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# Design and Implementation of a Multi-Modal Wireless Robotic System for Smart Vehicle Navigation

Chaitanya Pilane, Dhanashri Pawar, Mansi Patekari, Lakshaya Pillai, Milind Patil

Department of Electronics and Telecommunication Engineering Vishwakarma Institute of Technology, Pune, Maharashtra, India

**Abstract**— This paper describes the design and development of a multi-modal wireless robotic system for the robotic vehicle that can be controlled manually by Bluetooth, voice, and navigation by gestures. In this, the Arduino is the center of the controlling unit that combines the communication and sensing modules. There is an HC-05 Bluetooth module that allows manual and voice commands by the smartphone app. In controlling gestures, it uses an accelerometer-gyroscope sensor, an MPU-6050 module, where a reliable means of wireless data transfer is done using RF transceivers, nRF24L01. In motor control, it uses an L298N motor driver and DC motors. For safety reasons, an ultrasonic sensor is employed for real-time obstacle detection. On detection of an obstacle within a fixed distance, the vehicle automatically stops to avoid collisions. The results demonstrate that there is stable communication, good control response, efficient obstacle avoidance, and smooth mode switching. The new system provides enhanced flexibility and convenience and can be applied to educational robots, mobility aids, and surveillance systems.

**Keywords**— Arduino, Bluetooth wireless communication, gesture-controlled system, voice-controlled system, robotic vehicle, ultrasonic sensor, obstacle detection, wireless robotic system

## I. INTRODUCTION

In the last two decades, interest in robotic vehicles has grown due to a variety of applications in industrial automation, military, healthcare, surveillance, and assistive mobility. Remote operation allows robotic systems to work in hazardous, inaccessible, or precision-demanding environments while improving user safety. Besides flexible mechanisms for control, safety-related features such as real-time obstacle detection are crucial for efficient robotic operation, especially in dynamic and unpredictable environments. Among several sensing techniques, ultrasonic sensors have been one of the widely adopted solutions for short-range obstacle detection due to their simplicity and efficacy. Conventional control of robotic vehicles has been developed in the framework of single-mode control systems, such as wired controllers, wireless handheld devices, or fixed control terminals. While functional, these methods usually share some serious drawbacks: notably, restricted flexibility and decreased user engagement. Given recent advances in human-machine interaction and wireless communication technologies, there is a growing need for intelligent robotic platforms that can support multiple control modes within one unified system architecture. This research work is devoted to the design and development of a multi-modal robotic vehicle control system that supports three complementary modes of operation: Bluetooth-based manual control, voice command control, and gesture-based control. Bluetooth-based control allows users to intuitively operate manually using a smartphone application. Voice control enables hands-free manipulation, which is greatly important in the case of physically disabled users. Gesture-based control embeds more interactivity by translating hand movement through the use of an accelerometer and gyroscope sensor into directional motion commands. The Arduino microcontroller is being exploited for the implementation of the proposed system. This controller has multi-communication interfaces on board—such as HC-05 Bluetooth modules and nRF24L01 RF transceivers for gesture recognition—supported by an MPU6050 sensor. In this, the motor actuation is given by the L298N motor driver, and UART, I2C, and SPI protocols provide support to communicate among system components. Multi-protocol integration allows coordinating heterogeneous hardware components in this environment with much efficiency. Apart from multi-modal control, the system integrates an ultrasonic sensor that continuously monitors any obstacles along the path of the vehicle. If there is detection of an obstacle inside a threshold distance predefined, it automatically stops the vehicle and hence supports collision avoidance and improves safety in its operational capabilities.

This capability runs across all control modes and enhances the system's practical applicability in real-world settings of indoor navigation, monitoring, and also assistive robotics.

