



UNIVERSITI TEKNIKAL MALAYSIA MELAKA

**DESIGN AND DEVELOPMENT OF FOUR WHEELED
AUTONOMOUS ROBOT**

This report submitted in accordance with requirement of the Universiti Teknikal Malaysia Melaka (UTeM) for the Bachelor Degree of Manufacturing Engineering (Robotic & Automation) with Honours.

by

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ABSTRACT

The purpose of this project is to design and develop a four-wheel autonomous robot for the ROBOCON 2010 competition. This robot will utilize Light Dependant Resistor (LDR) sensor, two-wheel drive and Peripheral Interface Controller (PIC) microcontroller in order to perform its specified task. This robot will be programmed to track down a white line on a green colored game field. The main aim for this project is to produce an efficient, precise and high speed robot platform to carry out the competition task within an optimum time frame. The project involves data gathering about major robot components including hardware, software and studies on similar past project. The methodology discusses the flow chart of the whole project and Pugh Method of design selection. The design phase includes design process and design selection. By using SolidWork 2008 software, two designs are proposed. The best design will be chosen to be fabricated. The objectives that requires designing and developing the four wheels autonomous robot is achieved and give good result to fulfill the requirement of the ROBOCON 2010 competition.

ABSTRAK

Projek ini bertujuan untuk merekabentuk dan membangunkan sebuah robot berautonomi beroda empat untuk pertandingan ROBOCON 2010. Robot ini akan menggunakan penderia jenis Perintang Peka Cahaya, pacuan dua roda dan mikropengawal PIC dalam menyempurnakan tugasnya. Robot ini akan diaturcarakan untuk menjejak garisan putih pada latarbelakang kawasan gelanggang berwarna hijau. Tujuan utama projek ini adalah untuk menghasilkan robot yang cekap, tepat dan berkelajuan tinggi dalam menjalankan tugas dengan penggunaan waktu yang optimum. Projek ini merangkumi pengumpulan data tentang komponen utama robot termasuklah dari perkakasan, perisian dan juga kajian tentang projek lepas yang hampir sama. Bahagian methodologi membincangkan carta aliran berkaitan dengan keseluruhan projek dan pemilihan rekabentuk menggunakan kaedah Pugh. Fasa rekabentuk termasuklah proses rekabentuk dan pemilihan rekabentuk. Dengan menggunakan perisian SolidWorks 2008, dua rekabentuk dikemukakan. Rekabentuk terbaik akan dipilih untuk difabrikasi. Objektif yang memerlukan rekabentuk dan pembangunan robot berautonomi beroda empat telah tercapai dan memberikan hasil yang serta memenuhi keperluan bagi pertandingan ROBOCON 2010.

DEDICATION

Specially dedicated to my beloved father, Haji Shaari bin Kassim and my mother, Hajjah Jamaliah binti Hassan who are very concern, understanding, patient, and supporting. Special thanks to my supervisor, Mrs. Syamimi binti Shamsuddin for her constructive guidance, encouragement and patient in fulfilling our aspiration in completing this project. To my brothers, sisters, and my entire friend, the work and success will never be achieved without all of you.

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TABLE OF CONTENT

| | |
|------------------------------|-----|
| Abstract | i |
| Abstrak | ii |
| Dedication | iii |
| Acknowledgement | iv |
| Table of Content | v |
| List of Tables | x |
| List of Figures | xi |
| List Abbreviations | xvi |
| | |
| 1. INTRODUCTION | |
| 1.1 Background | 1 |
| 1.2 Problem Statement | 5 |
| 1.3 Project Aim & Objectives | 6 |
| 1.4 Project Scope | 6 |
| 1.5 Robotic Technologies | 6 |
| 1.5.1 History | 7 |
| 1.5.2 Robot Definition | 8 |
| 1.5.3 Benefits of Robots | 8 |
| 1.5 Project Planning | 10 |
| | |
| 2. LITERATURE REVIEW | |
| 2.1 Introduction | 12 |
| 2.2 Introduction to Robots | 13 |
| 2.2.1 Manual Robots | 13 |
| 2.2.2 Autonomous Robots | 14 |
| 2.3 Mechanical Structure | 14 |
| 2.3.1 Aluminium | 15 |
| 2.3.2 Acrylic | 16 |

