

## ROCKERS BOGIE MECHANISAM

MR. MD MAINODDIN<sup>1</sup>, L.Srinivas<sup>2</sup>, CH.Shashank Reddy<sup>3</sup>, S.Abhishek sharma<sup>4</sup>,  
N.Tadesh Naik<sup>5</sup>, K.Shivasai<sup>6</sup>

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### ABSTRACT:

It is obvious that rovers are important vehicles of today's solar system exploration. Most of the rover designs have been developed for Mars and Moon surface in order to understand the geological history of the soil and rocks. Exploration operations need high speed and long-distance traversal in a short mission period due to environmental effects, climate and communication restrictions. Several mechanisms have been suggested in recent years for suspensions of rovers on rough terrain. Although their different mechanisms have found a wide spread usage in mobile robotics, their low operation speed is still a challenging problem. In this research, a new suspension mechanism has been designed and its kinematic analysis results were discussed. Standard rocker-bogie suspension mechanism, which has been developed in the late 1990's, has excellent weight distribution for different positions on rough terrain. New design, mostly similar to rocker-bogie suspension system, has a natural advantage with linear bogie motion which protects the whole system from getting rollover during high speed operations. This improvement increases the reliability of structure on field operations and also enables the higher speed exploration with same obstacle height capacity as rocker-bogie

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### INTRODUCTION:

NASA recently started an ambitious exploration program of Mars. Pathfinder is the first over explorer in this program. Future rovers will need to travel several kilometers over periods of months and manipulate rock and soil samples. The term "rocker" describes the rocking aspect of the larger links present each side of the suspension system and balance the bogie as these rockers are connected to each other and the vehicle chassis through a modified differential. In the system, "bogie" refers to the conjoining links that have a drive wheel attached at each end. Bogies were commonly used to bare loading as tracks of army tanks as idlers distributing the load over the terrain. Bogies were also quite commonly used on the trailers of semitrailer trucks as that very time the trucks will have to carry much heavier load. As accordance with the motion to maintain center of gravity of entire vehicle, when one rocker moves upward, the other goes down. The chassis plays vital role to maintain the average pitch angle of both rockers by allowing both rockers to move as per the situation. The physics of these rovers is quite complex. To design and control these analytical models of how the rover interacts with its environment are essential. Models are also needed for rover action planning. Simple mobility analysis of rocker-bogie vehicles have been developed and used for design evaluation in the available published works. The rocker-bogie configuration is modeled as a planer system. Improving the performances of a simpler four wheel rover has also been explored.

### LITERATURE REVIEW :

The concept of our research work is to create a rocker bogie drive system based on those of NASA. NASA developed the rocker-bogie suspension system for their rovers and was implemented in the Mars Pathfinder's and Sojourner rover. The rocker-bogie suspension system passively keeps all six wheels on the robot in contact with the ground even on uneven

surfaces. This creates for great traction and manoeuvrability (Harrington & Voorhees). The rocker-bogie suspension mechanism which was currently NASA's approved design for wheeled mobile robots, mainly because it had study or resilient capabilities to deal with obstacles and because it uniformly distributes the payload over its 6 wheels at all times.

It also can be used for other purposes to operate in rough roads and to climb the steps. It was having lots of advantages but one of the major disadvantages is the rotation of the mechanism when and where is required. The rotation can be possible by providing individual motors to individual wheels which causes arise in cost and complicity in design. Here an attempt was made to modify the existing design by incorporating a gear type steering mechanism which will be operated by a single motor which simplifies the design as well as the total cost and operating cost of the mechanism. In this work the proposed steering mechanism was designed and the modeling was done in CATIA (V-5) and the same was analyzed for static analysis for the proposed torque condition of the motor in ANSYS. All the results in the analysis were analyzed for static analysis [1]. The researchers discusses the concept and parameter design of a Robust Stair Climbing Compliant Modular Robot, capable of tackling stairs with overhangs. Modifying the geometry of the periphery of the wheels of our robot helps in tackling overhangs. Along with establishing a concept design, robust design parameters were set to minimize performance variation. The grey based Taguchi Method was adopted for providing an optimal setting for the design parameters of the robot. The robot prototype was shown to have successfully scaled stairs of varying dimensions, with overhang, thus corroborating the analysis performed [2]. An analysis method to make the rocker bogie mechanism can climb up a stair was achieved in the work. The east coast of Malaysia faced a massive flood from heavy downpour, leading to huge flood damage and caused irreparable loss to life and property. The flood carries the debris, soil and trees along their path, damaging the road and building structure, leaving the road become uneven. This situation gives difficulty to task force bearing aids during the post disaster management. The research paper proposed an intelligent inclined motion control of an amphibious vehicle while moving on uneven terrain surface [3]. The research paper deals with the designing and modeling of stair climbing robot based on the well-known rocker bogie mechanism in Ansys rigid body dynamics module. The robots often suffer from undesired phenomenon slip, sticking and floating while climbing steps and stairs, which may cause instability of the mobile robot. The Taguchi method was used to chosen as an optimization tool to make trajectory of center of mass close to straight line while all wheels keep in contact with ground during climbing stairs. Taguchi method was adopted due to its simplicity and cost effectiveness both in formulating the objective function and satisfying multiple constraints simultaneously. In the Optimization, Seven kinematic parameters of rocker bogie mechanism were optimized which include four link lengths ( $l_1, l_2, l_3$ ) and three wheel radius ( $R_1, R_2, R_3$ ). The kinematic Model of proposed mechanism was built and it was simulated in ANSYS Rigid body dynamics. Three different shapes of typical stairs were selected as user conditions to determine a robust optimal solution. The result obtained shows the variation of center of mass position with time, variation of velocity of joint with time, variation of force with time [5]. It was basically a suspension arrangement used in mechanical robotic vehicles used specifically for space exploration. The rocker-bogie suspension based rovers has been successfully introduced for the Mars Pathfinder and Mars Exploration Rover (MER) and Mars Science Laboratory (MSL) missions conducted by apex space exploration agencies throughout the world. The proposed suspension system was currently the most favored design for every space exploration company

