**TABLE OF CONTENTS**

**ACKNOWLEDGEMENTS**

**ABSTRACT**

**TABLE OF CONTENTS**

**LIST OF FIGURES**

**LIST OF TABLES**

**LIST OF ABBREVIATIONS**

1. **INTRODUCTION**
   1. Locomotion for Rough Terrain
   2. Additive Manufacturing (3D Printing)
2. **LITERATURE REVIEW AND PROBLEM IDENTIFICATION**
   1. Problem Identification
   2. Objectives of Project
   3. Types of All-Terrain Robots
      1. Legged Robots
      2. Wheeled Robots
      3. Tracked Robots
      4. Re-Configurable Robots
   4. Comparison Factors
      1. Terrain Capabilities
      2. Payloads
      3. Stability
      4. Speed
      5. Complexity
   5. Comparison of Various Types of Locomotion
   6. Types of Additive Manufacturing Techniques
      1. Stereo-Lithography - SLA
      2. Multi-Jet Modelling – MJM
      3. Selective Laser Sintering - SLS
      4. Fused Deposition Modelling – FDM
   7. Problem Identification
3. **METHODOLOGY**
   1. Methodology
4. **IMPLEMENTATION** 
   1. Obstacle Negotiating Strategies
      1. Types of Obstacles
      2. Obstacle Negotiation
      3. Proposed Performance Specifications
   2. Development of IAR 1 and IAR 2
      1. Performance Comparison of IAR 1 and IAR 2
   3. Final Design and Prototype – IAR 3
      1. Design of Vehicle Body
      2. Design of Vehicle Arms
      3. Performance of the Vehicle
5. **RESULT ANALYSIS, CONCLUSION & FUTURE WORK**

**REFERENCES**

**APPENDICES**