While different robotic control systems using Bluetooth, voice, or gesture inputs are reported in the literature, most of the existing solutions focus on single-mode operation and do not allow seamless integration of multiple techniques within a unified platform. Furthermore, the literature has paid little attention so far to the issues of automatic modes switching and coherent safety enforcement across the various modes of control. Major contributions in this work are as follows: A unified multi-modal robotic control system, comprising design and implementation, that uses Bluetooth-based manual control, voice commands, and gesture-based navigation.

- Seamlessly and automatically switching between different control modes without manual intervention. The integration of different wireless communication protocols over a compact, low-cost robotic platform.
- Obstacle detection mechanism based on an ultrasonic sensor operational throughout all the control modes. This is aimed at the design and development of modular and extensible robot architecture for assistive, educational, surveillance, and automation tasks.

## II. LITERATURE REVIEW

Owing to the flexibility and ease with which they are implemented, wireless control mechanisms for mobile robotic systems have become popular topics in the literature. In this regard, Bluetooth-based robotic control systems have already been shown suitable for low-power, short-range applications; however, it has also been reported that besides the restricted operating range, the key drawbacks include signal instability [1]. Human-robot interaction studies developed so far suggest that, for real-world deployment of a robotic system, its control interface should ideally be intuitive and user-friendly, especially because environmental and usability constraints play a vital role in such processes [2]. To address these challenges, multi-modal robotic control systems based on various input techniques have been proposed. Gesture-based robotic control has gained considerable attention due to its natural and interactive mode of navigating motions [3]. Studies using motion sensors like the MPU6050 have demonstrated effective recognition of hand gestures for directional control of robotic vehicles [4]. Real-time interpretation of the tilt angles of the hand using accelerometer and gyroscope data has been shown to improve responsiveness and control accuracy [5]. Comparative analyses between gesture-based autonomous and hybrid systems show that multi-modal approaches offer greater flexibility and improved user interaction [6].

The robotic system of voice control has been extensively investigated for hands-free operations, especially in the applications of assistive mobility. Various voice command-based navigations were possible using smartphone applications and Bluetooth communications [7]. With higher-order improvements in speech recognition algorithms, voice-controlled robotic systems are becoming more feasible for practical applications because of their higher command accuracy and system reliability [8]. On the other hand, voice-based control alone may show performance degradation in noisy environments, thus necessitating alternative or complementary control modes. In order to eliminate the range limitations linked with the Bluetooth-based systems, some researchers focused on investigating the integration of RF communication modules. Consequently, some studies highlighted that the integration of Bluetooth and RF communications improves the operational range and the communication reliability [9]. To enhance the navigation stability and overall performance of the systems, the adaptive hybrid control systems that can switch dynamically between different control modes have been proposed [10]. Moreover, the optimization of filtering techniques and the application of sensor error compensation methods to the inertial measurement units provided an improved accuracy in recognizing gestures [11].

RF-based multi-modal robotics systems provide high reliability and faster response times, especially in open and long-distance environments [12]. Low-power RF transceivers like the nRF24L01 module have been singled out as efficient solutions for energy-efficient long-range wireless communication in mobile robotics [13]. Motor driver modules like the L298N are widely used in order to provide stable current control and reliable bidirectional motor operation in robotic platforms [14]. Recent survey studies indicate a growing trend toward integrating multiple control modalities, including Bluetooth, voice, gesture, and sensor-based safety mechanisms, to enhance robustness, user comfort, and system intelligence [15]. Modular and dynamically adaptable robotic architectures have been emphasized as essential for supporting multi-modal interaction in practical applications [16]. Moreover, natural and flexible user interfaces are reviewed as key success factors in human-robot interaction within dynamic operational environments [17]. Sensor-based safety systems, especially ultrasonic sensing, have been widely adopted for short-range obstacle detection and collision avoidance [18]. While these efforts constitute important progress, most existing systems focus on individual control modes or lack seamless integration of multiple control techniques within a unified platform. This work addresses these limitations by presenting a unified multi-modal robotic control system that integrates Bluetooth, voice, and gesture-based control with consistent safety enforcement.

