

See discussions, stats, and author profiles for this publication at: <https://www.researchgate.net/publication/269695712>

# Towards Fully Automated Tunnel Inspection: A Survey and Future Trends

Conference Paper · July 2014

DOI: 10.22260/ISARC2014/0005

CITATIONS

42

READS

2,385

5 authors, including:



**Roberto Montero**

University Carlos III de Madrid

7 PUBLICATIONS 428 CITATIONS

[SEE PROFILE](#)



**Juan G. Victores**

University Carlos III de Madrid

94 PUBLICATIONS 897 CITATIONS

[SEE PROFILE](#)



**Santiago Martinez**

University Carlos III de Madrid

82 PUBLICATIONS 873 CITATIONS

[SEE PROFILE](#)



**Alberto JARDÓN HUETE**

University Carlos III de Madrid

139 PUBLICATIONS 1,724 CITATIONS

[SEE PROFILE](#)

Some of the authors of this publication are also working on these related projects:



Robot Sign Language [View project](#)



Special Issue "Robotics and Advanced Technology for Tele-Rehabilitation" [View project](#)

# **Towards Fully Automated Tunnel Inspection: A Survey and Future Trends**

**C. Balaguer, R. Montero, J. G. Victores,  
S. Martínez, A. Jardón**

RoboticsLab, University Carlos III of Madrid, Spain

E-mail: balaguer@ing.uc3m.es, romonter@pa.uc3m.es,  
jcgvicto@ing.uc3m.es, scasa@ing.uc3m.es, ajardon@ing.uc3m.es

## **Abstract –**

Tunnels environments are characterized by dust, humidity, and absence of natural light. Artificial and natural impacts, change in load criteria, or the simple effect of ageing, make tunnels require inspection and maintenance. These operations are commonly performed by human workers taking time and expertise without guarantee quality control. Robotic tunnel inspection and maintenance (RTIM) introduces high productivity, quality and repetitiveness. This paper describes the current trends in the subject, and introduces new technologies such as scenario modeling, robotic platforms, image and ultrasound sensors, control algorithms and decision making strategies. Additionally, the result of several recent and ongoing projects will be presented.

## **Keywords -**

Robotics, Automation, Inspection, Maintenance, Tunnels, IAARC

## **1 Introduction**

One of the greatest challenges engineers face is the inspection, assessment, maintenance and safe operation of the existing civil infrastructure. This includes large-scale constructs such as tunnels, bridges, roads and pipelines. In the case of tunnels (water supply, metro, railway, road, etc.), they have increased in both total length and number, and will continue to do so. Furthermore, some tunnels still in service were completed over 50 years ago, with the existing construction and materials technology.

Only in Japan in 2006, the number of active tunnels was up to 9000 [1], with tunnels such as the Seikan Tunnel which is 54 km long and partially below the seabed [2]. Figure 1 shows the evolution of Japanese

tunnels in terms of number and length until 2006.

Tunnels progressively deteriorate due to ageing, environmental factors, increased loading, change in use, damages caused by human/natural factors, inadequate or poor maintenance, and deferred repairs. Unfortunately, several incidents related to the structural condition of tunnels have taken place, such as the Big Dig ceiling collapse in 2006 in Boston [3], or the Sasago Tunnel collapse in 2012 in Tokyo [4].

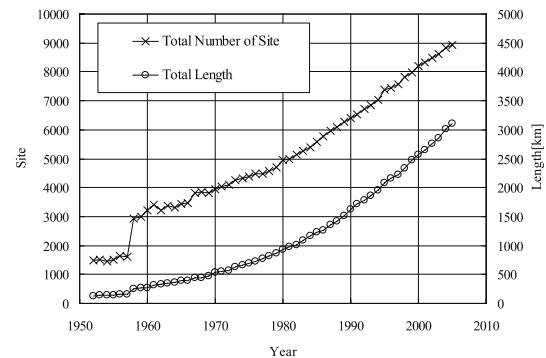


Figure 1. Changes in the number and total length of road tunnels in Japan (2006) [1]

These examples highlight the need of automated, cost-effective and exhaustive inspection of tunnels that prevents such disasters. In this work, we present current tendencies and future trends within this area.

## **1.1 Tunnel Defects**

The first aspect of inspection that must be defined is the related to the types of defects that may affect tunnels. Identifying these defects is crucial for performing a successful inspection, verifying the state of a tunnel, and performing maintenance if required.

The following list of common defects in tunnels is based upon the *TOMIE Manual* [5], created by the Federal Highway Administration (FHWA).

- Concrete structures: scaling, cracking (traverse, longitudinal, horizontal, vertical, diagonal, pattern, d-cracks, random), spalling, joint spall, pop-outs, efflorescence, staining, delamination, honey-comb, leakage
- Steel structures: corrosion, cracks, buckles and kinks, leakage, protective layer fail
- Masonry structures: masonry units (displaced, cracked, broken, crushed, or missing), mortar, shape, alignment, leakage
- Timber structures: decay, insects, checks/splits, fire damage, hollow area, leakage

The walls of most tunnels are made of concrete, though these walls may contain finishes such as ceramic tiles or metal panels. In most cases, the typical defects found in a tunnel are cracks, spalling and efflorescence/leakage [6]. Examples of this type of defects are displayed in Figure 2. If the walls are covered by a finish, the condition of such walls is generally defined by the deficiencies of the finish on the wall surface. An analysis of the causes of these common defects in tunnels can be found in the work by C. C. Xia et al. [7].



Figure 2. Examples of spalling (left) and crack with efflorescence (right) [5]

## 1.2 Tunnel Inspection Methods

The purpose of inspection is to check if a structure that has been functional for years is still safe or not. Furthermore, it is desirable to do this without creating any negative effect on the structure or component, and this is why the non-destructive inspection (NDI) methods [5][8] are far more commonly used than destructive methods. As said before, the most common structural material in tunnels is concrete, thus the following inspection processes are usually applied to concrete tunnels. NDI methods in structures can be

divided in visual, strength-based, sonic and ultrasonic, magnetic, electrical, thermography, radar, radiography, and endoscopy methods.

### 1.2.1 Visual Methods

Visual testing is probably the most important of all non-destructive tests. It can often provide valuable information to the well trained eye. Visual features may be related to workmanship, structural serviceability, and material deterioration, and it is particularly important for the engineer to be able to differentiate between the various signs of distress which may be encountered. Information can be gathered from visual inspection to give a preliminary indication of the condition of a structure and allow the formulation of a subsequent testing program.

### 1.2.2 Strength Based Methods

Rebound and penetration tests measure the surface hardness of materials and provides an estimation of surface compressive strength, uniformity and quality of the structure. Examples include the Schmidt Hammer [8][9] (rebound), the Windsor Probe [8][10] (penetrating), Flat Jack Testing [11][12] (applied to masonry), or methods without contact [13].

### 1.2.3 Sonic and Ultrasonic Methods

In sonic methods, also known as impact-echo tests, hammer blows create impulses, and the time of travel of these sonic pulses is measured with pickups placed on the wall [14][15][16], as can be seen in Figure 3. The time of travel is related to the modulus of elasticity and, hence, the strength. Sometimes chain drags, sounding rods or standard hammers are used for detecting delamination on horizontal surfaces if the inspector has experience in detecting hollow sounds.



