

Configuration Variables

```
uint8_t receiver_mac[ESP_NOW_ETH_ALEN] = {0xe4, 0xb0, 0x63, 0x17,
0x9e, 0x44};
```

Sending & Encapsulating Data

```
void onDataReceived (const uint8_t *mac_addr, const uint8_t *data,
uint8_t data_len) {
    ESP_LOGI(TAG,
    "Data received from: %02x:%02x:%02x:%02x:%02x:%02x, len=%d",
    mac_addr[0], mac_addr[1], mac_addr[2], mac_addr[3], mac_addr[4],
    mac_addr[5], data_len);
    memcpy(&buf, data, sizeof(buf));

    x_axis = buf.x_axis;
    y_axis = buf.y_axis
}
```

Main Function

```
#include "freertos/FreeRTOS.h"
#include "nvs_flash.h"
#include "esp_err.h"

void app_main(void) {
    // Initialize internal temperature sensor
    chip_sensor_init();

    // Initialize NVS
    esp_err_t ret = nvs_flash_init();
    if (ret == ESP_ERR_NVS_NO_FREE_PAGES || ret ==
ESP_ERR_NVS_NEW_VERSION_FOUND) {
        ESP_ERROR_CHECK( nvs_flash_erase() );
        ret = nvs_flash_init();
    }
}
```

```
}  
ESP_ERROR_CHECK( ret );  
wifi_init();  
joystick_adc_init();  
transmission_init();  
system_led_init();  
}
```

RECEIVER

Configuration Variables

```
uint8_t transmitter_mac[ESP_NOW_ETH_ALEN] = {0x9C, 0x9E, 0x6E, 0x14,
0xB5, 0x54};
```

Receiving & De-Ecapsulating Data

```
void onDataReceived (const uint8_t *mac_addr, const uint8_t *data,
uint8_t data_len) {
    ESP_LOGI(TAG,
    "Data received from: %02x:%02x:%02x:%02x:%02x:%02x, len=%d",
    mac_addr[0], mac_addr[1], mac_addr[2], mac_addr[3], mac_addr[4],
    mac_addr[5], data_len);
    memcpy(&buf, data, sizeof(buf));

    x_axis = buf.x_axis;
    y_axis = buf.y_axis
}
```

Main Function

```
#include <string.h>
#include "freertos/FreeRTOS.h"
#include "nvs_flash.h"
#include "esp_err.h"

void app_main(void) {
    // Initialize NVS
    esp_err_t ret = nvs_flash_init();
    if (ret == ESP_ERR_NVS_NO_FREE_PAGES || ret ==
ESP_ERR_NVS_NEW_VERSION_FOUND) {
        ESP_ERROR_CHECK( nvs_flash_erase() );
        ret = nvs_flash_init();
    }
    ESP_ERROR_CHECK( ret );
}
```

```
wifi_init();
ESP_ERROR_CHECK(esp_now_init());

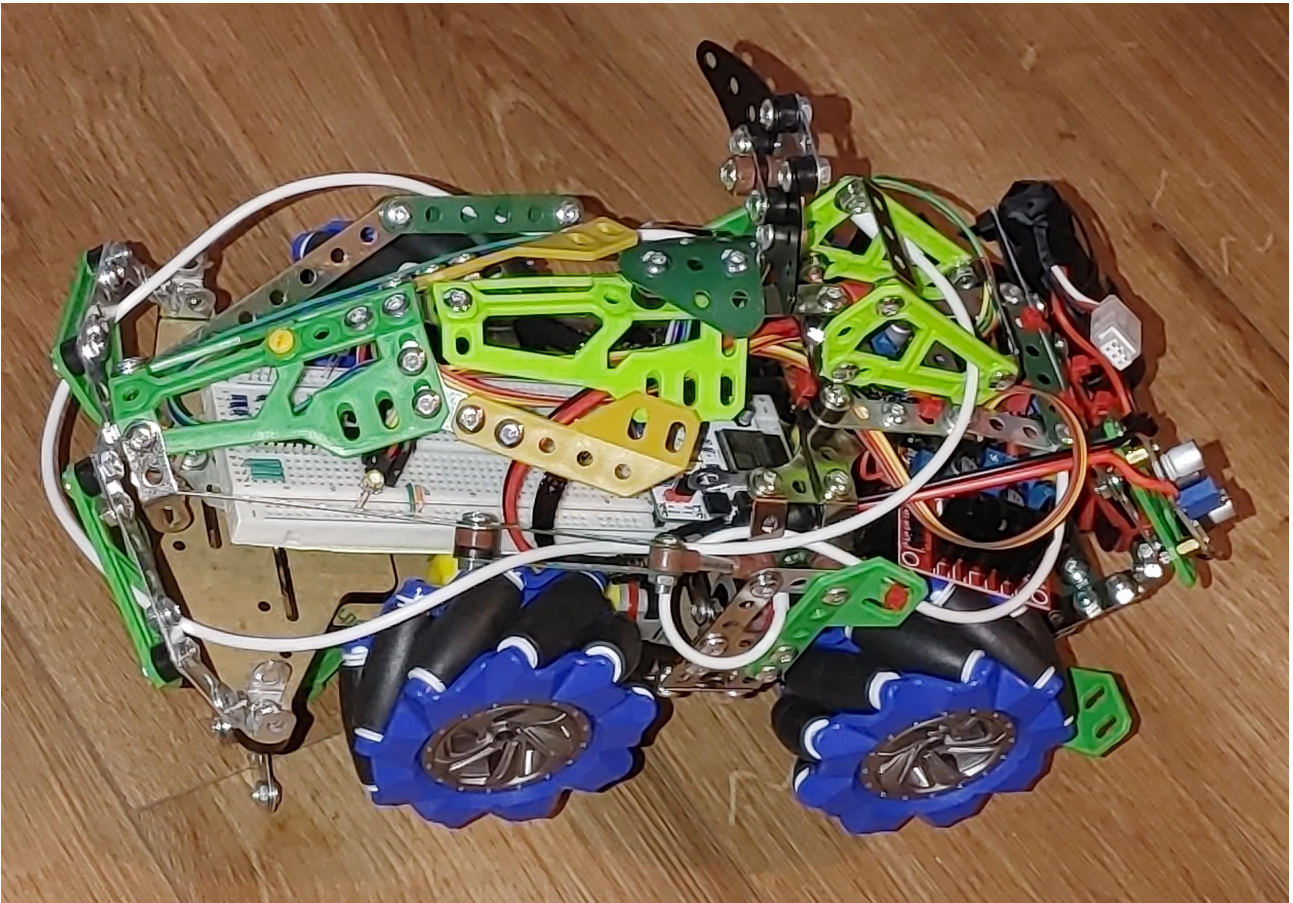
esp_now_peer_info_t transmitterInfo = {0};
memcpy(transmitterInfo.peer_addr, transmitter_mac,
ESP_NOW_ETH_ALEN);
transmitterInfo.channel = 0; // Current WiFi channel
transmitterInfo.ifidx = ESP_IF_WIFI_STA;
transmitterInfo.encrypt = false;
ESP_ERROR_CHECK(esp_now_add_peer(&transmitterInfo));

ESP_ERROR_CHECK(esp_now_register_recv_cb((void*)onDataReceived));

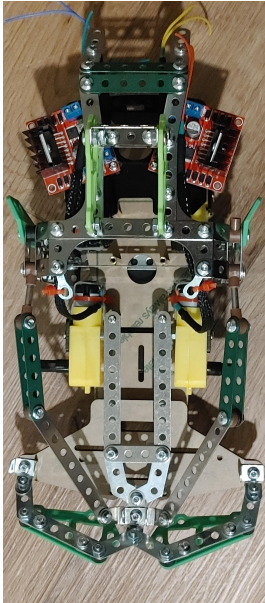
system_led_init();
}
```