### III. METHODOLOGY

In the proposed system, the method employed emphasizes building an autonomous robotic car that can be controlled by three different techniques: manual control using Bluetooth technology, voice commands, and gesture control technology. In this system, control signals are processed by an Arduino Uno microcontroller, which acts as the main CPU in the system by interpreting commands and making necessary decisions regarding motor movement. In manually and voice-controlled systems, an Android smartphone is used, while gesture recognition is done using an MPU6050 gyroscope and accelerometer module, and wireless transmission is done using nRF24L01 radio modules. It constantly observes all the input channels and performs the first valid command that enables automatic switching and increases the flexibility of operation. Furthermore, the ultrasonic sensor is implemented on the receiver side for real-time obstacle detection and safe operation for all control methods. The workflow of the proposed system is shown below in Figure 3.

- 1) **Receiver-Side System Architecture:** The design of the receiver-side system architecture will incorporate components mounted on the robotic vehicle to receive control commands and perform motion. This will include an Arduino Uno microcontroller board, an HC-05 Bluetooth module, an nRF24L01 RF receiver, an ultrasonic sensor, an L298N motor driver, DC motors, and a rechargeable battery. The hardware architecture for the receiver-side system will appear as Fig. 1. In the figure according to transmitter or app command the L298 get PWM signals.
- 2) **System Power Initialization:** In this system, a 12 V rechargeable battery is utilized as the major source of power. This battery powers the Arduino Uno board, which is responsible for controlling the specified voltage levels in all the modules connected to the system. When the system is turned on, the microcontroller begins processing by initializing the serial communication, sensor calibration, motor driver setup, and system standby state configuration.
- 3) **Bluetooth Connectivity Establishment:** The HC-05 Bluetooth module is capable of communicating with the Android smartphone by utilizing the UART communication process at a baud rate of 9600. The control commands are sent to the Android smartphone, which in turn sends them to the robot by utilizing predefined characters such as F to move forward, B to move backward, L to move to the left, R to move to the right, and S to stop.
- 4) **Voice Command Control:** The voice command control system is implemented by making use of the built-in voice recognition system that is present in a smartphone. This system translates voice commands into text and sends them to the robotic car through a HC-05 Bluetooth module. The system is alternatively used when one wants to control the car while his or her hands are occupied. The system works properly when used in a noise-free environment.
- 5) **Gesture-Based Transmitter Unit:** The gesture-controlled subsystem includes a distinct transmitter component where the hand movement data is processed and transmitted wirelessly to the robotic vehicle for the execution of control commands. The hardware components for the transmitter are depicted in Fig. 2 below.
- 6) **Gesture Sensor Calibration & Processing:** The MPU6050 sensor has a three-axis accelerometer and a three-axis gyroscope, which detects hand motion and direction. The accelerometer senses linear acceleration, while the gyroscope is measuring the angular velocity. The data from the sensors is interpreted by the Arduino, and tilt angles are calculated, resulting in the predefined commands necessary for the movement of a road vehicle.
- 7) **Wireless Gesture Transmission:** The processed gesture commands are transmitted from the transmitter unit to the robotic vehicle through nRF24L01 wireless transceiver modules. The wireless communication method of gesture control is superior to the Bluetooth communication method because of enhanced robustness and range of wireless gesture control.
- 8) **Command Interpretation by Arduino:** This is because the Arduino is constantly monitoring all incoming commands coming from the Bluetooth manual control system, Bluetooth voice commands, and RF-based gesture commands. This is because as soon as it receives the first command, it acts on it without delay.
- 9) **Obstacle Detection and Safety Control:** In this process, an ultrasonic sensor is connected to the Arduino to measure the distance continuously between the robotic car and the nearby obstacle. If any obstacle comes within a fixed threshold distance range, the Arduino will override the control signal.
- 10) **The ultrasonic sensor calculates distance using the time-of-flight principle:** and send a stop signal to the motor driver.
- 11) **Motor Control and Motor Action:** The command for control of movement and direction and speed of the command as well will be sent to the L298N motor driver module from the Arduino board to control the DC motors accordingly. As soon as the stop command is produced, the motor operation ceases.
- 12) **Continuous Operation Loop:** The robotic car, after the execution of a command, keeps moving in the desired direction until another command is sent. When in gesture command mode, the car keeps moving if the user holds the respective hand position, thus allowing real-time control. When using the Bluetooth or voice command mode, it moves until a command for stop or change in