Figure 3. Inspection using an impact hammer [17]

Ultrasonic devices are normally used by measuring the velocity in the material of a pulse generated by a piezoelectric transducer [18][19][20]. The pulse velocity depends on the composition and maturity of the structural material and its elastic properties. The relationship to strength depends on several other properties and is best determined experimentally [21].

#### **1.2.4 Magnetic Methods**

Magnetic methods are used to determine the position of reinforcements and are not techniques for detecting defects or deterioration directly, but the fact that inadequate cover is often associated with corrosion-induced deterioration indicates that a method for locating the reinforcing bars can be important in corrosion control. Examples of these methods are the Magnetic Flux Leakage method [22][23] or the Magnetic Field Disturbance method [5].

#### **1.2.5 Electrical Methods**

Electrical methods for inspection of tunnel components include resistance and potential measurements [24][25][26][27]. Electrical resistance has been used for measuring the permeability of deck seal coats and involves measuring the resistance between the reinforcing steel and surface, while electrical potential differences are caused by corrosion of reinforcement.

#### **1.2.6 Thermography Methods**

Infrared thermography measures the thermal radiation emitted by the tunnel's walls. Infrared registration techniques allow visual presentation of the temperature distribution on the surface [28][29][30]. The temperature on the surface represents the thermal flow through the surface, which in turn is influenced by the mechanical and/or hydraulic discontinuities of the structure. Consequently, thermal discontinuities on a surface reflects abnormalities within the underlying structure.

#### **1.2.7 Radar Methods**

Radar methods have been widely used to detect defects in tunnels and other structures, and the most used is the Ground-Penetrating Radar (GPR) [31][32][33][34]. GPR is the electromagnetic analogue of sonic and ultrasonic pulse echo methods. It is based on the propagation of electromagnetic energy through materials of different dielectric constants. The greater the difference between dielectric constants at an

interface between two materials, the greater the amount of electromagnetic energy reflected at the interface.

#### **1.2.8 Radiography Methods**

X-rays, gamma radiation or neutron rays can penetrate structural materials and therefore can be used on inspection purposes [35][36][37]. The amount of radiation absorbed by the material is dependent upon the density and thickness. This radiation can be detected and recorded on either film or sensitized paper, viewed on a fluorescent screen, such as a television screen, or detected and monitored by electronic sensing equipment. With this method, limitations are imposed by accessibility to both sides of the object, long exposure times, and safety precautions required to protect both the operators and public.

#### **1.2.9 Endoscopy Methods**

Endoscopes or videoscopes consist of rigid or flexible viewing tubes that can be inserted into pre-drilled boreholes of an element under investigation to examine its condition [38][39]. Light can be provided by glass fibers from an external source. In the rigid tubes, viewing is provided through reflecting prisms and, in the flexible tubes, a fiber optics system is used. New models consist of an additional CCD chip to improve the images. These scopes allow close examination of parts of the structure which could not be otherwise viewed. Although this is a viewing instrument, some destruction of material is necessary for its proper use.

## **2 A Survey on Robotic Inspection**

Even with the great variety of inspection methods presented in Section 1, presently structural tunnel inspection is predominantly performed through scheduled, periodic, tunnel-wide visual observations by inspectors who identify structural defects and rate these defects. This process is slow, labor intensive and subjective (depending on the experience and fatigue of the inspector), working in an unpleasant environment due to dust, absence of natural light, uncomfortable conditions or even toxic substances such as lead and asbestos. These working conditions are a main motivation behind the development of robotic systems.

### **2.1 Robotic Tunnel Inspection Systems**

The use of robotics systems in the construction field

had been a common research area, and several studies review the advantages in the use of robotic platforms for construction [40][41] and underground construction [42] purposes. Robotic systems can complete the inspection process with objective results and high efficiency. They also improve safety by performing inspection in dangerous environments instead of the inspectors. Therefore, manual and (human) visual inspection are being replaced with more precise methods using mechanical, electronic and robotic systems and processing data provided by cameras, laser, sonar, etc.

In the case of the system in the Figure 4, a small mobile robot is equipped with a CCD camera [43][44][45]. The robot stays at a constant distance of the wall using a differential-drive wheel configuration, and a set of photos are taken. The camera is mounted on an anti-vibration device to stabilize the images. The robot goes through all the tunnel performing the inspection, but the data is processed after all the images are collected. The inspection consists in the detection of cracks via computer vision algorithms.



Figure 4. Robotic platform with camera used in tunnel inspections [43]

A similar robot can be found in the work by F. Yao et al. [46][47]. In this case, the mobile robot is equipped with 21 ultrasonic sensors and 6 video cameras. These sensors are mounted on the same plane and with a semi-ring shape. The inspection consists in the scan of the tunnel lining to search for deformations. The experimental results show that this system can detect the deformed inner-walls at the division of 14 mm when the robot moves at 20 mm/s.

Figure 5 shows a system built with an industrial manipulator robot [48]. The system consists of an eight-ton truck used as a base machine, tunnel cross section

measuring systems, Electronic Distance Measuring (EDM) instruments employed to measure impact locations, an impact unit with five hammers that generates impact sounds and its equipped on the robotic arm, a lifter that raises the robot up to ceiling level, and finally a computer unit that controls all these components.



Figure 5. A robotic tunnel inspection system that uses the impact sound method [48]

The system uses an impact acoustics method for the inspection procedure, which impacts the concrete wall with hydraulic hammers, converts the impact sounds into electric signals, and then analyses them. The system is capable of finding exfoliation and cavities in a concrete lining. In order to maintain stable attitude, the truck has been equipped with outriggers on the non-motorized wheels. Three people conduct the impact sound diagnosis: a foreman, an operator and a driver. The machine is operated from the touch panel of the computer that is situated at the operator console.

Another example, seen in Figure 6, uses two lasers to perform a hammer-like inspection to detect inner defects in concrete structures like transportation tunnels [49]. The system is mounted on a motor vehicle and the technique is based on the initiation and detection of standing Lamb waves (or natural vibration) in the concrete layer between surface and inner defects. The concept consists in one laser used like a hammer to impact the surface and another one used to take the measurements. The system can detect various types of inner defects like voids, cracks and honeycombs. The accuracy of defect location is about 1 to 3 cm and the detection depth up to 5 cm.



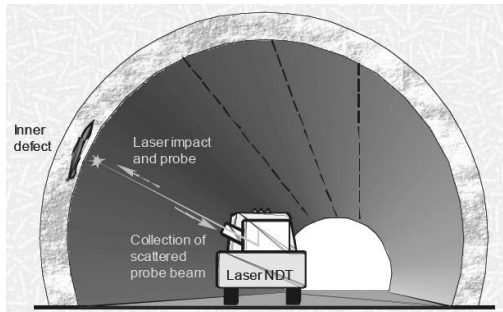


Figure 6. Schematic of the hammer-like laser remote inspection system [49]

Also of interest is the Tunnelings project [50]. The tunnel inspection system developed by Euroconsult and Pavemetrics, shown in Figure 7, is based on cameras and laser sensors that allow scanning a tunnel's wall linings at speeds up to 30 km/h. The software of the system also allows the data from two different inspection runs to be rapidly compared, and structural changes and wall lining defects to be assessed.

