FeLinks

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Project Description

The purpose of this project is to make a linkage driven quadrupedal robot with the ability to steer. Recently, there has been increased interested in quadrupedal robots for traversal of rough terrain at high speeds. Most often these robots are driven by a large number of expensive and heavy actuators. Linkages could offer a simpler, less expensive, and lighter means for driving quadrupedal robots. In addition linkages can be used to obtain high mechanical advantages allowing large torques to be obtained from high speed electric motors. Various linkage driven quadruped automata have been produced before, but they have lacked the ability to steer.