direction is given

- 13) Mode Switching Flexibility: The Arduino is constantly observing all the control channels and switching automatically to the last valid input. For example, if the project is running in the Gesture mode and there is an input from the Bluetooth, the project immediately switches to the Bluetooth mode. Such an aspect creates an easy and friendly interface for the users.
- 14) System Shutdown: Upon receipt of the shutdown signal or when the battery voltage becomes unsafe, the machine turns off all motor function and keeps non-essential subsystems from operating. Meanwhile, this shutdown process prevents the possibility of machine overheating and battery cell damage by any unexpected mechanical movement of the machine.

#### A. Mathematical Modelling

- 1) To analytically describe the behavior of the proposed multi-modal robotic system, mathematical models for motion control, sensing, gesture interpretation, and system delay are formulated below.

##### Differential Drive Motion Model

The robotic vehicle is based on a differential drive mechanism with two independently driven wheels.

Let:

- $V_L$  = Left wheel velocity
- $V_R$  = Right wheel velocity
- $L$  = Distance between wheels
- $\theta$  = Orientation angle
- $(x, y)$  = Robot position

The linear velocity of the robot is:

$$V = \frac{V_R + V_L}{2} \quad (1)$$

The angular velocity is:

$$\omega = \frac{V_R - V_L}{L} \quad (2)$$

The position of the robot in a 2D plane is governed by:

$$\frac{dx}{dt} = V \cos \theta \quad (3)$$

$$\frac{dy}{dt} = V \sin \theta \quad (4)$$

$$\frac{d\theta}{dt} = \omega \quad (5)$$

These equations define the trajectory and orientation of the robotic vehicle.

##### 2) Ultrasonic Obstacle Detection Model

The ultrasonic sensor calculates distance using the time-of-flight principle:

$$D = \frac{v \cdot t}{2} \quad (6)$$

Where:

- $D$  = Distance to obstacle
- $v$  = Speed of sound (343 m/s)
- $t$  = Echo return time

For collision avoidance:

$$\text{If } D > D_{th} \text{ Motor Output} = 0 \quad (7)$$

This overrides all control commands and ensures safety.

##### 3) Gesture Angle Computation Model

The MPU6050 sensor provides acceleration values:

$a_x, a_y, a_z$

Tilt angles are calculated as:

$$\theta_x = \tan^{-1}\left(\frac{a_y}{a_z}\right) \quad (8)$$

$$\theta_y = \tan^{-1}\left(\frac{-a_x}{\sqrt{a_y^2 + a_z^2}}\right) \quad (9)$$

Gesture commands are generated based on threshold comparison:

- $\theta_x > \theta_{th} \rightarrow$  Forward
- $\theta_x < -\theta_{th} \rightarrow$  Backward
- $\theta_y > \theta_{th} \rightarrow$  Right
- $\theta_y < -\theta_{th} \rightarrow$  Left