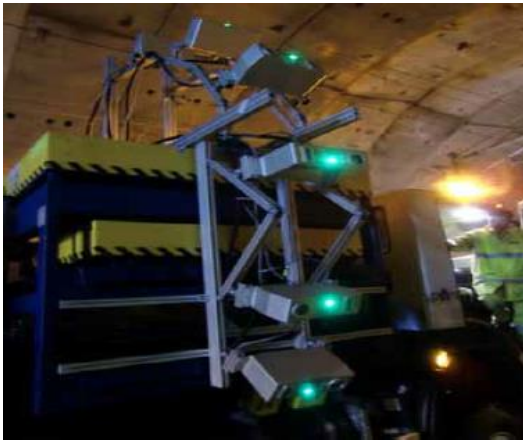


Figure 7. The Tunnelings system sensor structure

The measurement sensors for the condition survey are installed on a truck capable of running on rails and on flat terrain. The vehicle comprises all the systems necessary for safe road and rail travel (lane occupation indicator, speed governor, electric power supply for all systems, signaling equipment etc.). It can hold up to 6 laser cameras, as. Each pair of laser-camera units inspects a 2 m wide section with an accuracy of 1 mm. Using the six cameras, tunnels with a 9 m diameter can be inspected at the system's maximum resolution.

The system developed by N. Sano et al. [51] consists in a crack detecting vehicle equipped with laser sensors and CCD cameras. The vehicle is driven through the

tunnel by an operator and the cameras take pictures of the tunnel walls. The isolated images taken by the cameras are merged together into a surface map of the tunnel. After the map is obtained, a dedicated vision software detects cracks in it.

The system shown in Figure 8 checks for voids behind lining by drilling holes with a mechanized crane [52]. It performs high speed drills of 33 mm diameter by a combination of rotation and striking the lining concrete of a tunnel surface in order to investigate the thickness of a lining and the height of a rear cavity with high accuracy.



Figure 8. Void detection rotary percussive drilling machine [52]

This example and others (such as methods based on a mechanized hammering tester installed on a crane, Figure 9) were described by Hideto Mashimo and Toshiaki Ishimura in [1], where they define the status of road tunnel inspection and maintenance in Japan in 2006.

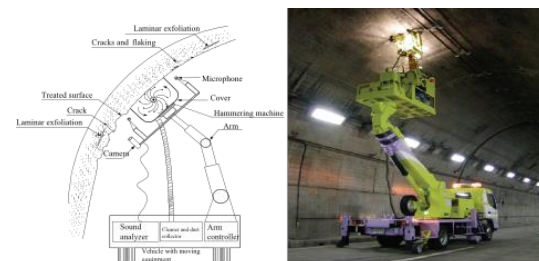


Figure 9. Mechanized hammer test [1]

More examples of systems working on Japan tunnels can be found in the work by Toshihiro Asakura and Yoshiyuki Kojima [53], which shows maintenance technology and typical deformation cases of Japanese railway tunnels, along with some methods of inspection

and diagnosis and three case studies (Tsukayama Tunnel, Fukuoka Tunnel and Rebunhama Tunnel). The inspection methods examples includes Hammer testing on the lining (performed by an operator in this case), crack measurements in tunnel lining using line-sensor cameras mounted in a vehicle in rails, and investigation of the surface of the tunnel lining using an infrared camera and CCD cameras.

The mechanized cleaning truck shown in Figure 10 is an example of a tunnel maintenance system [54][55], which is important to prevent further damage. It has been designed by engineers of Colas, Switzerland, in collaboration with operators of road networks. It was set up in seven months in 2012. This tunnel cleaning system consists in a standard commercial truck equipped with eight mechanical arms with different types of brushes. The arms and the brushes have hydraulic actuators which provide movement and water flow for the cleaning process. The mechanical arms can be positioned remotely to adapt to different tunnel geometries.



Figure 10. Tunnel cleaning system [55]

This is achieved with a communication briefcase-like system controlled by an operator near the truck. A second operator is needed to drive the truck at a speed of 2 km/h while the tunnel walls are being cleaned with the brushes. The system can operate in tunnels of a 7.66 maximum height. Only one half of the tunnel section is covered each time, without blocking the traffic on the free lanes.

Another commercial example is the IRIS Hyrail built by Penetradar [56], shown in the Figure 11. The system is based on a GPR sensor mounted in a telescopic piece in the front of a Hyrail vehicle (e.g. a

vehicle able to go on road and on rails). The GPR positioning device can be rotated to cover the sides and top of the tunnel walls and the motorized boom can be retracted to avoid obstructions. Penetradar provides specialized software to manage data collection, data processing and display of GPR data.



Figure 11. IRIS Hyrail system inspecting a tunnel. Note the capability to be mount on rails [56]

When tunnels that need to be inspected have reduced dimensions, such as underground tunnels used to deploy power cables, the use of robotic platforms is more than appropriate. In this scenario, small tele-operated mobile robots can make inspections providing visual and concentration data of some poisonous gases, like the system by Fu Zhuang et al. [57] shown in Figure 12. This tele-operated robot (420mm long, 320mm wide and 300mm high) can operate in 1 meter wide tunnels, move at a rate of 24 m/min, and has 2 hours of autonomy. Its sensor system includes a pan-tilt-zoom camera, inclinometer, gyroscopes, gas sensors (CO, CH<sub>4</sub>, CO<sub>2</sub>, and O<sub>2</sub>), thermometer, IR distance sensors, and ultrasonic sensors.

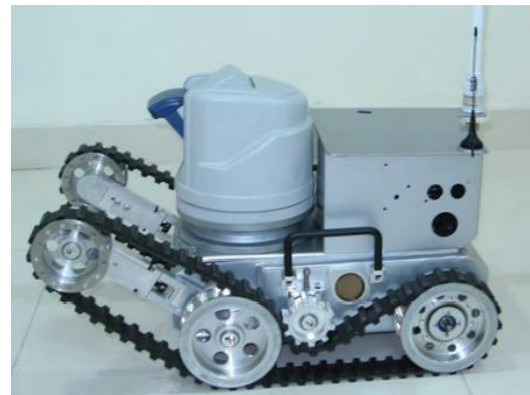


Figure 12. Cable tunnel inspection robot [57]

In other cases, cables are not inside small tunnels but along a greater one placed on the walls. Taking this into account, Songyi Dian et al. [58] designed a robot based on a shrimp-rover vehicle [59] with six wheels able to go over tunnel power cables while making the inspection. Unfortunately this work is only theoretical and the robot does not exist physically. Other examples of tunnel cables inspection robots can be found in B. Jiang et al. [60][61] and Claudio Mello et al. [62].

Another type of small tunnel is ventilation tunnels. R. Minichan et al. [63] designed three different mobile robots to inspect the ventilation tunnels of the H-Canyon Facility in 2003, 2009 and 2011. Due to the toxic environment of the tunnels, only a robot could perform the inspection process. The control of the robots is made remotely and the system was connected through a long tether to the control station. The inspection consisted in a visual assessment with the images provided by the robot cameras. Figure 13 shows the three robot models.

Not all tunnels are designed to carry vehicles, people or cables. Water distribution is managed with tunnels too, and different solutions must be used to inspect this kind of structures. In this scenario, alternatives to mobile wheeled robots include Autonomous Underwater Vehicles (AUV) [64] and Remotely Operated Vehicles (ROV) [65][66] which can exploit the use of sonar sensors for the mapping procedure.