indulge in the business of space research. The motive the research initiation was to understand mechanical design and its advantages of Rocker- bogie suspension system in order to find suitability to implement it in conventional loading vehicles to enhance their efficiency and also to cut down the maintenance related expenses of conventional suspension systems [6]. The world market of mobile robotics was expected to increase substantially in the next 20 year, surpassing the market of industrial robotics in terms of units and sales. Important fields of application are home land security, surveillance, demining, reconnaissance in dangerous situations, and agriculture. The design of the locomotion systems of mobile robots for unstructured environments was generally complex, particularly when they were required to move on uneven or soft terrains, or to climb obstacles. The three main categories of locomotion systems (wheeled – W, tracked – T and legged – L) and the four hybrid categories that can be derived by combining these main locomotion systems were discussed with reference to maximum speed, obstacle-crossing capability, step/stair climbing capability, slope climbing capability, walking capability on soft terrains, walking capability on uneven terrains, energy efficiency, mechanical complexity, control complexity and technology readiness. The current and future trends of mobile robotics were discussed [7]. The optimization of a particular suspension system known as the “rocker-bogie” for our Mars Rover. This type of mechanism has been used on most of the rovers on Mars and has proved to be a simple and elegant design. A Genetic Algorithm was implemented and used to optimize the geometry and kinematics of the rovers wheel suspension system subject to the defined performance metrics. This work shows the effectiveness of the optimization of a rocker-bogie suspension system using a Genetic Algorithm. It also reveals that the resulting system meets all constraints and that significantly reduces the error of individual performance metrics and the overall system. It was shown that the overall fitness of the rover suspension system can be increased by an average of 28% after 100 iterations compared to an initial guess. All performance metrics defined were improved significantly throughout the optimization. The method can be applied to different types of rovers in order to optimize the wheel suspension mechanism’s geometry [8]

## **DESIGN OF ROCKER BOGIE :**

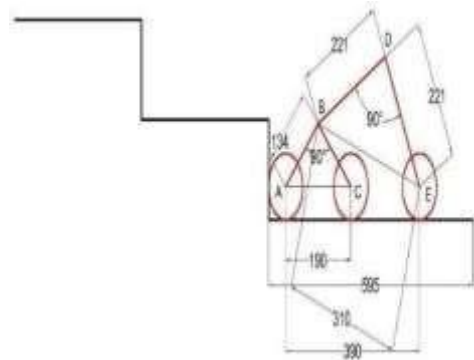
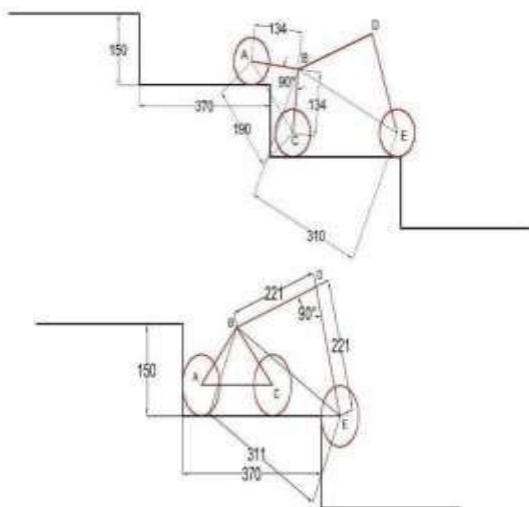
The important factor in manufacturing of rocker bogie mechanism is to determine the dimensions of rocker and bogie linkages and angles between them. The lengths and angles of this mechanism can be changed as per requirement. In the work aim is to manufacture the rocker bogie mechanism which can overcome the obstacles of 150 mm height (like stones, wooden blocks) and can climb over stairs of height 150 mm. Also another target is to climb any surface at an angle of  $45^\circ$ . To achieve the above targets we had design the rocker-bogie model by assuming stair height 150 mm and length 370 mm. Using Pythagoras theorem, find the dimensions of the model. It have both angles of linkages are  $90^\circ$ .