| | | |
|---------|------------------------------------|----|
| 2.3.3 | Fiber | 17 |
| 2.3.4 | High Density Polyethylene (HDPE) | 17 |
| 2.4 | Actuator | 19 |
| 2.4.1 | Motor | 19 |
| 2.4.1.1 | Basic Principles of Electric Motor | 19 |
| 2.4.2 | Types of Motor | 21 |
| 2.4.3 | AC Motor | 21 |
| 2.4.4 | DC Motor | 21 |
| 2.4.4.1 | Brushless | 23 |
| 2.4.4.2 | Servo | 24 |
| 2.4.4.3 | Stepper | 26 |
| 2.5 | Fabrication | 28 |
| 2.5.1 | Machining | 28 |
| 2.5.1.1 | Lathe | 29 |
| 2.5.1.2 | Grinding | 29 |
| 2.5.1.3 | Drilling | 31 |
| 2.5.2 | Fasteners | 32 |
| 2.5.2.1 | Screw thread | 32 |
| 2.5.2.2 | Rivet | 33 |
| 2.5.2.3 | Welding | 33 |
| 2.6 | Wheel | 34 |
| 2.6.1 | Conventional Wheel | 34 |
| 2.6.2 | Castor Wheel | 35 |
| 2.6.3 | Omni directional wheel | 36 |
| 2.6.4 | Mecanum | 36 |
| 2.7 | Sensor | 37 |
| 2.7.1 | Limit switch | 38 |
| 2.7.2 | Light Dependent Resistor (LDR) | 38 |
| 2.7.3 | Color sensor | 39 |
| 2.7.4 | Optical Sensor | 40 |
| 2.8 | Gripping Mechanism | 40 |

| | | |
|-----------|---|----|
| 2.8.1 | Clapper | 41 |
| 2.8.2 | Parallel Jaw Gripper | 43 |
| 2.9 | Controller | 45 |
| 2.9.1 | PC Based Controller | 46 |
| 2.9.2 | Programmable Logic Control (PLC) | 47 |
| 2.9.3 | PIC Microcontroller | 49 |
| 2.9.4 | PIC Microcontroller Family | 50 |
| 2.9.5 | PIC Microcontroller Manufacturer | 51 |
| 2.9.5.1 | Microchip | 52 |
| 2.9.5.2 | Atmel | 52 |
| 2.10 | Two Wheeled and Four Wheeled Robots | 53 |
| 2.10.1 | Two wheeled robot | 53 |
| 2.10.2 | Four wheeled robot | 55 |
| 2.11 | Software for Project development | 61 |
| 2.11.1 | Structural Design | 61 |
| 2.11.1.1 | AutoCAD | 61 |
| 2.11.1.2 | CATIA | 62 |
| 2.11.1.3 | SolidWork | 63 |
| 2.11.2 | Electronic Circuit Design Software | 64 |
| 2.11.2.1 | Express PCB | 65 |
| 2.11.3 | Microcontroller Programming | 66 |
| 2.11.3.1 | MPLAB | 66 |
| 2.12 | Similar Past Project | 67 |
| 2.12.1 | ROBOCON 2009 Autonomous Robot | 69 |
| 2.13 | ROBOCON Competition | 70 |
| 2.13.1 | ABU ROBOCON 2010 | 70 |
| 2.13.2 | Requirement for ROBOCON 2010 Autonomous Robot | 71 |
| 3. | METHODOLOGY | |
| 3.1.1 | Introduction | 74 |
| 3.1.2 | Process Flow Planning | 74 |

| | | |
|-----------|---------------------------------------|----|
| 3.1.3 | Data Collection for Literature Review | 77 |
| 3.1.3.1 | Internet | 77 |
| 3.1.3.2 | Journal | 78 |
| 3.1.3.3 | Books | 78 |
| 3.2 | Methodology | 79 |
| 3.2.1 | Mechanical Structure | 80 |
| 3.2.2 | Design | 80 |
| 3.2.3 | Fabrication | 80 |
| 3.2.4 | Assembly | 80 |
| 3.2.5 | Electrical and Electronic | 80 |
| 3.2.6 | Programming | 81 |
| 3.3 | Integration and Testing | 81 |
| 3.4 | Finalize Project Development | 81 |
| 3.6 | Software Tools | 82 |
| 3.6.1 | SolidWorks | 82 |
| 3.6.2 | MPLAB | 86 |
| 4. | DESIGN AND DEVELOPMENT | |
| 4.1 | Design Phase | 90 |
| 4.1.1 | Pyramids Main Blocks Specification | 91 |
| 4.1.2 | First design | 91 |
| 4.1.2.1 | Specification of First Design | 92 |
| 4.1.2.2 | Advantages | 93 |
| 4.1.2.3 | Disadvantages | 93 |
| 4.1.3 | Second Design | 93 |
| 4.1.3.1 | Specification of Second Design | 94 |
| 4.1.3.2 | Advantages | 94 |
| 4.1.3.3 | Disadvantages | 95 |
| 4.2 | Design Selection | 95 |
| 4.2.1 | Pugh Method | 95 |
| 4.3 | Development Of Robot | 97 |