Figure 13. Three ventilation tunnel robotic inspection systems [63]

All the systems seen in this section have their own sensors, and publish the data obtained to perform the assessment of the structure. However, an alternative strategy involves the use of sensors embedded in the structures to be inspected, such as strain gauges, which are usually more precise and reliable. Brian Esser et al. [67] implemented this method and developed a robot capable of remotely powering and collecting data from a

network of embedded sensing nodes, and providing remote data access via the Internet. The system uses Addressable Sensing Modules (i.e. ASM's) to sample data from a wide variety of sensors (e.g. peak displacement, peak strain, corrosion, temperature, inclination, etc.). This kind of system is useful in long tunnels where a wired sensor network is difficult to implement, or in tunnels with complicated access.

## 2.2 Other Related Systems

There is also a great number of systems that have been developed for inspection purposes that may be applicable to the tunnel environment. These systems were designed for the inspection of bridges, pipes, or pavement among others. The similarities in geometry, materials, defects and inspection procedures of these systems leads to similar technological solutions able to be used for the tunnel inspection procedure.

Two examples of this kind of robots are the ones designed by Carnegie Mellon. One is a tele-operated vehicle for mapping of abandoned mines [68] (similar in geometry and dimensions to a tunnel). The other is a similar robot, developed for the inspection of hazardous environments with cameras embedded on an articulated arm [69].

Inspection of pipes is also a relevant area. Some pipes' dimensions can be up to 3 m, similar to a small ventilation tunnel. These scenarios involve small tele-operated robots [70][71] able to make visual inspections along with mapping of pipes and deformation analysis [72]. Some of these systems can even perform cleaning [73] and maintenance [74][75][76] operations. Commercial solutions like Redzone Robotics [77] also provide pipe inspection robots.

Certain robots designed for bridge inspection have the vehicle-crane configuration, similar to some of the ones used in the tunnel inspection [1][53][48][78][79], but modified to reach zones under the bridges [80][81][82]. The majority of these systems use the same sensors to achieve the inspection (vision, laser, ultrasound, etc.) and some solutions use robotic arms installed on the tip of the crane to perform maintenance operations [83]. On the other hand, robots designed to inspect the superior part of bridges mainly focus on the crack detection of the pavement [84], and are similar to road pavement inspection robots [85][86][87] that have similar sensors and algorithms to the tunnel crack detecting in tunnels; while others mount a variety of sensors to achieve a more complete assessment [88].



Lastly, climbing capabilities of some robots are being used to perform inspections in zones with difficult access [89][90]. Early attempts used legged robots capable of climbing metallic-based structures [91], while the most modern systems uses suction [92] or negative pressure [93][94][95][96] devices to attach to structure walls.

### 3 Main Drawbacks

As seen in the previous section, all of the robotic tunnel inspection systems are tele-operated in some way. This is one of the main disadvantages of all these systems. These systems slightly improve the working conditions of the operators in the tunnel, but to successfully overcome all the problems of the manual inspection procedures, a fully automated tunnel inspection system must be developed.

The need for one or more human operators of the presented systems sometimes require the workers to be in the same location as the robot, eliminating one of the benefits of the robotic inspection, which is remote operation. Because of this, the operator is exposed to the dangerous tunnel environment, including large isolated areas, low visibility, dust, humidity or even toxic gases.

In some cases, the inspection data gathered by the system is not enough to make a complete assessment of the tunnel, and an additional manual inspection performed by a qualified inspector is required. This causes subjectivity in the inspection results that relies on the inspector judgment and may contain diverse errors.

In other cases, the limitations in the type of communication used (e.g. tether length, wireless area) leads to the same problem described before. In the case of wired tele-operation, the main bottleneck is the length of the cable itself, which limits the operational range of the robot with respect to the control station. Regarding the wireless communication, one problem is the signal intensity decay, and it could depend on the tunnel length, material or complexity. Other problem is the bandwidth that needs to be high if the robot has little autonomy and sends a large amount of data to the tele-operator.

The difficulties mentioned before mainly affect the quality of the inspection and the operators working conditions, but an important aspect of the inspection procedure is the economical impact that is incurred when a tunnel must to be closed for inspection. Leaving

the tunnel inoperable reverts in losses for the tunnel owners and users. Because of this, taking into account this issue is desirable to develop systems that can allow the use of the tunnel during the inspection procedure.

One of the solutions to these problems begins with the improvement of the automatic behaviors of the robots. With a fully automated inspection system, the security of the operators is guaranteed, along with the management, quality and objectivity of the tunnel data. Current efforts should be focused on obtaining more autonomous behaviors, that may adapt to different tunnel environments with less operator dependency.

### 4 Current Efforts in Fully Automated Tunnel Inspection

The latest developments in robotic and automation science allow the current tunnel inspection systems being developed to become more automated than the previously seen tele-operated systems. This confirms that the tendency is to reach a fully automated inspection system that allows a remote inspection with no direct human operation needed. The first part of this section reviews the TunConstruct system, which was partially autonomous, while the second part explains the ROBINSPECT system, which aims to perform fully automated tunnel inspection.

#### 4.1 TunConstruct System

The TunConstruct project [78][79] was part of the European Commission 6th Framework Program (FP6), and was conducted by 41 partners from 11 European countries. This project's objectives involved the development of a robotic system capable of performing inspection and maintenance in concrete tunnels.

The TunConstruct system is shown in Figure 14, and consists in a robotic arm on the tip of a crane, mounted on a vehicle. The system is able of applying a composite material on cracks of a tunnel. Inspection is performed through a user-friendly guided HMI (Human Machine Interaction), where a 2D camera image stream is displayed and operation procedures are requested. Visual servoing based on the depth measure captured by the tool's laser telemeter, and operation-oriented actuators are coordinated through task-specific control software, allow the process to be automatically performed by the robotic system.

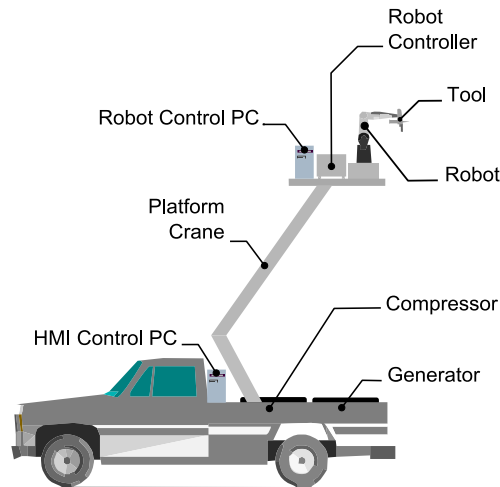


Figure 14. TunConstruct system scheme [79]

The robot arm chosen for the application was the Mitsubishi PA-10, a 7 DOF manipulator with a 10 kg load capacity and a 1 meter maximum extension range. The global increment of this range is achieved by mounting the Robot on a 5 meter extensible articulated lift platform. The HMI is installed in the wheeled vehicle's cabinet to which the articulated lift platform is attached. Power for the system can be supplied from an on-board generator, the wheeled vehicle's motor, or the tunnel's basic provided services.

Once in the tunnel, the inspection procedure is achieved by means of a camera mounted in the robotic arm. Using the HMI with the images provided, the operator can guide the robot and select the crack in the tunnel surface in which the system is going to apply the repair material. For the maintenance process, the robot uses a specially designed tool to prepare the selected surface and apply the resin and the composite material on it. The superficial preparation is accomplished blowing compressed air to clean the zone. The mentioned tool is composed by two complementary systems: a material application system composed by mechanical subsystems and actuators, and a vision and security system composed by the camera, the laser distance sensor, and security micro-switches. The resin is attached to the tool in a cartridge, while the composite (Fiber Reinforced Polymer) is loaded in the form of a roll.

