

CHASSIS - In-Flight Self-Stabilizing Rover

Karan Gill; Hamza Ahad; Msalam Laham; Diganta Sengupta; Gurjiwan Brar; Tony Dong
Department of Mechanical & Manufacturing Engineering | University of Calgary

Introduction

• Problem Statement :

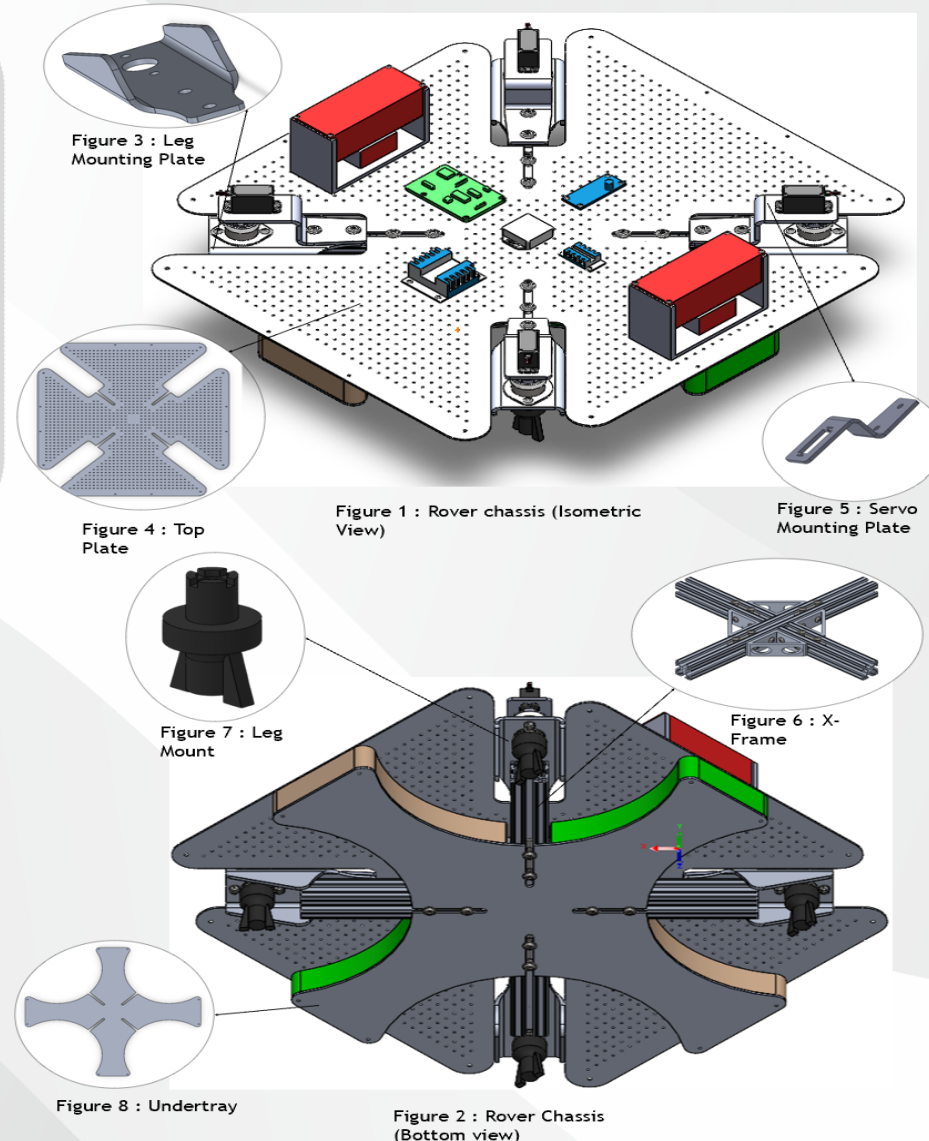
Current Search & Rescue rovers are restricted by having to be placed down upright. A self-stabilizing rover that will allow people to throw it into hard to access areas without worrying about landing upside down would be greatly beneficial

• Customer Requirements:

- Individual hub motors for every wheel
- Independently Steerable
- Lightweight (less than 4kg)
- Withstand drop from 2m
- Dimensions (LxWxH): 650mm x 500mm x 350 mm

Features

- **X-frame chassis** for symmetry and strength.
- **Aluminum extrusions** for a modular design
- Interchangeable **leg mount** for mounting suspension components or connecting straight to the wheel
- **Top plate** manufactured using 5052 Aluminum for high corrosion resistance and workability with 3mm grid pattern holes for mounting electronic components
- **Undertray** to protect the rover's frame and electronics from impact and debris
- Steering Mechanism is obtained using servomotors and the impact force observed by servomotor gear is reduced using bearings



Results

- Developed mounting locations and space for electrical and suspension components
- SolidWorks simulation was used for stress analysis
 - X-frame successfully passed load test using a static normal load of **500 N**
 - This gives an estimated maximum load capacity of **51.2 kg**
- Final chassis weight : **7.6 kg.**
- Final chassis dimensions (LxWxH) : **580mm x 615mm x 123mm**

Discussion

- Design Limitations:
 - Cannot be thrown upside down
 - Landing on the side will likely result in electrical component damage
- Potential future improvements:
 - Decrease chassis size to help reduce weight
 - Develop a roll cage that protects from roll-overs or side landings

REFERENCES

1. A. Ramirez, "Project 1 and 2 - Self-Stabilizing Robot Car in flight," University of Calgary, Calgary, 2022.
2. D. Gonzalez, M. Lesak, A. Rodriguez, J. Gysmerman, C. Korpela, "Dynamics and Aerial Attitude Control for Rapid Emergency Deployment of the Agile Ground Robot AGRA," IEEE International Conference on Intelligent Robots and Systems (IROS), pp. 1-8, 2022.
3. "Logos," University of Calgary, 23-Mar-2023. [Online]. Available: <https://www.ucalgary.ca/brand/brand-standards/logos>. [Accessed: 28-Mar-2023]