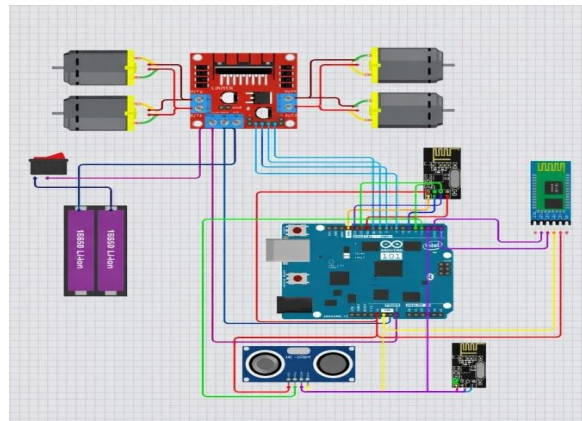


Fig. 1: Receiver-side hardware architecture of the robotic vehicle

Fig. 1. Is Hardware architecture and wiring diagram of the transmitter side of proposed multi-modal robotics system. The Arduino microcontroller is used for processing and control, handling data acquisition, decision-making, and actuator control. An L298N Dual H-Bridge motor driver is connected to Arduino for controlling four DC motors, making it possible for the robotic vehicle to move in both forward and reverse directions with varying speeds. For wireless communication with regard to manual control and voice control, an HC-05 Bluetooth module is connected to Arduino for transmitting control commands from a smartphone application. For control through hand gestures, another external MPU6050 unit of the accelerometer and gyroscope sensor is used, and control information is transferred to the robotic vehicle through nRF24L01 wireless RF modules. To improve safety and autonomous control, an ultrasonic sensor is placed on the vehicle to measure continuously the distance to objects around it, providing real-time feedback about collision avoidance by halting motor operations if objects are detected within a predetermined range. The entire system is capable of being continually supplied by a rechargeable battery pack, providing a robust and convenient means for sustained operation of the robotics system.

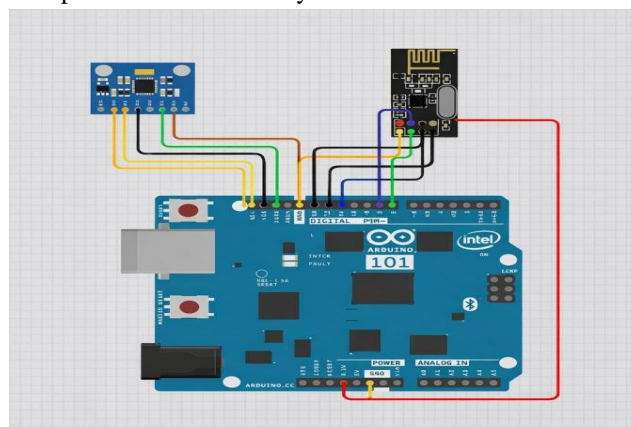


Fig. 2: Transmitter hardware architecture for gesture-based control

Fig. 2. Connection of the gesture control unit with the Arduino microcontroller. The Arduino microcontroller board serves as the main processing element and is coupled with an MPU6050 acceleration and gyro sensor, which uses the I<sup>2</sup>C communication interface to obtain real-time data about the motion and orientation of the human hand for gesture generation. The sensor is capable of detecting acceleration and rotation rates in three directions and sends these results to the microcontroller for processing into gesture commands for directional control of various robotic applications. The gesture control unit communicates with other components of the robotic vehicle wirelessly using an nRF24L01 wireless transceiver that is connected to the Arduino board using the SPI interface for efficient wireless data transfer. It is powered through the regulated supply. This setup constitutes the input control unit of the multi-modal robotic framework.

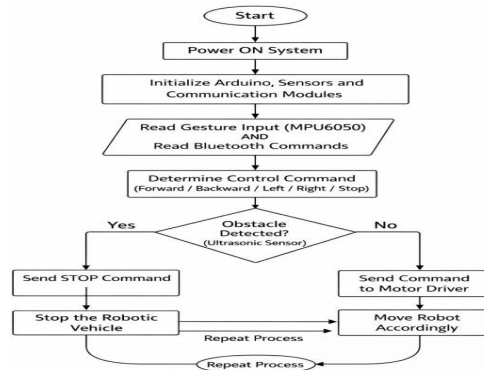


Fig.3: Overall workflow of the proposed multi-modal robotic control system

Fig.3. Flowchart of the operational logic of the designed multi-modal robotic system. The sequence starts from turning on and initializing power, followed by initialization of the Arduino microcontroller, sensors, and wireless communication modules. The system is designed for continuous reading of gesture commands from the MPU6050 sensor and reception of Bluetooth control commands from the user. On this basis, depending on analyzed inputs, the control unit generates a particular motion command, such as “forward,” “backward,” “left,” “right,” or “stop.” However, prior to executing a particular command, the ultrasonic sensor is used to check for any possible presence of an obstacle in the path of the vehicle. In both instances where an