The system was tested successfully first in laboratory conditions and then in real, non-controlled environments in tunnels in León, Spain. Figure 15 shows one of the mentioned tests in real tunnels.



Figure 15. TunConstruct system test in a Spanish tunnel. Note that one lane of the tunnel traffic flow is not blocked

#### 4.2 ROBINSPECT: Towards a Fully Automated Robotic Inspection System

ROBINSPECT (ROBOTic System with Intelligent Vision and Control for Tunnel Structural INSPECTION and Evaluation) [97] is a project co-funded by the European Commission, under its 7th Framework Program (FP7). The project begun on October 2013 and will finalize in 2016. This project comprises the design of an autonomous robotic system capable of performing intelligent inspection and assessment of a tunnel in one pass. Figure 16 depicts a schematic representation of the ROBINSPECT system. Its similarity with previous projects of the field is in line with a “not reinventing the wheel” philosophy, and instead focusing on automation, intelligence, and benchmarking objectives.



Figure 16. ROBINSPECT schematic representation

ROBINSPECT is driven by the tunnel inspection industry and adapts and integrates recent research results in intelligent control in robotics, and computer vision tailored with semi-supervised and active continuous learning and sensing, in an integrated robotic system for automatically scanning intrados for potential defects on concrete surfaces and detecting and measuring radial deformation in cross-sections, distances between parallel cracks, and cracks and open joints that impact tunnel stability, with millimeter accuracies. This will allow, in one pass, both the inspection and structural assessment of tunnels.

The initial dataset on tunnel defects will be provided from case studies (including London Underground, an interesting case study as the network incorporates the world's first underground railway) to be used not only for transfer learning but also for the evaluation of structural models. The robotic system will be evaluated and benchmarked at the research infrastructure of tunnels of VSH, at three road tunnels of the Egnatia Motorway, and sections of the railway tunnel of London Post Office.

The ROBINSPECT extended mobile robotic system will be a wheeled robotic system that will be able to extend an automated crane to the lengths commonly found in tunnels (4 to 7 meter range) sustaining a robot manipulator while being automated through the use of robotic controllers. This robotic system will be composed by three subsystems: a mobile robot, an automated crane arm, and an industrial-quality robot manipulator. Systems with similar configurations are the TunConstruct system [78][79], and other existing systems of the construction industry [98]. Basic 1D (such as laser, infrared and ultrasound proximity and distance sensors), 2D (such as vision camera and SICK sensors) and 3D (as in time of flight or similar technology) sensors will be incorporated to the subsystems to enable collision avoidance. Apart from that, a special new ultrasonic sensor will be equipped to measure cracks width and depth. The mechanical concept design of the robotic system will be based on an existing industrial platform, so to ensure the successful operation under real tunnel conditions, although localization and navigation tests will be performed initially under simulated environments.

At the software level, Component Based Software Engineering (CBSE) techniques will be applied. Specifically, a set of low-level "device drivers" for each of the subsystems will be developed to allow the component's control to be integrated into the

developments of the following tasks of the project. Currently, several robotic software architectures (YARP [99], ROS [100], OROCOS [101], etc.) for implementing CBSE exist and are interoperable. The dynamic and kinematic requirements of the robotic platform needed to reach the measurement area will be designed. Special attention will be placed in keeping the vehicle stability as well as developing the platform modular enough to allow both road and railway navigation. Controllability will be improved as much as possible to achieve an accurate path following in tunnels.

A global controller for the system in the presented scenario will be developed for two main reasons. First, the additional length requirement means that any deviation of the control output at any of the stages of the low-level will be multiplied at the end-effector of the robotic manipulator (sensing tip). Secondly, the three different subsystems (the mobile robot, the automated crane arm, and the robot manipulator) must fulfill a set of required behaviors conjunctly: only a global controller can assure coherent and optimized trajectories. Moreover, the input of this global controller will come from the vision and sensory systems as data of three very different natures: an online stream of updated 3D model data of the tunnel environment coming from the 1D/2D/3D sensors, associated uncertainties (both intrinsic to the nature of the sensors as information regarding the confidence at each given instant), and additional semantic information regarding the state of the system and the required action/behavior. An intelligent controller will be developed as the global controller. It will update its prior belief model of the environment continuously by using the 3D model stream as input while taking into account the uncertainties as confidence values of the given data. The semantic information will be treated as conditional clauses for generating trajectories that comply with the general system's requisites. The feedback will be used for the global controller to auto-tune its parameters. The system's safety for the robotic system and environment will additionally be assured by the local controllers developed for each of the as the global intelligent controller is set at the high level to send references to these (and not directly on the actuators).

## 5 Future Trends

The previous sections have presented an extensive review on tunnel inspection methods and robotic systems with tele-operated and more modern

approaches focusing on the structural inspection problem. A discussion is open in this section, in the context of presenting solutions based on forthcoming improvements in the robotics area and related fields, in order to have a more complete vision of the future trends of technology and new approaches.

In terms of complex and unstructured environments, the great majority of large inspection systems cannot work properly, or have difficulties in doing so because of the use of wheeled platforms. One possible solution could be the use of legged robots with insect-like legs, such as the proof of concept robotic harvest system developed by John Deere [102] or the quadruped robot built by Boston Dynamics [103], to go through rough and uneven terrain and avoid unexpected obstacles easily. Another technology applicable to the future tunnel inspection process that avoids the mobility limitations are the Unmanned Aerial Vehicles (UAV) developments. There are some works that start to use this approach [104][105]. One advantage is that these robots may be produced at low cost, and also used simultaneously as they do not interrupt traffic. A complete swarm of robots with reduced dimensions may be used to perform the inspection process faster and exhaustively, concurrently gathering large amounts of data. Figure 17 depicts a hypothetical tunnel inspection scenario using legged robots and UAVs.

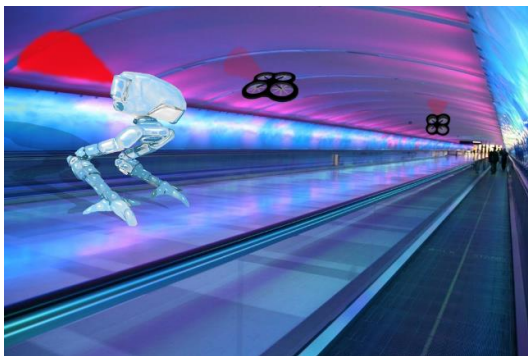


Figure 17. Conceptual image of a future tunnel inspection process<sup>1</sup>

A more advanced notion of legged robots would be the use of humanoids and anthropomorphic robots. Advances within the field of robot walking gait generation and solving stability issues are required for this step, but it is favored in turn with the advantages of the capabilities of these robots, which have the potential of using the same vehicles and tools that human workers currently employ, without exposing humans to the

associated risks.

On the other side, reducing robot dimensions with advances in the field of nanotechnology could lead to a different type of inspections in the future, using nano-robots, a.k.a. nano-bots. These nano-mechanisms could penetrate tunnel walls through cracks or small fissures and perform inspection and structural assessments of the materials from the inside, or search for invisible cracks in the extrados. Tests that are currently destructive could be performed through the use of non-destructive nano-bot mechanisms.

