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GSM BASED PNEUMATIC ARM CONTROL SYSTEM

1 NIJI KURIAKOSE, 2 ABHIJITH VINU, 3 ALAN BABY, 4 MOHAMMED NUFAIS

1 ASSISTANT PROFESSOR, 2 STUDENT, 3 STUDENT, 4 STUDENT

DEPARTMENT OF MECHATRONICS ENGINEERING

Nehru College of Engineering and Research Centre,Thrissur, India

Abstract: This project presents the design and development of a GSM-based pneumatic arm control system for remote operation in industrial and automation applications. The system uses GSM communication technology to control a pneumatic robotic arm from a remote location through SMS commands. A microcontroller processes the received commands and activates pneumatic actuators using solenoid valves to perform movements such as gripping, lifting, and rotating.The pneumatic arm provides fast and reliable motion using compressed air as the power source. The integration of GSM technology enables long-distance control without requiring internet connectivity. The system includes components such as a GSM module, microcontroller, relay driver circuit, solenoid valves, pneumatic cylinders, and air compressor.Experimental testing shows that the system responds quickly to SMS commands and performs accurate arm movements. The proposed system can be used in hazardous environments, industrial automation, and remote material handling applications. Future improvements may include camera integration, feedback sensors, and mobile application control for improved precision and monitoring.

***Index Terms* - Gsm communication,pneumatic robotic arm,muscle signal control,assistive robotics,ESP 32.**

I. INTRODUCTION

Automation plays an important role in modern industries by improving efficiency, safety, and productivity. Robotic arms are widely used in manufacturing, assembly lines, material handling, and hazardous environments where human intervention is difficult.A pneumatic robotic arm uses compressed air to produce mechanical motion through pneumatic cylinders and actuators. Compared to hydraulic systems, pneumatic systems are simpler, cheaper, and easier to maintain.The objective of this project is to design a GSM-based remote control pneumatic arm. GSM communication allows users to control the robotic arm by sending SMS commands from a mobile phone. The GSM module receives the message and sends it to the microcontroller, which then activates the required pneumatic actuators.The system integrates a GSM module with a microcontroller to receive SMS commands from a user and convert them into control signals for operating the robotic arm. Another objective is to utilize pneumatic actuators and solenoid valves to generate mechanical movement using compressed air, ensuring fast and reliable operation. The project also aims to develop a control mechanism that allows the arm to perform different movements such as gripping, lifting, and positioning of objects. In addition, the system is designed to be low-cost, simple, and efficient, using easily available electronic and pneumatic components. This project also focuses on improving safety by enabling remote operation in hazardous or hard-to-reach environments, where direct human intervention may be risky. Overall, the objective is to demonstrate the practical application of GSM communication, microcontroller programming, and pneumatic automation in the development of an efficient robotic control system.

THE OBJECTIVE OF THIS PROJECT :

- To design and develop a GSM based pneumatic robotic arm.
- Maintaining balance using sensor feedbackTo control the robotic arm remotely using SMS commands from a mobile phone.
- To interface a GSM module with a microcontroller for communication
- To operate pneumatic cylinders using solenoid valves for arm movement.
- To use the system in industrial and hazardous environments where human work is difficult.
- To perform actions like gripping, lifting, and placing objects using the arm.gently using camera-based vision

This project is divided into two major development phases:

- Phase 1 – Electronic Control System Development

This phase includes the design and implementation of the GSM module, microcontroller, and relay driver circuit used to receive SMS commands and control the system.

- Phase 2 – Pneumatic System Development This phase focuses on the design and assembly of the pneumatic components such as pneumatic cylinders, solenoid valves, air compressor, and the mechanical structure of the robotic arm for performing movements like gripping and lifting.

II. LITERATURE REVIEW

Several Many researchers have worked on the development of robotic arms and remote automation systems for industrial applications. Robotic arms are widely used in industries for tasks such as material handling, assembly, welding, and packaging. These systems help improve productivity, reduce human effort, and increase safety in hazardous environments.

