

WALL CLIMBING ROBOT (CAR)

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College : *S G Balekundri Institute of Technology, Belagavi*

Branch : *Department of Mechanical Engineering*

Guide(s) : *Prof. S A Alur*

Student(S) : *Mr. Pranav Kakade*

Mr. Umesh B Padatari

Mr. Vinayak Soragavi

Mr. Vishwanath R Patil

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Introduction:

Wall climbing robots (car) are versatile machine that can be utilized in an assortment of utilizations like security inviolability devices, washing supplies, review and support of ground of ocean watercraft; oil container, goblet pieces of tall structure construction and so forth. To safeguard personage wellbeing and security in unsafe undertakings to create the wall climbing robot a valuable gadget. Specialists have created different wall climbing robot (car) models. Sticking and motion components are the two fundamental components of wall climbing machine (car). Every bond or headway component has its own assets and shortcomings. Attachment system can create strain to get the robot on walls.

Headway instrument decides the movement capacity of the robot. The ongoing movement instruments of the wall climbing robot can chiefly be classified into crawler, haggled type. In the robot planned, we are utilizing the strategy of vacuum bond and wheel movement. Vacuum grip or negative tension bond, is generally utilized in wall climbing robots, as it has a few famous benefits, for example, state forward construction, broadly useful grip to different sorts of surfaces, which in corporate day to day existence wall and surfaces. Wheeled robots typically have straight forward mechanical construction and need simple control.

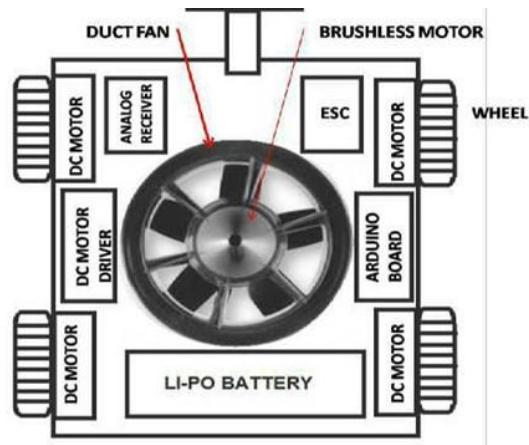
Objectives:

1. To protect human health and safety in hazardous tasks make the wall climbing robot a useful device.
2. Security and contour terrorist for intelligence gathering about hostile situation within a building.
3. In the warfare used for weapon delivery and guiding around the building.
4. It takes a part of assistance in firefighting.

Methodology:

There are three points involved in making of wall climbing robot: equipment configuration, control and arranging. A significant measure of work should be finished in every of these areas to foster a genuine climbing robot.

The segment beneath portrays the difficulties engaged with these areas, Hardware Design, Control, Force Involved, Planning, Planning Challenge, Planning Framework, Planning Implementation.



Robot Design

Conclusion:

1. In this paper, a propeller wall-climbing robot that can stably adsorb on a variety of different walls is designed. By analyzing the robot's movement from the ground to the wall and the robot's stable adsorption conditions on the wall, a propeller-type wall mobile robot is produced.
2. The robot climbing experiment under a small slope and the 90° slope stable adsorption experiment verified the feasibility of the robot moving stably on the vertical wall.
3. Future work should aim to optimize the robot structure model, manufacture a front wheel drive with a rotatable prototype for the front and rear wheel fixed brackets, carry out experimental research on the robot's forward, backward, and turn tests in a real terrain environment, and add ranging and sensors to sense the robot's position and posture.
4. By adjusting and correcting the robot posture, further steps can be taken to obtain the appropriate robot motion state and lay the theoretical and experimental accumulation for realizing the smooth transition from the ground to the wall of the robot

Scope for future work:

1. Wall-climbing robot with the vacuum adsorption system and adhesive belts has been proposed for some smooth wall surfaces.
2. Moreover, kinematic and dynamic models are set up to analyze the motion characteristics of the robot and the motor torque, respectively, and also provide a theoretical basis for the optimization of the control strategy.
3. Furthermore, the prototype of the wall-climbing robot has been manufactured, whose climbing abilities have been tested on various wall surfaces.
4. In the future, we need to further investigate the attachment mechanisms adapting to multiple walls as far as possible and develop novel composite materials of the skirt edge for suction cup and adhesive belts.