

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

<b>INTRODUCTION</b>	<b>4</b>
<b>HOW DOES IT WORK?</b>	<b>5</b>
• Reserved Pins & GPIOs	5
• Fusion of Software with Hardware	6
• Schematic	8
<b>WORK-IN-PROGRESS WALK THROUGH</b>	<b>9</b>
• Finished Work	9
• Chassis	10
• Wiring	11
• Motor Wires Harness	12



# ByteRider documentation

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# 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 two DC motors on the left side are wired to the dedicated PWM channels in pairs. This means that PWM channels can control rotation speed and direction of DC motors in pairs (i.e. left and right side). Consequently, only four PWM channels are required for controlling the direction of the RC car. Based on this constraint, the RC car can only move front, back, and rotate left and right. Any other movements are not possible (i.e. diagonal).

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.

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.

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

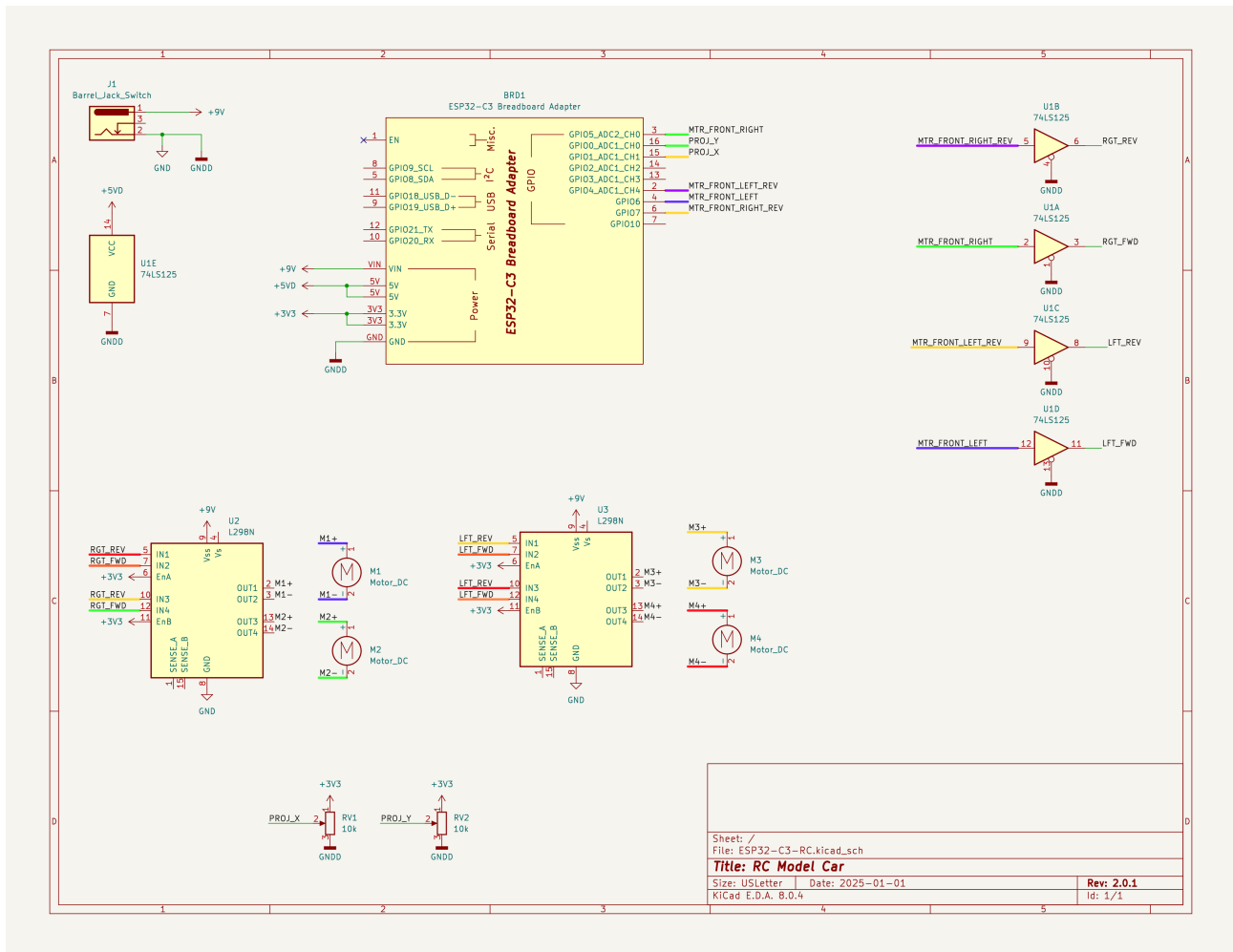
```

// Continuous, 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);
    }
}