WORK-IN-PROGRESS WALK THROUGH

Finished Work

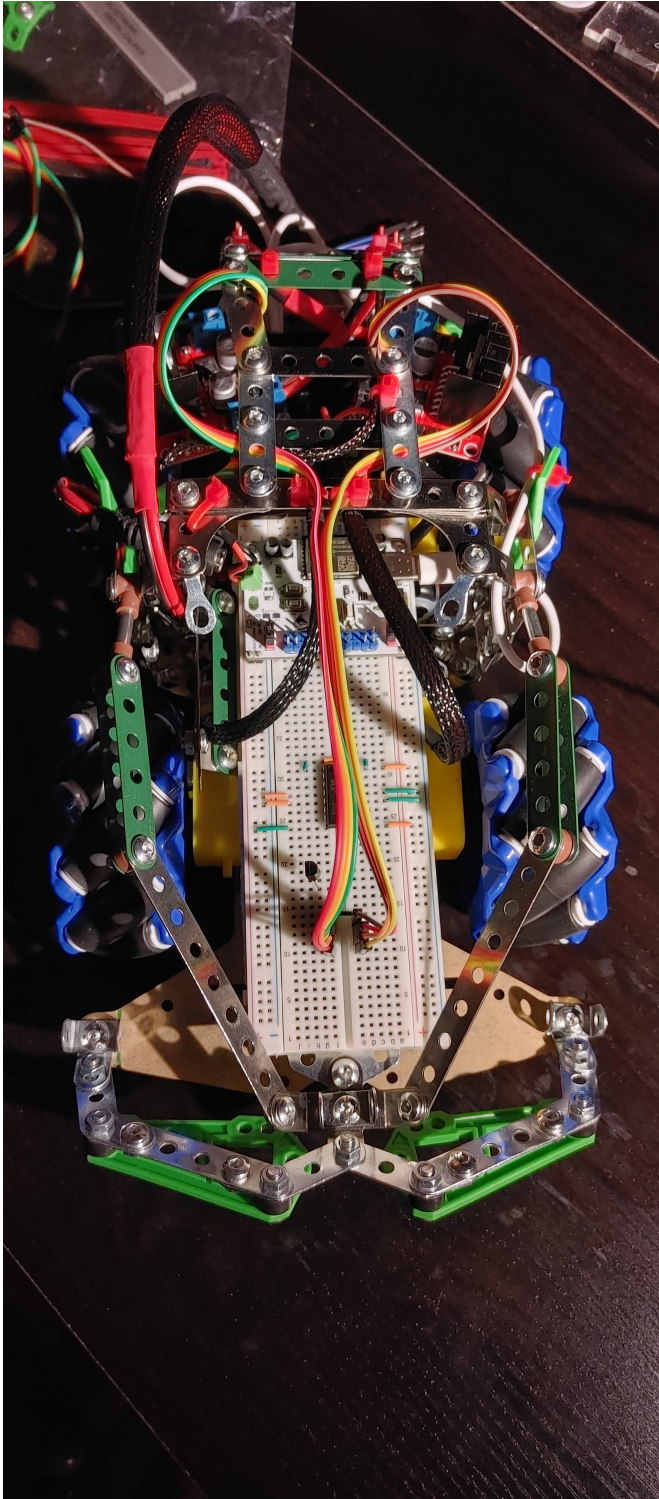


Chassis



Completed chassis with only DC motor controllers installed.

Wiring



Completed wiring.

Motor Wires Harness



DC Motors wires secured inside harness.