Several studies have focused on pneumatic robotic arms, which use compressed air to generate mechanical motion. Pneumatic systems are preferred in many industrial applications because they are simple, reliable, and require less maintenance compared to hydraulic systems. Pneumatic actuators such as cylinders and solenoid valves are commonly used to control the movement of robotic arms.

Research has also been carried out on GSM-based control systems for automation. GSM technology allows devices to be controlled remotely using SMS commands sent from mobile phones. This technology has been used in various applications such as home automation, industrial monitoring, security systems, and remote machine control.

Microcontrollers like Arduino and ESP32 are widely used in automation projects because they provide easy programming, low cost, and efficient control of sensors and actuators. By integrating GSM modules with microcontrollers, researchers have developed systems that can receive commands and control different devices remotely.

Based on these studies, the integration of GSM communication with pneumatic robotic systems can provide an efficient solution for remote control applications in industries, especially in environments where direct human intervention is difficult or dangerous.

III. METHODOLOGY

The methodology of this project involves designing and developing a GSM-based pneumatic arm control system. First, the required components such as the GSM module, microcontroller, relay module, solenoid valves, pneumatic cylinders, and air compressor are selected. Next, the GSM module is connected to the microcontroller to receive SMS commands from a mobile phone. The microcontroller processes the received command and sends signals to the relay module. The relay then activates the solenoid valves, which control the airflow to the pneumatic cylinders. The pneumatic cylinders convert compressed air into mechanical motion and move the robotic arm to perform actions such as gripping and lifting objects. Finally, the system is tested to ensure proper response and smooth operation of the pneumatic arm.

Phase 1 – Electronic Control System Development

In Phase 1,

1. Selection of electronic components such as GSM module, microcontroller, relay module, and power supply.

2. Interfacing the GSM module with the microcontroller to receive SMS commands

3. Programming the microcontroller to read and process the received messages.

4. Generating control signals from the microcontroller to activate the relays based on the received commands.

This phase we established a GSM-based control system that allows a pneumatic robotic arm to be operated remotely using SMS commands through a microcontroller and pneumatic actuators.

Phase 2 –Pneumatic System Development

Phase 2 ,

1. Selection of pneumatic components such as pneumatic cylinders, solenoid valves, air compressor, and pneumatic tubes.
2. Designing and assembling the mechanical structure of the pneumatic robotic arm.
3. Connecting solenoid valves to the pneumatic cylinders to control the airflow.
4. Supplying compressed air from the air compressor to operate the cylinders.
5. Testing the pneumatic arm movements such as gripping, lifting, and placing objects.

V. System Architecture

1. User Input – The user sends control commands using a mobile phone through SMS.
2. GSM Communication – The GSM module receives the SMS command and transfers it to the microcontrollers.
3. Microcontroller Processing – The microcontroller reads and processes the received command..
4. Control Signal Generation

The microcontroller generates control signals based on the command..

5. Relay and Solenoid Control The relay module activates the solenoid valves to control airflow
6. Pneumatic Arm Movement – The pneumatic cylinders use compressed air to move the robotic arm and perform actions like gripping, lifting, and placing objects.

VI. Procedure

The procedure of this project explains the steps followed to design, assemble, and test the GSM-based pneumatic arm system. It includes the setup of electronic components, programming of the microcontroller, and assembly of the pneumatic mechanism. The GSM module is used to receive SMS commands from a mobile phone, which are processed by the microcontroller to control the relays and solenoid valves. These valves regulate the airflow to the pneumatic cylinders, allowing the robotic arm to perform movements such as gripping, lifting, and placing objects. Finally, the system is tested to ensure proper communication, accurate response, and smooth operation of the pneumatic arm

1. **Collect Required Components**
Gather all necessary components such as the GSM module, microcontroller (Arduino/ESP32), relay module, solenoid valves, pneumatic cylinders, air compressor, power supply, and connecting wires.

2. **Check Component Functionality**
Test each component individually to ensure that they are working properly before assembling the system.