```

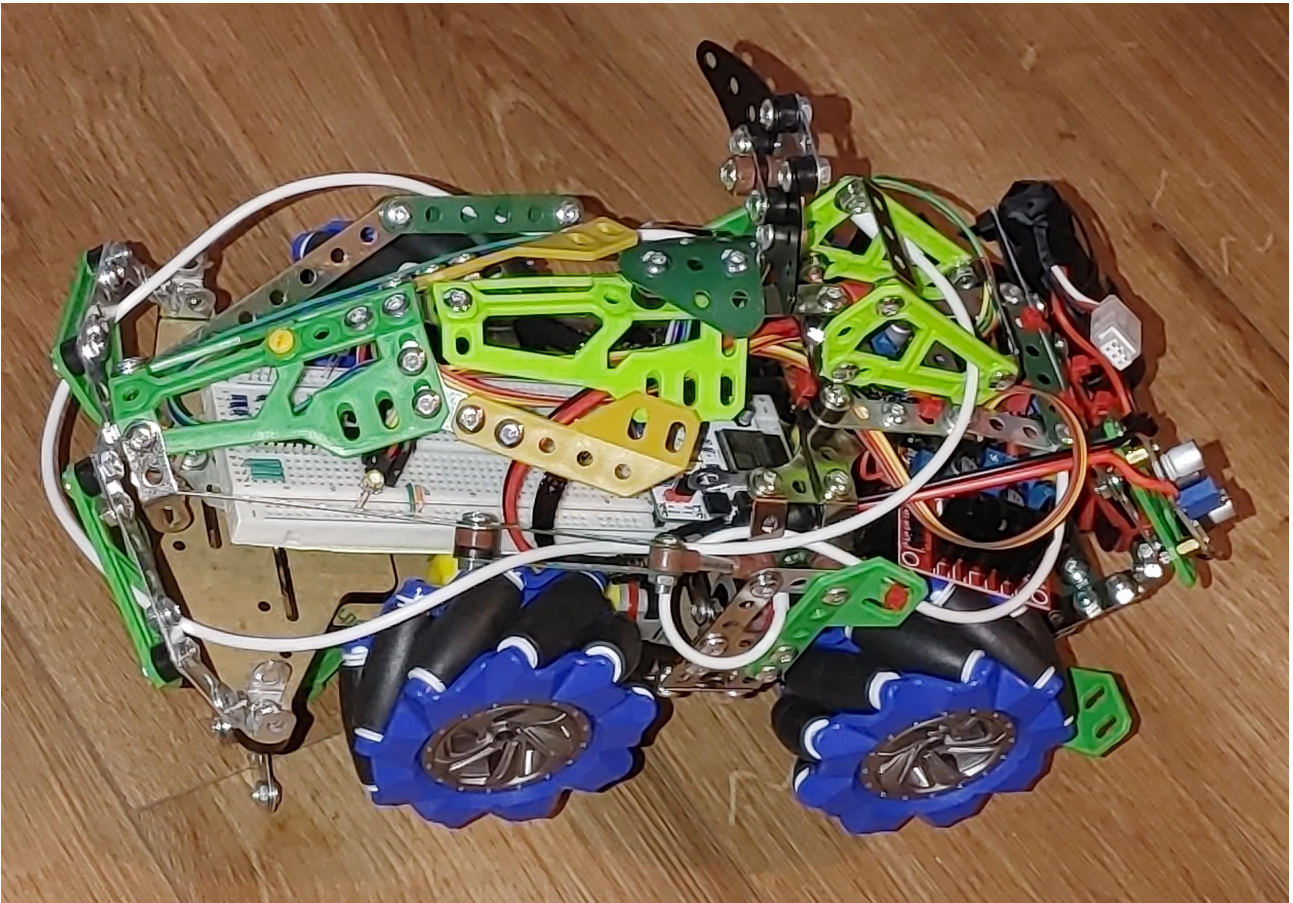
# Schematic



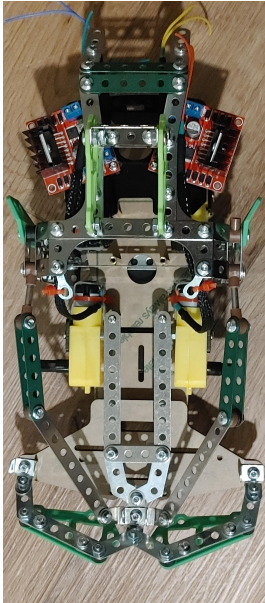


# WORK-IN-PROGRESS WALK THROUGH

## Finished Work

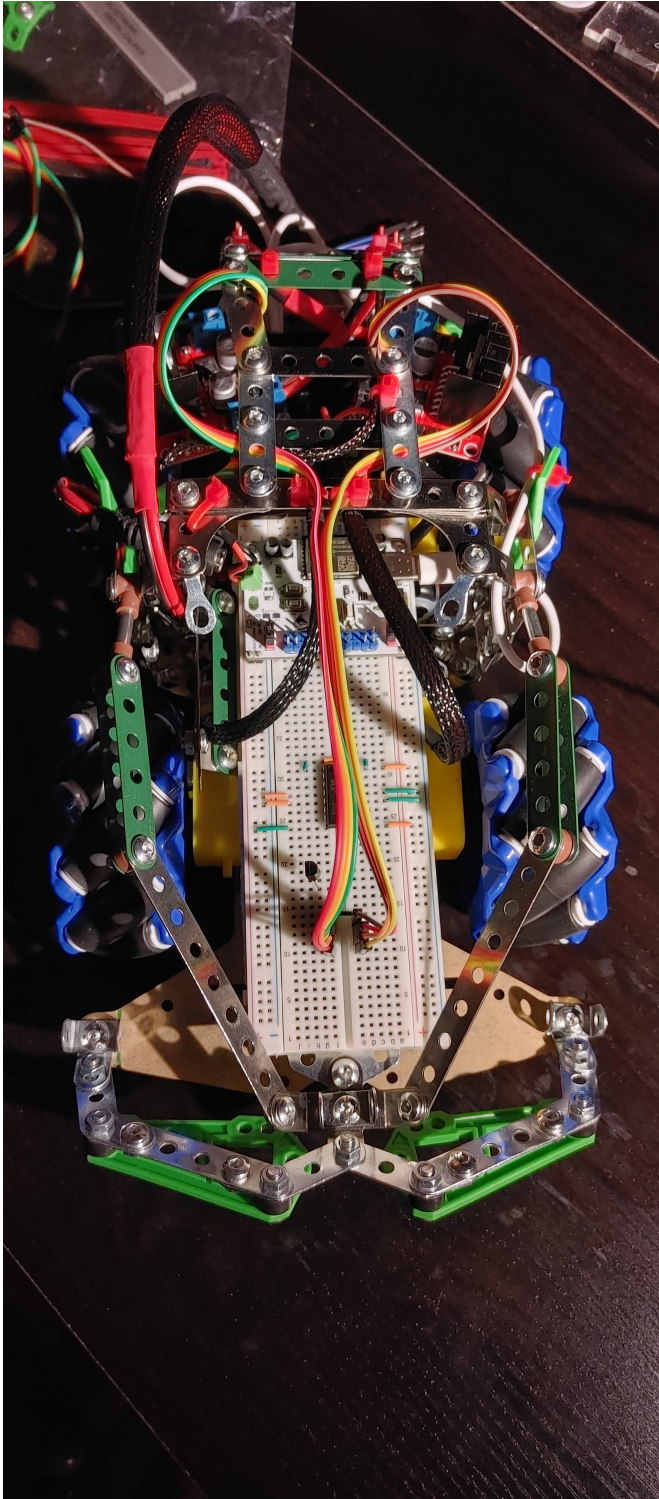


## Chassis



Completed chassis with only DC motor controllers installed.

## Wiring



Completed wiring.



## Motor Wires Harness



DC Motors wires secured inside harness.



