



UNDERGRADUATE THESIS

DESIGN AND CONSTRUCTION OF AN MULTIFUNCTIONAL EDUCATIONAL MOBILE ROBOT FOR STEM LEARNING BASED ON VISUAL PROGRAMMING USING ESP32

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SURABAYA
2026**

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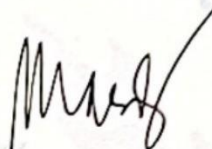
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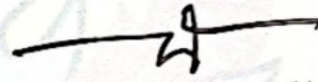

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STATEMENT OF ORIGINALITY

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Hereby declares that this undergraduate thesis contains no part of any other scientific work that has been submitted to obtain an academic degree at any higher education institution. Furthermore, it does not contain any work or opinions previously written or published by others, except for those which are explicitly cited in this thesis and listed completely in references.

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ABSTRACT

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STEM-based learning (Science, Technology, Engineering, and Mathematics) requires interactive and applicable media to enhance 21st-century skills such as critical thinking, creativity, and problem solving. However, currently available STEM learning media are still lacking in interactivity, the price of commercial robotics platforms is relatively expensive, and the use of text-based programming languages poses a barrier for students who do not yet have a programming background. This research aims to design and build a multifunctional educational mobile robot based on the ESP32 microcontroller by applying the Finite State Machine (FSM) method as a decision-making mechanism for each operating mode, as well as implementing Scratch/PictoBlox-based visual programming. The research method used is Research and Development (R&D) with the Prototyping Model as the product development framework and the V-Model as the system verification and validation framework. A Moore Machine type FSM was applied to model the robot's behavior across three operating modes, namely line follower (4 states), obstacle avoidance (4 states), and smartphone control (9 states). The test results show that the HC-SR04 ultrasonic sensor has an average error of 1.48%, the TCRT5000 line sensor achieves a detection success rate of 96.7%, and Bluetooth communication remains stable up to a distance of 8 meters. The line follower and obstacle avoidance modes each achieved a 90% success rate with 90% FSM conformity, while the smartphone control mode achieved 100% with a response time under 100 ms. The application of FSM successfully modeled the robot's behavior in a structured, deterministic, and well-documented manner, and could be translated directly into PictoBlox visual programming blocks. Thus, this robot is effective as an interactive, flexible STEM learning medium that is easy to use across various levels of education.

Keywords: ESP32, Finite State Machine, Mobile Robot, PictoBlox, Visual Programming, STEM.

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Surabaya, June 26 2026

Mochamad Farid Fadhlulloh

TABLE OF CONTENTS

TITLE PAGE SHEET	i
APPROVAL SHEET	ii
STATEMENT OF ORIGINALITY	iv
ABSTRACT	v
ACKNOWLEDGEMENT	vi
TABLE OF CONTENTS.....	viii
LIST OF FIGURE	xi
LIST OF TABLE	xii
CHAPTER I INTRODUCTION.....	1
1.1 Background	1
1.2 Problem Statement	4
1.3 Research Objectives	5
1.4 Research Benefits	5
1.5 Scope and Limitations	6
CHAPTER II LITERATUR REVIEW.....	8
2.1 Previous Studies	8
2.2 ESP32 Microcontroller	10
2.2.1 ESP32 Power Requirements	11
2.3 Push Button Switch	13
2.4 HC-SR04 Ultrasonic Sensor Module	14
2.5 Line Sensor.....	17
2.6 DC Motor	18
2.6.1 Working Principle.....	19
2.6.2 Advantages of DC Motors	19
2.6.3 Disadvantages of DC Motors.....	20
2.7 DC Motor Driver	20
2.7.1 Features and Specifications of the L293D	20
2.7.2 Working Principle.....	21
2.8 Mecanum Wheel.....	21
2.9 PictoBlox Software.....	22