| | | |
|-----------|---|-----|
| 4.3.1 | Mechanical Structure | 97 |
| 4.3.1.1 | Robot Base and Body | 97 |
| 4.3.1.2 | Lifting Mechanism | 98 |
| 4.3.1.3 | Robot Gripper | 100 |
| 4.3.1.4 | Wheel Locomotion | 101 |
| 4.3.2 | Electrical Circuit | 102 |
| 4.3.2.1 | Etching Printed Circuit Board | 102 |
| 4.3.2.2 | Wiring the Circuit and Electric Device. | 106 |
| 4.3.3 | Robot Programming | 107 |
| 5. | TESTING, RESULT AND DISCUSSION | |
| 5.1 | Sensor and Circuit Test | 113 |
| 5.2 | Line Following Test | 116 |
| 5.3 | Lifting Test | 119 |
| 5.4 | Discussion | 121 |
| 6. | CONCLUSION AND RECOMMENDATION | |
| 6.1 | Conclusion | 123 |
| 6.2 | Recommendation | 124 |
| | REFERENCES | 125 |
| | APPENDIX | |

LIST OF TABLES

| | | |
|-----------|--|-----|
| Table 2.1 | Types of Lathe Operation. | 29 |
| Table 4.1 | Selection of Design using Pugh Method | 92 |
| Table 4.2 | Weigh for Criteria Selection | 92 |
| Table 4.3 | Function of PIC IO pin at AR40B controller board | 109 |

LIST OF FIGURES

| | | |
|-------------|---|----|
| Figure 1 | Design of an ideal differentially driven robot | 3 |
| Figure 1.1 | Four wheel Mobile Robot | 3 |
| Figure 1.2 | Simple design of wheel robot | 4 |
| Figure 1.3 | All terrain Robot | 5 |
| Figure 1.4 | Gantt Chart for project Planning | 10 |
| Figure 2 | Manual robot from ROBOCON competition | 12 |
| Figure 2.1: | Autonomous robot compete in ROBOCON | 13 |
| Figure 2.2 | Lifting mechanism using Aluminum on the ROBOCON 2008 Autonomous Robot | 14 |
| Figure 2.3 | Gripper made by acrylic sheet on the ROBOCON 2008 manual robot. | 15 |
| Figure 2.4 | Carbon Fiber for robot base | 16 |
| Figure 2.5 | Robot base from HDPE | 17 |
| Figure 2.6 | Robot Structure and gripper from HDPE | 17 |
| Figure 2.7 | Part of an electric motor | 19 |
| Figure 2.8 | A rotating electric motor | 19 |
| Figure 2.9 | The construction of DC Motor | 21 |
| Figure 2.10 | DC Motor | 22 |
| Figure 2.11 | Brushless Motor | 22 |
| Figure 2.12 | The typical radio-controlled (R/C) servo motor. | 23 |
| Figure 2.13 | The internal parts of an R/C servo. The servo consists of a motor, a gear train, a potentiometer, and some control circuits. | 24 |
| Figure 2.14 | A typical unipolar stepper motor. | 26 |
| Figure 2.15 | Inside a unipolar stepper motor .Note the two sets of coils and stators. The unipolar stepper is rally two motors sandwiched together | 26 |
| Figure 2.16 | Drill machine, | 31 |
| Figure 2.17 | Some of the different mechanical fasteners that can be used to hold different pieces of a robot's structure. | 32 |

