

PROJECT REPORT TITLED

“SIX LEGGED WALKING ROBOT FOR DISABLED PEOPLE”

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ABSTRACT

Traditionally robots have been created which utilize wheels for locomotion; the humble wheel can provide fast and simple locomotion which can be easily setup and controlled. However in many real world situations where a robot may be required on uneven terrain, for example in earthquake disaster zones, the wheel fails to provide effective locomotion due to the limitation of vertical motion. It is for this reason that engineers have long sought to create effective robotic locomotion utilizing legs. A walking robot would be more desirable when assisting human beings with dangerous works such as operation of radioactive materials in a nuclear plant, rescuing victims in an earthquake disaster, dealing with a bomb, and helping disabled human. For locomotion on rugged grounds, leg systems are superior to wheel systems or track systems, because leg systems have discrete contact points to the land, which can be chosen intentionally.