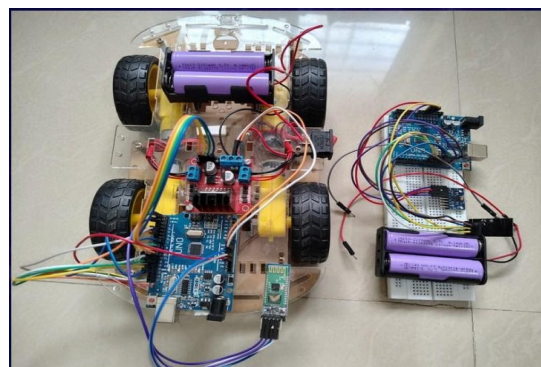


Fig.4: Actual prototype developed during the study

The hardware prototype for the multi-modal robotic vehicle is shown below in Figure 4. The vehicle is constructed using a differential drive system, propelled by DC motors, controlled by an L298N motor controller. The brain of the vehicle is an Arduino Uno controller, used for effective connection to other devices such as the Bluetooth module, used for voice control, the RF module, used for hand gesturing control, as well as an ultrasonic sensor for obstacle detection. The robot is driven by rechargeable batteries, hence an example of a miniaturized design used for multi-modal wireless control. usability. The designed multi-modal robotic vehicle is a reliable and economical solution for applications such as assistive mobility, surveillance, automation, and robotics education.

#### IV. RESULTS

The developed multi-modal robotic system was tested under indoor conditions to evaluate control accuracy, response time, communication range, and safety performance. The system operated successfully in all three control modes: Bluetooth, voice, and gesture.

Bluetooth control showed stable connectivity within approximately 10 meters and provided smooth directional movement with minimal delay. Voice control achieved high command recognition accuracy in low-noise environments, though slight performance reduction was observed under background noise. Gesture-based control allowed intuitive hand-driven navigation and demonstrated a larger communication range due to the RF module.

The ultrasonic sensor continuously monitored obstacle distance and successfully stopped the robot whenever an object entered the predefined safety range. This safety mechanism functioned effectively in all operating modes.

Overall, experimental observations confirm that the integrated multi-modal approach improves flexibility, usability, and operational reliability compared to single-moderobotic systems

Control Mode	Accuracy (%)	Delay (ms)	Range (m)	Safety	Obstacle Detection
Bluetooth Control	98	80–100	~10	Yes	Yes
Voice Control	92	150–200	~10	Yes	Yes
Gesture Control	90	120–160	~25	Yes	Yes

Table 1: Performance Comparison of Control Modes

The findings support that a combination of several control methods into one system enhances malleability and ease of use over traditional systems, which support a single mode.

#### V. CONCLUSION

In this section, experimental analysis and results of integrating the multi-modal robotic controlling system by using Bluetooth, Voice, and Gesture modes will be described. Figure 4 shows a practical prototype developed in this study. The robots were tested by means of a robotic car controlled by three different control methods.

In the control mode based on Bluetooth, the communication of the system is stable within a range of about 10m, with smooth and accurate control through a smartphone. Voice control had an average voice command recognition accuracy of around 92% in low-noise conditions, and the performance was slightly impacted by the presence of background noise. The system of control by gestures, developed using the MPU6050 sensor and an RF24L01 RF module, facilitated intuitive control by tilt motions of hands, though some in accuracies occurred during fast motion of the

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