| | | |
|-------------|---|----|
| Figure 2.18 | Conventional wheel for autonomous robot | 35 |
| Figure 2.19 | Commonly castor wheel use for robots | 35 |
| Figure 2.20 | Universal wheel : (a)simple,(b) double,(c) alternate | 36 |
| Figure 2.21 | Traditional Mecanum wheels | 37 |
| Figure 2.22 | Limit switch | 38 |
| Figure 2.23 | Block diagram of color sensor system | 39 |
| Figure 2.24 | Optical Sensor | 40 |
| Figure 2.25 | Simple direct drive swinging jaw | 41 |
| Figure 2.26 | Simple direct drive through right angle worm drive gear motor | 41 |
| Figure 2.27 | Rack and pinion drive gripper | 42 |
| Figure 2.28 | Reciprocating lever gripper | 42 |
| Figure 2.29 | Linear actuator direct drive gripper | 43 |
| Figure 2.30 | Parallel jaw on linear slides | 43 |
| Figure 2.31 | Parallel jaw using four-bar linkage and linear actuator | 44 |
| Figure 2.32 | Passive parallel jaw using cross tie | 44 |
| Figure 2.33 | Functional Block Diagram of Controller | 45 |
| Figure 2.34 | The structure of the robot control system | 46 |
| Figure 2.35 | Component In PLC | 47 |
| Figure 2.36 | Hardwired logic circuit and its PLC ladder language implementation | 48 |
| Figure2.37 | Burning data process into PIC | 49 |
| Figure 2.38 | PIC Models | 50 |
| Figure 2.39 | PIC 16F Block Diagram | 51 |
| Figure 2.40 | Microchip logo and product | 52 |
| Figure 2.41 | (a)ATMEL logo and (b) microcontroller | 53 |
| Figure 2.42 | A commercial two-wheel differential-drive robot | 54 |
| Figure 2.43 | Differential drive configuration with two drive wheels and a castor wheel | 55 |
| Figure 2.44 | Example of two wheeled robot | 55 |
| Figure 2.45 | The Ackerman Steering types | 56 |

| | | |
|--------------|---|----|
| Figure 2.46 | The Independent Explicit steering schemes | 57 |
| Figure 2.47 | The Frame Articulated steering schemes | 57 |
| Figure 2.48 | The Axle Articulated steering schemes | 58 |
| Figure 2.49 | The Skid steering schemes | 59 |
| Figure 2.50: | The Skid Steer Locomotion | 59 |
| Figure 2.51 | Types of four wheeled locomotion for autonomous robot. | 60 |
| Figure 2.52 | Example drawing using AutoCAD software | 62 |
| Figure 2.53 | Example drawing use CATIA software | 63 |
| Figure 2.54 | Drawing using SolidWork software | 64 |
| Figure 2.55 | Circuit Design using Express PCB software | 65 |
| Figure 2.56 | Window for MPLAB Software | 66 |
| Figure 2.57 | Monster truck robot | 67 |
| Figure 2.58 | Squarebot | 68 |
| Figure 2.59 | Autonomous Robot for ROBOCON 2009 | 69 |
| Figure 2.60 | ROBOCON 2010 gamefield | 71 |
| Figure 2.61 | Khafraa Pyramid | 72 |
| Figure 2.62 | Dimension of Main block | 73 |
| Figure 2.63 | Dimension of Top Block | 73 |
| Figure 3.1 | Flow Chart for Planning Process | 72 |
| Figure 3.2 | Web browser and search engine (a) Mozilla Firefox,(b) Internet Explorer,(c) Yahoo and(d) Google | 78 |
| Figure 3.3 | Flow chart for design and develop mechanical structure | 79 |
| Figure 3.4 | Click on SolidWorks icon. | 82 |
| Figure 3.5 | SolidWork window | 83 |
| Figure 3.6 | Click on New file icon | 83 |
| Figure 3.7 | Select the drawing option | 84 |
| Figure 3.8 | Select the plain surface to start drawing | 84 |
| Figure 3.9 | Start drawing by using the selection icon. | 85 |
| Figure 3.10 | Save the drawing to selection location | 85 |
| Figure 3.11 | Click on MPLAB icon to open software. | 86 |
| Figure 3.12 | Select the project wizard. | 86 |