3. **Connect GSM Module to Microcontroller**
Interface the GSM module with the microcontroller using TX and RX pins so that SMS commands can be received and processed.

4. **Connect Relay Module**
The relay module is connected to the digital output pins of the microcontroller to control the solenoid valves.

5. **Program the Microcontroller**
Write the control program using Arduino IDE and upload it to the microcontroller to read and process SMS commands.

6. **Insert SIM Card in GSM Module**
A SIM card is inserted into the GSM module to allow communication through the GSM network and receive messages from a mobile phone.

7. **Mount Pneumatic Cylinders**
Pneumatic cylinders are fixed to the robotic arm structure so that they can generate mechanical movement.

8. **Connect Solenoid Valves**
Solenoid valves are connected to the pneumatic cylinders through pneumatic tubes to control the airflow direction.

9. **Connect Air Compressor**
The air compressor supplies compressed air to the pneumatic system for operating the cylinders.

10. **Integrate Electronic and Pneumatic Systems**
The electronic control system and pneumatic mechanism are connected together to create a complete working system.

11. **Adjust Air Pressure**
The air pressure from the compressor is adjusted to ensure smooth and controlled movement of the pneumatic arm.

12. **Check for Air Leakage**
All pneumatic tubes and connections are inspected to ensure there is no leakage of compressed air.

13. **Send SMS Commands**
SMS commands are sent from a mobile phone to control the movements of the pneumatic arm.

14. **Observe Arm Movements**

The robotic arm movements such as gripping, lifting, and placing objects are observed to verify system operation.

15. **Perform Repeated Testing**

The system is tested multiple times to ensure reliability, accuracy, and stable performance of the GSM-based pneumatic arm.

Data Analysis

1. **SMS Command Transmission**

In this system, the user sends control commands in the form of SMS messages from a mobile phone. These messages are used to control different movements of the pneumatic arm remotely without direct physical interaction.

2. **GSM Signal Reception**

The GSM module installed in the system receives the SMS command through the cellular network. After receiving the message, it converts the data into a format that can be read by the microcontroller.

3. **Network Delay Observation**

During testing, a small delay was noticed between sending the SMS and receiving it in the GSM module. This delay mainly depends on the strength and availability of the GSM network signal.

4. **Message Processing**

Once the message is received, the microcontroller reads the data from the GSM module through serial communication. It then begins processing the command contained in the message.

5. **Command Interpretation**

The microcontroller analyzes the received command and determines which operation needs to be performed, such as gripping, lifting, or moving the pneumatic arm.

6. **Control Signal Generation**

After interpreting the command, the microcontroller generates electrical signals that are used to control other components in the system.

7. **Relay Activation**

These control signals activate the relay module. The relay works as an electronic switch that allows the system to control high-power components safely.

8. **Solenoid Valve Control**

The relays turn the solenoid valves ON or OFF. These valves control the flow of compressed air within the pneumatic system.

9. **Compressed Air Supply**

The air compressor supplies compressed air to the pneumatic system. This compressed air acts as the main power source for moving the cylinders.

10. **Air Flow Regulation**

Solenoid valves regulate the direction and amount of compressed air entering the pneumatic cylinders. This helps in controlling the movement of the robotic arm.

11. **Cylinder Actuation**

When compressed air enters the pneumatic cylinder, it pushes the piston inside the cylinder. This piston movement converts air pressure into mechanical motion.

12. **Robotic Arm Movement**

The mechanical motion produced by the pneumatic cylinders causes the robotic arm to move in different directions depending on the command received.

13. **Gripping Operation**

The arm can close its gripping mechanism using pneumatic force to hold objects securely during the operation.

14. **Lifting Operation**

The pneumatic system allows the robotic arm to lift objects by extending or retracting the cylinders.

15. **Placing Operation**

After lifting the object, the arm moves to the desired location and releases the object carefully.

16. **Air Pressure Monitoring**

Proper air pressure must be maintained for smooth functioning of the pneumatic cylinders. Too low pressure may reduce movement efficiency.