In terms of including preventive measures within the design phase, another good idea is to take into account the inspection and maintenance processes at the time of the structure construction. A set of rails may be planned and located along the tunnels, ready to a rail-robot to be attached. In this way, the robot (e.g. a robotic arm with sensors at the tip) may travel around the structure and inspect it with different sensors. Additionally, the robot could store different tools and sensors, and only pick up the appropriate ones when required for a given tunnel structural assessment.

Predictive efforts should benefit from advances in sharing and storing big data and information theory. Tunnel data can be saved and retrieved, and this process should become globally accessible through integrated services. Data may be used to compare different inspections of the same tunnel or similar tunnels around the world. Information from nearby and similar structures could be used to infer an idea of the land movements and predict how this will affect to the structures.

## 6 Conclusions

The vast majority of the presented tunnel inspection methods presented is currently performed manually by human workers in tunnel environments. Moreover, most part of the presented robotic inspection systems is actually tele-operated, and none of the presented currently operational systems is fully autonomous. One or more human operators must move the robotic system, control where to go, and command what to do. In addition, in most cases the data is processed after completing the inspection procedure, causing a delay between the time the inspection is completed and the results are available. This makes the tunnel unsecure for longer times if critical defects exists.

<sup>1</sup> Original background photograph by Scott Beale



This situation causes the efforts to be focused on developing systems that aim to be fully autonomous, such as the ROBINSPECT system. Future systems must be capable of both inspection and maintenance with minimal human intervention, and perhaps with no supervision at all. Much research is ongoing in able to design better systems, capable of performing accurate and cost-effective inspection, maintenance and assessment of civil structures that reverts in more safety in environments and less budget spent in reparations.

## Acknowledgements

This work was supported by RoboCity2030-II-CM project (S2009/DPI-1559) funded by Programas de Actividades I+D in Comunidad de Madrid and co-funded by Structural Funds of the EU, ARCADIA project DPI2010-21047-C02-01 funded by CICYT project grant, and ROBINSPECT project number 611145 co-funded by the European Commission under 7<sup>th</sup> Framework program. The authors would also like to acknowledge the work of the other partners involved in the TunConstruct project: DRAGADOS, SIKA, and M. Lorenzana.

## References

- [1] Mashimo, H., Ishimura, T.: State of the art and future prospect of maintenance and operation of road tunnel. *23th International Symposium on Automation and Robotics in Construction ISARC*, p. 299–302, 2006.
- [2] Ikuma, M.: Maintenance of the undersea section of the Seikan Tunnel. *Tunnelling and Underground Space Technology*, 20 (2), p. 143–149, 2005.
- [3] National Transportation Safety Board: *Ceiling Collapse in the Interstate 90 Connector Tunnel*. Boston, Massachusetts, 2006.
- [4] Fackler, M.: Nine Killed When Highway Tunnel Collapses in Japan. *The New York Times*, 2012.
- [5] Federal Highway Administration: *Tunnel Operations, Maintenance, Inspection and Evaluation (TOMIE) Manual*.
- [6] Park, S. et al.: A guideline on condition assessment of existing old railway tunnels. *Tunnelling and Underground Space Technology*, 21 (3), p. 329–330, 2006.
- [7] Xia, C. et al.: *Analysis on The Causation and Classification of Common Damages of Highway Tunnel*. In: ISGSR2007 First International Symposium on Geotechnical Safety & Risk. 2007, p. 197–204.
- [8] International Atomic Energy Agency: *Guidebook on non-destructive testing of concrete structures*. 2002.
- [9] Basu, A., Aydin, A.: A method for normalization of Schmidt hammer rebound values. *International Journal of Rock Mechanics and Mining Sciences*, 41 (7), p. 1211–1214, 2004.
- [10] Malhotra, V.M.: Evaluation of the Windsor probe test for estimating compressive strength of concrete. *Matériaux et Construction*, 7 (1), p. 3–15, 1974.
- [11] Binda, L., Tiraboschi, C.: Flat-Jack Test: A slightly destructive technique for the diagnosis of brick and stone masonry structures. *International Journal for Restoration of Buildings and Monuments*, 5 (5), p. 449–472, 1999.
- [12] Lourenço, P., Gregorczyk, P.: Review on Flat-Jack Testing. *Engenharia Civil*, 9, p. 35–50, 2000.
- [13] Mori, K. et al.: A new non-contacting non-destructive testing method for defect detection in concrete. *NDT & E International*, 35 (6), p. 399–406, 2002.
- [14] Sansalone, M.J., Streett, W.B.: *Impact-echo. Nondestructive evaluation of concrete and masonry*. 1997.
- [15] Carino, N.: *The impact-echo method: an overview*. In: Proceedings of the 2001 Structures Congress & Exposition. Washington, DC, American Society of Civil Engineers, 2001, p. 18.
- [16] Sansalone, M., Carino, N.J.: Detecting delaminations in concrete slabs with and without overlays using the impact-echo method. *ACI Materials Journal*, 86 (2), p. 175–184, 1989.
- [17] Aggelis, D.G. et al.: Evaluation of grouting in tunnel lining using impact-echo. *Tunnelling and Underground Space Technology*, 23 (6), p. 629–637, 2008.
- [18] Powers, T.C.: Measuring Young's modulus of elasticity by means of sonic vibrations. *Proceedings American Society for Testing and Materials*, 38 (Part II), p. 460, 1938.
- [19] Obert, L.: Sonic method of determining the modulus of elasticity of building materials under pressure. *Proc. ASTM*, 39, p. 987, 1939.
- [20] Toutanji, H.: Ultrasonic wave velocity signal interpretation of simulated concrete bridge decks. *Materials and Structures*, 33 (3), p. 207–215, 2000.
- [21] Blitz, J., Simpson, G.: *Ultrasonic methods of non-destructive testing*. Springer, 1996.
- [22] Makar, J., Desnoyers, R.: Magnetic field techniques for the inspection of steel under concrete cover. *NDT & E International*, 34 (7), p. 445–456, 2001.
- [23] Sawade, G., Krause, H.-J.: *Inspection of Prestressed Concrete Members using the Magnetic Leakage Flux Measurement Method—Estimation of Detection Limit*. In: Advances in Construction Materials (Editor: C. Grosse). Springer Berlin Heidelberg, 2007, p. 639–649.
- [24] Polder, R.: Test methods for on site measurement of resistivity of concrete—a RILEM TC-154 technical recommendation. *Construction and building materials*, 15 (2), p. 125–131, 2001.
- [25] Lataste, J.F. et al.: Electrical resistivity measurement applied to cracking assessment on reinforced concrete structures in civil engineering. *NDT & E International*, 36 (6), p. 383–394, 2003.