2.10 Finite State Machine.....	25
2.11 Dabble Application.....	27
2.11.1 Gamepad Mobile.....	27
CHAPTER III METHODOLOGY	31
3.1 Research Stages	31
3.2 Analysis	32
3.2.1 Problem Analysis	33
3.2.2 Solution Analysis.....	33
3.2.3 Requirements Analysis	34
3.3 System Design.....	36
3.3.1 Robot Concept Design	36
3.3.2 Hardware Design	37
3.3.3 Control System Design (ESP32 and L293D)	42
3.3.4 Sensor and Actuator Integration	43
3.3.5 Finite State Machine (FSM) Method Design.....	43
3.4 Software Implementation	50
3.4.1 DC Motor Control Implementation	50
3.4.2 Obstacle Avoidance Robot Implementation	53
3.4.3 Line Follower Robot Implementation.....	58
3.4.4 Robot Control Implementation with Dabble	60
CHAPTER IV RESULT AND DISCUSSION.....	67
4.1 Testing Method.....	67
4.1.1 Ultrasonic Sensor Testing.....	67
4.1.2 Line Sensor Testing (Line Follower).....	68
4.1.3 Bluetooth Communication Testing.....	69
4.1.4 Line Follower Mode Testing	69
4.1.5 Obstacle Avoidance Mode Testing.....	70
4.1.6 Smartphone Control Mode Testing.....	70
4.2 Testing Results	71
4.2.1 Ultrasonic Sensor Testing Results	71
4.2.2 Line Sensor Testing Results	71
4.2.3 Bluetooth Testing Results.....	72

4.2.4 Line Follower Mode Testing Results.....	73
4.2.5 Obstacle Avoidance Mode Testing Results	74
4.2.6 Smartphone Control Mode Testing Results.....	75
4.3 Analysis	76
4.3.1 Unit Testing Analysis (Hardware).....	77
4.3.2 Integration Testing Analysis (Operation Modes and FSM).....	77
4.3.3 Analysis of Finite State Machine (FSM) Implementation.....	77
4.3.4 Overall System Testing Analysis.....	78
CHAPTER V CONCLUSIONS AND RECOMMENDATIONS	79
5.1 Conclusions.....	79
5.2 Recommendations	80
BIBLIOGRAPHY	82

LIST OF FIGURE

Figure 2. 1 ESP32 Internal Block Diagram	11
Figure 2. 2 ESP32 DevKit Pinout	12
Figure 2. 3 Push Button Switch	14
Figure 2. 4 HC-SR04 Ultrasonic Module	14
Figure 2. 5 Transmitting a Burst Signal	15
Figure 2. 6 Burst Signal Reflection.....	15
Figure 2. 7 Distance Formula.....	16
Figure 2. 8 Line Sensor	18
Figure 2. 9 DC Motor.....	19
Figure 2. 10 L293D DC Motor Driver IC	20
Figure 2. 11 Mecanum Wheel.....	22
Figure 2. 12 PictoBlox Software Environment.....	24
Figure 2. 13 Gamepad Digital Mode.....	28
Figure 2. 14 Gamepad Joystick Mode.....	29
Figure 3. 1 Research Stages	31
Figure 3. 2 Block Diagram of the Multifunctional Educational Mobile Robot....	37
Figure 3. 3 Multifunctional Robot Circuit	41
Figure 3. 4 Robot Mechanical Design	41
Figure 3. 5 Multifunctional Robot Circuit Schematic.....	42
Figure 3. 6 Line Follower Mode FSM State Diagram	44
Figure 3. 7 Obstacle Avoidance Mode FSM State Diagram.....	46
Figure 3. 8 Smartphone Control Mode FSM State Diagram	48
Figure 3. 9 Scratch Visual Coding for Testing Robot Movement	52
Figure 3. 10 Scratch Visual Coding for Obstacle Avoidance Robot	55
Figure 3. 11 Scratch Visual Coding for Line Follower Robot.....	60
Figure 3. 12 Scratch Visual Coding for Robot Controlled Through the Dabble Application.....	66

LIST OF TABLE

Table 2. 1 L293D Chip Pin Functions	21
Table 3. 1 Hardware Requirements Analysis.....	36
Table 3. 2 Software Requirements Analysis	36
Table 3. 3 Main Electronic Components of the Robot	38
Table 3. 4 Pin Connections Between ESP32 and Motor Driver	39
Table 3. 5 Line Follower Mode FSM State Transitions	45
Table 3. 6 Obstacle Avoidance Mode FSM State Transition Table	47
Table 3. 7 Smartphone Control Mode FSM State Transition Table	49
Table 4. 1 Ultrasonic Sensor Testing Results	71
Table 4. 2 Line Sensor Testing Results.....	72
Table 4. 3 ESP32 Bluetooth Testing Results	72
Table 4. 4 Line Follower Testing Results	73
Table 4. 5 Obstacle Avoidance Testing Results	74
Table 4. 6 Smartphone Control Testing Results	76