| | | |
|-------------|---|-----|
| Figure 3.13 | Click the next option in the project wizard window | 87 |
| Figure 3.14 | Select the PIC device | 87 |
| Figure 3.15 | Step to active tool suite | 88 |
| Figure 3.16 | Step to create new project | 88 |
| Figure 3.17 | Create the file for new project | 89 |
| Figure 3.18 | Window of finish after create new file project wizard | 89 |
| Figure 4.1 | Specification of Main Block | 91 |
| Figure 4.2 | First Design for Autonomous Robot | 92 |
| Figure 4.3 | Second Design for Autonomous Robot | 93 |
| Figure 4.4 | Different gripper length | 94 |
| Figure 4.5 | Belting system for autonomous robot. | 95 |
| Figure 4.6 | Robot Base | 97 |
| Figure 4.7 | Robot Body | 98 |
| Figure 4.8 | Lifting Mechanism | 99 |
| Figure 4.9 | Rope path | 99 |
| Figure 4.10 | Rope reel | 100 |
| Figure 4.11 | Robot Gripper | 101 |
| Figure 4.12 | PCB Electrical pads | 102 |
| Figure 4.13 | (a) Transparent sheet on the board, (b) Iron the transparent sheet to leave the carbon. | 103 |
| Figure 4.14 | (a) Pour the Ferric Chloride in the container, (b) Finished PCB circuit. | 103 |
| Figure 4.15 | Voltage regulator circuit | 104 |
| Figure 4.16 | LDR Sensor circuit | 105 |
| Figure 4.17 | LDR Comparator Circuit | 105 |
| Figure 4.18 | Wiring the circuit and electric component. | 106 |
| Figure 4.19 | Wiring the controller board | 107 |
| Figure 4.20 | Example of Starting the program | 108 |
| Figure 4.21 | Declaration for input and output port | 110 |
| Figure 4.22 | Function for LDR Sensor | 111 |
| Figure 4.22 | LDR Sensor Programming | 112 |

| | | |
|-------------|--|-----|
| Figure 5.1 | LDR sensor for the center line of the white line, sensor detected R1, C and L1. | 114 |
| Figure 5.2 | LDR sensor for the left position of the white line, sensor detected L1, L2 and L3. | 115 |
| Figure 5.3 | LDR sensor for the right position of the white line, sensor detected R1, R2 and R3. | 115 |
| Figure 5.4 | LDR comparator for adjustment the sensor. | 116 |
| Figure 5.5 | Robot testing on the white line. | 117 |
| Figure 5.6 | Robot testing on the white line junction | 118 |
| Figure 5.7 | Lifting test. | 119 |
| Figure 5.8 | Lifting test for first level | 120 |
| Figure 5.9 | Lifting test for second level | 120 |
| Figure 5.10 | Lifting test for third level | 120 |
| Figure 5.11 | Lifting the golden top cube. | 121 |

LIST ABBREVIATIONS

| | | |
|---------------|---|--|
| ABU | - | Asia-Pacific Broadcasting Union |
| AC | - | Alternate Current |
| ADC | - | Analog-to-Digital Converter |
| AGV | - | Automated Guided Vehicles |
| API | - | Application programming interfaces |
| BLDCs | - | Brushless direct-current motors |
| CAD | - | Computer Aided Design |
| CATIA | - | Computer Aided Three-dimensional Interactive Application |
| CCP | - | Capture/ Compare/Pulse width modulation |
| Co | - | Company |
| CPU | - | Central Processing Unit |
| DC | - | Direct Current |
| DOF | - | Degree of freedom |
| EEPROM | - | Electrically erasable programmable read-only memory. |
| HDPE | - | High density Polyethylene |
| IDE | - | Integrated Development Environment |
| I/O | - | Input and Output |
| IR | - | Infra red |
| LDR | - | Light dependent resistor |
| LED | - | Light Emmiting Diode |
| NASA | - | National Aeronautics and Space Administration. |
| PC | - | Personal Computer |
| PCB | - | Printed Circuit Board |
| PIC | - | Peripheral Interface Controller |
| PLC | - | Programmable Logic Control |
| PMDC | - | Permanent-magnet direct-current |
| PSM | - | Projek Sarjana Muda |

| | | |
|----------------|---|---|
| QFD | - | Quality Function Deployment |
| RAM | - | Random Access Memory |
| R/C | - | Radio controlled |
| ROBOCON | - | Robot Contest |
| ROI | - | Return on investment |
| ROM | - | Read only memory |
| TV | - | Television |
| USART | - | Universal Synchronous Asynchronous Receiver Transmitter |
| VCRs | - | Video cassette recorder |
| LDR | | Light Dependent Resistor |
| LED | | Light Emmiter Diod |
| V | | Volt |

CHAPTER 1

INTRODUCTION

This chapter reviews the overall content of the project. Introduction of the project includes the project background, problem statements of the project, project aims and objectives, project scopes, robotic technologies and project planning.

