Tractive mechanisms for wall climbing robots

University of Portsmouth, Dept. of Mechanical and Manufacturing Engineering - Figure 8 from A wall

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-Tractive mechanisms for wall climbing robots
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Figure 8 from A wall

In an irregular environment where rescue robots perform exploratory activities, the robots must be mobile enough to travel on uneven ground and climb over steps. The abilities of flat surface locomotion, anti-overturning, preload and detection capacity are validated by using experiments.

Design of Track

The robot positioning method based on the support and positioning mechanism can effectively locate the robot inside a spherical tank. Hence most of the models are slow, less agile, have less load carrying capacity.

Design of adhesive surface for track

Comprehensive Testing As shown in Figure , the support mechanism is connected to a magnetic adsorption robot.

Development of quadruped walking robot with spherical shell: improvement of climbing over a step

Climbing performance To verify the mobility of QRoSS V on uneven terrain, we conducted an experiment of the step, which was standardized. In: Proceedings of IEEE International Conference on Robotics and Automation pp.

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