- [26] McCarter, W.J., Vennesland, Ø.: Sensor systems for use in reinforced concrete structures. *Construction and Building Materials*, 18 (6), p. 351–358, 2004.
- [27] Nakamura, E. et al.: *Half-Cell Potential Measurements to Assess Corrosion Risk of Reinforcement Steels in a PC Bridge*. In: RILEM Symposium on On Site Assessment of Concrete, Masonry and Timber Structures - SACoMaTiS 2008. Como Lake - Italy, 2008, p. 109–117.
- [28] Richards, J.: Inspection, maintenance and repair of tunnels: international lessons and practice. *Tunnelling and Underground Space Technology*, 13 (4), p. 369–375, 1998.
- [29] Wu, D., Busse, G.: Lock-in thermography for nondestructive evaluation of materials. *Revue générale de thermique*, 37 (8), p. 693–703, 1998.
- [30] Avdelidis, N.P., Moropoulou, A.: Applications of infrared thermography for the investigation of historic structures. *Journal of Cultural Heritage*, 5 (1), p. 119–127, 2004.
- [31] Daniels, D.J.: *Ground penetrating radar*. Iet, 2004.
- [32] Parkinson, G., Ékes, C.: *Ground penetrating radar evaluation of concrete tunnel linings*. In: 12th International Conference on Ground Penetrating Radar. Birmingham, UK, 2008, p. 11.
- [33] Xie, X., Zeng, C.: *Non-destructive evaluation of shield tunnel condition using GPR and 3D laser scanning*. In: Ground Penetrating Radar (GPR), 2012 14th International Conference on. IEEE, 2012, p. 479–484.
- [34] Hugenschmidt, J., Mastrangelo, R.: GPR inspection of concrete bridges. *Cement and Concrete Composites*, 28 (4), p.384–392, 2006.
- [35] Gamidi, S.H.: *Non-destructive testing of structures*. Indian Institute of Technology, Bombay, 2009, p. 35.
- [36] Büyükoztürk, O.: Imaging of concrete structures. *NDT & E International*, 31 (4), p. 233–243, 1998.
- [37] McCann, D.M., Forde, M.C.: Review of NDT methods in the assessment of concrete and masonry structures. *NDT & E International*, 34 (2), p. 71–84, 2001.
- [38] Colla, C. et al.: Combination of NDT techniques for site investigation of non-ballasted railway tracks. *NDT & E International*, 35 (2), p. 95–105, 2002.
- [39] Zhu, Y.-K. et al.: A review of optical NDT technologies. *Sensors*, 11 (8), p. 7773–98, 2011.
- [40] Gambao, E., Balaguer, C.: Robotics and automation in construction [Guest Editors]. *Robotics & Automation Magazine, IEEE*, 9 (1), p. 4–6, 2002.
- [41] Balaguer, C., Abderrahim, M.: Trends in robotics and automation in construction. *Robotics and Automation in Construction*, p. 1–20, 2008.
- [42] Balaguer, C., Victores, J.G.: *Robotic tunnel inspection and repair*. In: Technology Innovation in Underground Construction. CRC Press, 2010, p. 445–460.
- [43] Yu, S. et al.: Auto inspection system using a mobile robot for detecting concrete cracks in a tunnel. *Automation in Construction*, 16 (3), p. 255–261, 2007.
- [44] Lee, S.Y. et al.: Development of an inspection system for cracks in a concrete tunnel lining. *Canadian Journal of Civil Engineering*, 34 (8), p. 966–975, 2007.
- [45] Ko, B. et al.: *Development of an Inspection System for Cracks on the Lining of Concrete Tunnels*. In: Proceedings of the 20th ISARC. Eindhoven, Holland, 2003, p. 457–463.
- [46] Yao, F.-H.F. et al.: *Development of an automatic concrete-tunnel inspection system by an autonomous mobile robot*. In: Robot and Human Interactive Communication, 2000. RO-MAN 2000. Proceedings. 9th IEEE International Workshop on. IEEE, 2000, p. 74–79.
- [47] Yao, F. et al.: Automatic concrete tunnel inspection robot system. *Advanced Robotics*, 17 (4), p. 319–337, 2003.
- [48] Suda, T. et al.: Development of an impact sound diagnosis system for tunnel concrete lining. *Tunnelling and Underground Space Technology*, 19 (4), p. 328–329, 2004.
- [49] Fujita, M. et al.: *Non-Destructive Remote Inspection for Heavy Constructions*. In: Conference on Lasers and Electro-Optics 2012. Washington, D.C.: Osa, 2012.
- [50] Gavilán, M. et al.: *Mobile Inspection System for High-Resolution Assessment of Tunnels*. In: The 6th International Conference on Structural Health Monitoring of Intelligent Infrastructure. 2013, p. 10.
- [51] Sano, N. et al.: Investigation of Cracks in Lining Concrete by Using Sequential Image Analysis. *Journal of Construction Management and Engineering*, 62 (3), p. 558–566, 2006.
- [52] Oshima, K. et al.: Inspection of Voids between Lining and Ground using Rotary Percussion System. *Tunnels and Underground*, 36 (4), p. 345–355, 2005.
- [53] Asakura, T., Kojima, Y.: Tunnel maintenance in Japan. *Tunnelling and Underground Space Technology*, 18 (2-3), p. 161–169, 2003.
- [54] Sanchez, S.: «Octopus», le camion fribourgeois qui part à l'assaut des tunnels romands. *La Liberté*, p. 2–3, 2013.
- [55] Groso, V.: *Camion de lavage de tunnels*. 2013, p. 1.
- [56] Penetradar: *Penetradar GPR Catalog 2013*. 2013, p. 19.
- [57] Zhuang, F. et al.: A cable-tunnel inspecting robot for dangerous environment. *International Journal of Advanced Robotic Systems*, 5 (3), p. 243–248, 2008.
- [58] Dian, S. et al.: *A novel shrimp rover-based mobile robot for monitoring tunnel power cables*. In: 2011 IEEE International Conference on Mechatronics and Automation. Beijing, China: IEEE, 2011, p. 887–892.
- [59] Estier, T. et al.: *Shrimp, a Rover Architecture for Long Range Martian Mission*. In: Proceedings of the Sixth ESA Workshop on Advanced Space Technologies for Robotics and Automation (ASTRA'2000). 2000, p. 5–7.
- [60] Jiang, B. et al.: *Robotic platform for monitoring underground cable systems*. In: Transmission and Distribution Conference and Exhibition 2002: Asia Pacific. IEEE/PES. 2002, p. 1105–1109.
- [61] Jiang, B. et al.: *Autonomous robotic monitoring of underground cable systems*. In: Advanced Robotics, 2005. ICAR'05. Proceedings., 12th International Conference on. IEEE, 2005, p. 673–679.