1.1 Background

Nowadays, development of technologies especially in robotic are growing in a very fast pace. A variety design of robots has been develop in recent years in order to improve the design and their performance. The most popular robot today is the autonomous robot.

Autonomous robots can be defined as the robot which is programmed for perform task continuously without human guide in unstructured environment. Every robot has different ability to perform task and different robots can be autonomous in different ways.

Autonomous distributed robots have potential to accomplish various missions which conventional robots have not ever done such as cooperative transportation, collection and construction (Inou *et al* 2003). Autonomous robot can perform the task that human cannot perform like space and underwater exploration and tasks that may dangerous for human like handling chemical and explosive materials. Industrial and technical applications of autonomous robots are continuously gaining in importance. They are already widely used for surveillance, inspection and transportation tasks.

One of the main characteristic of an autonomous mobile robot is its ability to move through the operational space, avoiding obstacles and finding its way to the next location, in order to perform its task, capabilities known as localization and navigation. In order to know where to go, the robot must have accurate knowledge of its current location. That means it should use a great variety of sensors, external references and algorithms. In order to move in tight areas and to avoid obstacles mobile robots should have good mobility and ability. These capabilities mainly depend on the wheels design. Research is continuously going on in this field, to improve the autonomous navigation capability of mobile robotic systems (Doroftei *et al* 2007).

Basically, autonomous robot can be developed in two way locomotion. It depends on the requirement whether to develop a legged robot or wheeled robot. Locomotion is most important part in design and develops a robot. In each case, the locomotion system is driven by a motor, which turns a shaft, cam, or lever. This motive force affects forward or backward movement. Wheels are the most popular method for providing robots with mobility. Robot wheels can be just about any size, limited only by the dimensions of the robot and builder outlandish imagination (Mccomb 2006).

Referring the Miles (2002), wheels are pretty much proven in all types of robot applications, from the smallest desktop Sumo machine to the largest mobile industrial robots. Even designers for NASA's Mars-exploration robots gave up on legs and other means of locomotion in favor of wheels.

Robots can have just about any number of wheels, although two is the most common, creating a differentially driven robot.

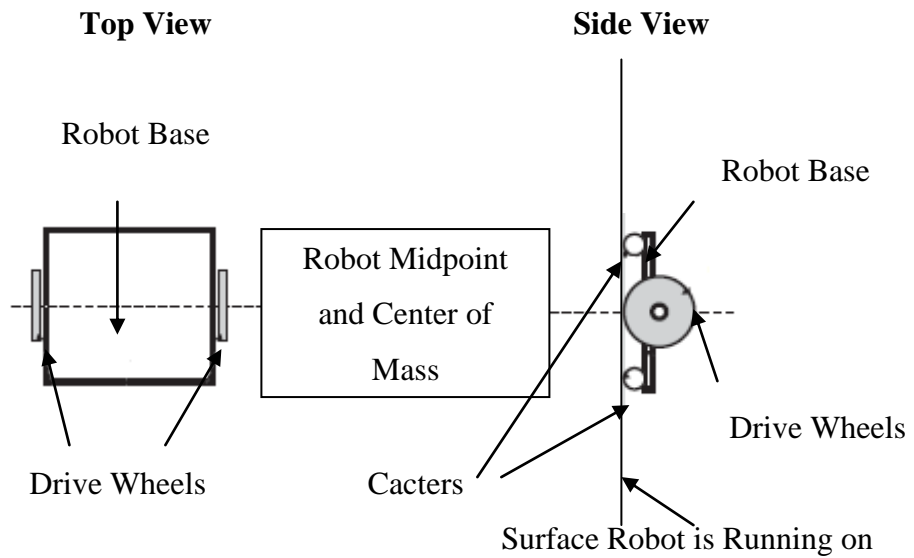


Figure 1.0: Design of an ideal differentially driven robot (Mccomb 2006).

Figure 1 shows the design of an ideal differentially driven robot. In this case, the robot is balanced on the two wheels by one or two free-rolling casters, or perhaps even a third swivel wheel. Besides that, autonomous robot also can be a four wheel locomotion.



Figure 1.1: Four wheel Mobile Robot (www.robots.mobilerobots.com)