17. **System Stability Observation**

The mechanical stability of the arm is observed during operation to ensure that there is no unwanted vibration or imbalance.

18. **Repeated Testing**

The system is operated multiple times with different commands to check whether it performs consistently under repeated usage.

19. **Performance Evaluation**

Key performance parameters such as response time, movement accuracy, and communication reliability are evaluated during testing.

20. **Overall System Analysis**

Based on the test results, the GSM-based pneumatic arm system demonstrates reliable remote control, effective pneumatic actuation, and suitable performance for automation and industrial applications.

Environmental Feedback

1. **Low Environmental Pollution**

The pneumatic arm operates using compressed air, which does not produce harmful gases or chemical waste. This makes the system environmentally friendly compared to systems that use oil or fuel.

2. **Energy Efficient Operation**

The electronic components such as the microcontroller, GSM module, and relay circuits consume low electrical power, helping to reduce overall energy consumption.

3. **No Oil Leakage Issues**

Unlike hydraulic systems that use oil, the pneumatic system uses air as the working medium. This avoids the risk of oil leakage that can contaminate soil or water.

4. **Remote Operation Reduces Human Risk**

Since the system can be controlled remotely through GSM communication, it reduces the need for human presence in hazardous or polluted environments.

5. **Reusable and Sustainable Components**

Most of the components used in the system such as electronic modules and mechanical parts can be reused or recycled, reducing environmental waste.

Final Evaluation

The GSM-based pneumatic arm system was successfully designed and implemented for remote control operations. The system demonstrated reliable communication, smooth pneumatic movement, and stable performance during testing. Overall, the project proves that GSM communication combined with pneumatic automation can be effectively used for remote industrial applications.

VII. Results

The **GSM-based pneumatic arm system** was successfully designed and implemented.

The system was able to **receive SMS commands through the GSM module** and process them using the microcontroller.

The **relay and solenoid valve mechanism** effectively controlled the pneumatic cylinders.

The pneumatic arm successfully performed **operations such as gripping, lifting, and placing objects**.
The overall system showed **reliable performance and effective remote control capability** for automation applications.

System and Components

1. GSM Module

- **Purpose:** Enables wireless communication via mobile network. Receives commands sent through SMS from a mobile phone.
- **Example:** SIM800/SIM900 GSM Module.
- **Function in system:** When a user sends an SMS command, the GSM module receives it and sends it to the microcontroller for processing.

2. **Microcontroller**

- **Purpose:** Acts as the “brain” of the system. Processes input commands and controls actuators.
- **Examples:** Arduino Uno, PIC16F877A, or STM32.
- **Function in system:** Interprets the SMS command from the GSM module and triggers pneumatic valves accordingly.

3. **Pneumatic Cylinders**

- **Purpose:** Convert compressed air into mechanical motion.
- **Types:** Single-acting or double-acting cylinders depending on movement needs.
- **Function in system:** Drives the movement of the robotic arm (lifting, rotating, gripping).

4. Solenoid Valves

- **Purpose:** Electrically controlled valves that regulate airflow to the pneumatic cylinders.
- **Function in system:** Opens or closes based on signals from the microcontroller to control cylinder motion.

5. Air Compressor

- **Purpose:** Supplies compressed air needed for pneumatic operation.

- **Function in system:** Provides the necessary air pressure to the cylinders for arm movement.

6. Power Supply

- **Purpose:** Provides electrical energy to all electronic components in the system.

Function in system:

- Powers the **microcontroller** (usually 5V DC).
- Powers the **GSM module** (usually 5–12V DC depending on the module).
- Powers the **solenoid valves** (usually 12V DC).

conclusion

The GSM-based Pneumatic Arm System successfully integrates wireless communication with pneumatic automation, allowing remote control of the robotic arm through simple SMS commands. By combining a GSM module, microcontroller, solenoid valves, and pneumatic cylinders, the system demonstrates precise, reliable, and efficient mechanical movement. This project highlights the practical application of IoT and automation in robotics, offering a foundation for future enhancements such as sensor feedback, automation sequences, and industrial applications.

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