**Design calculation** The objective of the research work is stair climbing. To achieve proper stair climbing the dimensions of linkages should be proper. Assume the stair height and length 150 mm and 370 mm respectively. To climb stairs with higher stability, it is required that only one pair of wheel should be in rising position at a time. Hence to find dimension of bogie linkages, first pair of wheels should be placed at horizontal position means at the end of the rising as shown in Fig.1. And second pair should be placed just before the start of rising. There should be some distance between vertical edge of stair and second pair of wheel to striking of wheels. By considering all these lengths and angles we have drawn whole mechanism. Above Fig. 3, shows all dimensions of robot. We take acrylic width is 40 mm suitable for drilling 15

mm diameter holes. After the calculation of triangle dimension using CAD software 2D drawing is prepared as per calculated dimension and same drawing views are shown in Fig. 4 Now, need to obtain the distance between first and second wheel through CAD software (190 mm). Considering the right angled triangle ABC, Using Pythagoras in  $\Delta ABC$  (Fig. 2.) assume lengths AB and BC is x.  $AC^2 = AB^2 + BC^2$   $190^2 = x^2 + x^2$   $190^2 = 2x^2$   $x = 134$  mm Hence, AB = BC = 134 mm (Fig. 2.) Similarly, to find dimensions for rocker linkages first two wheel pairs should be placed at horizontal position. Third wheel pair should nearly complete its rising before starting of rising of first pair of wheel. By placing wheel in such manner, we obtained dimension of link BC (311mm). Now consider  $\Delta BDE$  (Fig. 3.),  $BE^2 = BD^2 + DE^2$   $311^2 = 2y^2$   $y = 221$  mm Hence, BD = DE = 221 mm (Fig. 3.)

**Design & Selection of Wheel** Design of wheel is required at velocity up to 0.5 m/s. Assume speed is 60 - 100 rpm motor. Using velocity relation velocity is calculated for assumed speed. Using calculated velocity value need to find out diameter of wheel is 95.35 mm. Hence we select the wheel of 100 mm diameter (standard wheel). Selection of rubber thread bonded to the wheel makes it light weight and durable, provides excellent traction, friction. These plastic wheels (as shown in Fig. 5.) offer a low cost solution that is durable enough for a combat robot yet still light enough to be practical. For robot used six wheels. Wheel Diameter: 100 mm Wheel Width : 20 mm Shaft Diameter : 6mm Selection of acceleration for robot For a typical robot on flat terrain, it's needed to take acceleration about half of maximum velocity. Maximum velocity of robot is 0.5 m/s. Hence the acceleration of robot will be  $0.5/2$  means  $0.25 \text{ m/s}^2$ . This means it would take 2 seconds to reach maximum speed. If robot is going up inclines (as per Equ. No.1) or through rough terrain, you will need a higher acceleration due to countering gravity. We needed to climb the angle up to  $45^\circ$ . Hence, **Acceleration of inclines** =  $9.81 * \sin \text{ angle of inclination} * \pi 180 (1) = 0.121 \text{ m/s}^2$  Total Acceleration =  $0.25 + 0.121 = 0.371 \text{ m/s}^2$

**IV.PERFORMANCE AT DIFFERENT CONDITIONS** As per the ground level experimentation by rocker bogie manufactured; tested found that the performance satisfactory below are the result are shown see fig. 6- 10 on different obstacle and different surfaces.



## CONCLUSION :

This work shows how rocker bogie system works on different surfaces. As per the different weight acting on link determines torque applied on it. By assuming accurate stair dimensions, accurately dimensioned rocker bogie can climb the stair with great stability. The design and manufactured model can climb the angle up to  $45^\circ$ . Also we tested for the Web cam with AV recording mounted on rocker bogie system and found satisfactorily performance obtains during this test camera has rotated around  $360^\circ$ . During stair climbing test for length less than 375 mm (15 inch) system cannot climb the stair. It can be possible to develop new models of rocker bogie which can climb the stairs having low lengths. in the areas are IC Engine, automobile, fuel additives, and lubricants.

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