- [62] Mello Jr., C. et al.: *TATUBOT Robotic System for Inspection of Undergrounded Cable System*. In: 2008 IEEE Latin American Robotic Symposium. Ieee, 2008, p. 170–175.
- [63] Minichan, R. et al.: *H-Canyon Air Exhaust Tunnel Inspection Vehicle Development*. In: ANS EPRRS - 13th Robotics & remote Systems for Hazardous Environments • 11th Emergency Preparedness & Response. Knoxville, TN: American Nuclear Society, 2011, p. 11.
- [64] Kalwa, J.: *SeaCat Inspects 24 km Long Water Tunnel*. *Ocean News & Technology*, 18 (4), 2012.
- [65] Ageev, M. et al.: *Modernized TSL-underwater robot for tunnel and shallow-water inspection*. In: Underwater Technology, 2000. UT 00. Proceedings of the 2000 International Symposium on. IEEE, 2000, p. 90–95.
- [66] Loisy, F., François, P.: *Underwater inspection experiment for a long tunnel of EDF's hydroelectric facilities*. In: Applied Robotics for the Power Industry, 1st International Conference on. Montréal, Canada, 2010, p. 1–4.
- [67] Esser, B. et al.: *Wireless inductive robotic inspection of structures*. In: Proceedings of IASTED International Conference Robotics and Applications. Honolulu, Hawaii, USA, 2000, p. 14–16.
- [68] Thrun, S. et al.: *A system for volumetric robotic mapping of abandoned mines*. In: Robotics and Automation, 2003. Proceedings. ICRA'03. IEEE International Conference on. IEEE, 2003, p. 4270–4275.
- [69] Sensabot: A Safe And Cost-Effective Inspection Solution. *Journal of Petroleum Technology*, (October), p032–34.
- [70] Zhang, Y., Yan, G.: In-pipe inspection robot with active pipe-diameter adaptability and automatic tractive force adjusting. *Mechanism and Machine Theory*, 42 (12), p. 1618–1631, 2007.
- [71] Lokeman, M. Bin: *Tunnel Inspection Robot II*. Universiti Teknikal Malaysia Melaka, 2008.
- [72] Liu, Z., Kryz, D.: The use of laser range finder on a robotic platform for pipe inspection. *Mechanical Systems and Signal Processing*, 31, p. 246–257, 2012.
- [73] Saenz, J. et al.: *Robotic systems for cleaning and inspection of large concrete pipes*. In: Applied Robotics for the Power Industry (CARPI), 2010 1st International Conference on. IEEE, 2010, p. 1–7.
- [74] Mateos, L.A. LA, Vincze, M.: *In-pipe Cleaning Mechanical System for DeWaLoP - Developing Water Loss Prevention*. In: Proceedings of the Austrian Robotics Workshop 2013. 2013, p. 1–6.
- [75] Mateos, L.A. LA, Vincze, M.: *In-pipe Robot with Capability of Self Stabilization and Accurate Pipe Surface Cleaning*. In: Proceedings of the IEEE International Conference on Automation Science and Engineering 2013. 2013, p. 7.
- [76] Mateos, L.A. et al.: *Automatic in-pipe robot centering from 3D to 2D controller simplification*. In: Intelligent Robots and Systems (IROS), 2013 IEEE/RSJ International Conference on. Tokyo, Japan: IEEE, 2013, p. 258–265.
- [77] Redzone Robotics: *Redzone Robotics - Water Infrastructure and Sewer Inspection Robots and Software*. no date.
- [78] González, J.C. et al.: *Robot-aided tunnel inspection and maintenance system*. In: Proceedings of the 26th International Symposium on Automation and Robotics in Construction. 2009, p. 420–426.
- [79] Victores, J.G. et al.: Robot-aided tunnel inspection and maintenance system by vision and proximity sensor integration. *Automation in Construction*, 20 (5), p. 629–636, 2011.
- [80] Tung, P. et al.: The development of a mobile manipulator imaging system for bridge crack inspection. *Automation in construction*, 11 (6), p. 717–729, 2002.
- [81] Oh, J.-K. et al.: Bridge inspection robot system with machine vision. *Automation in Construction*, 18 (7), p. 929–941, 2009.
- [82] Lee, J. et al.: *Development of an Advanced Robot System for Automated Bridge Inspection and Monitoring*. In: Safety, Reliability and Risk of Structures, Infrastructures and Engineering Systems (Editor: F. & S. Furuta). Taylor & Francis Group, London, 2010, p. 2544–2551.
- [83] Lorenc, S. et al.: Development of a robotic bridge maintenance system. *Automation in Construction*, 9 (3), p. 251–258, 2000.
- [84] Lim, R.S. et al.: *Developing a crack inspection robot for bridge maintenance*. In: Robotics and Automation (ICRA). IEEE, 2011, p. 6288–6293.
- [85] Fugro Roadware: *Fugro Roadware*. no date.
- [86] Tseng, Y.H. et al.: Strategies for autonomous robots to inspect pavement distresses. *Automation in Construction*, 20 (8), p. 1156–1172, 2011.
- [87] Holmes, J. et al.: Development of an Automated Pavement Crack Sealing System. *No. FHWA-GA-10-2047*, 2010.
- [88] La, H. et al.: Mechatronic Systems Design for an Autonomous Robotic System for High-Efficiency Bridge Deck Inspection and Evaluation. *Mechatronics, IEEE/ASME Transactions on*, 18 (6), p. 1655–1664, 2013.
- [89] Giménez Fernandez, A.: *Metodología de Diseño y Control de Robots Escaladores. Aplicación a las Tareas de Inspección*. Universidad Carlos III de Madrid, 2000, p. 266.
- [90] Armada, M. et al.: Application of CLAWAR Machines. *The International Journal of Robotics Research*, 22 (3–4), p. 251–264, 2003.
- [91] Balaguer, C. et al.: A climbing autonomous robot for inspection applications in 3d complex environments. *Robotica*, 18 (3), p. 287–297, 2000.
- [92] Rosa, G. La et al.: A low-cost lightweight climbing robot for the inspection of vertical surfaces. *Mechatronics*, 12 (1), p. 71–96, 2002.
- [93] Berns, K., Hillenbrand, C.: *A climbing robot based on under pressure adhesion for the inspection of concrete walls*. In: Proc. ISR. 2004, p. 5.
- [94] Hillenbrand, C. et al.: *Cromsci-a climbing robot with multiple sucking chambers for inspection tasks*. In: 1th International Conference on Climbing and Walking Robots (CLAWAR). 2008, p. 311–318.

- [95] Hillenbrand, C., Berns, K.: *Inspection of surfaces with a manipulator mounted on a climbing robot*. In: 37th International Symposium on Robotics (ISR). 2006, p. 8.
- [96] Longo, D., Muscato, G.: The Alicia 3 climbing robot: a three-module robot for automatic wall inspection. *Robotics & Automation Magazine, IEEE*, 13 (1), p. 42–50, 2006.
- [97] ROBINSPECT: *ROBINSPECT (ROBotic System with Intelligent Vision and Control for Tunnel Structural INSPECTion and Evaluation)*. 2013.
- [98] Lee, S. et al.: *Design of a ceiling glass installation robot*. In: Proceedings of the 24th International Symposium on Automation and Robotics in Construction. 2007, p. 247–252.
- [99] Metta, G. et al.: YARP: Yet Another Robot Platform. *International Journal of Advanced Robotic Systems*, 3 (2006), 2006.
- [100] Quigley, M. et al.: *ROS: an open-source Robot Operating System*. In: ICRA workshop on open source software. 2009.
- [101] Bruyninckx, H.: *Open robot control software: the OROCOS project*. In: Robotics and Automation, 2001. Proceedings 2001 ICRA. IEEE International Conference on. IEEE, 2001, p. 2523–2528.
- [102] FoxNews: John Deere Walking Harvester treads lightly and carries very big sticks. *FoxNews*, 2012.
- [103] Raibert, M. et al.: *Bigdog, the rough-terrain quadruped robot*. In: Proceedings of the 17th World Congress. 2008, p. 10823–10825.
- [104] Metni, N., Hamel, T.: A UAV for bridge inspection: Visual servoing control law with orientation limits. *Automation in Construction*, 17 (1), p. 3–10, 2007.
- [105] Avendano, J. et al.: *Towards the development of a complex structural inspection system using small-scale aerial vehicles and image processing*. In: Systems Conference (SysCon), 2013 IEEE International. Orlando, FL: Ieee, 2013, p. 4123–425.