

# Design of Rocker Bogie Mechanism

Prof.Sandeep Tekale<sup>1</sup>, Ansari Mohd Yasir Afroz Ahmed<sup>2</sup>, Ansari Mohd Arquam Raees Ahmed<sup>3</sup>, Ansari Shah Aalam Md Akram<sup>4</sup>, Ansari Sifat Ahmed Mukhtar Ahmed<sup>5</sup>  
<sup>1, 2, 3, 4, 5</sup> Everest College Of Engineering And Technology

**Abstract-** *Rocker bogie are important for conducting in-situ scientific analysis of objectives that are separated by many meters to tens of kilometers. Current mobility designs are complex, using many wheels or legs. They are open to mechanical failure caused by the harsh environment on Mars. A four wheeled rover capable of traversing rough terrain using an efficient high degree of mobility suspension system. The primary mechanical feature of the rocker bogie design is its drive train simplicity, which is accomplished by using only two motors for mobility. Both motors are located inside the body where thermal variation is kept to a minimum, increasing reliability and efficiency. Four wheels are used because there are few obstacles on natural terrain that require both front wheels of the rover to climb simultaneously. A series of mobility experiments in the agriculture land, rough roads, inclined, stairs and obstacles surfaces concluded that rocker bogie can achieve some distance traverses on field.*

**Keywords-** Rocker bogie; Wheel type mobile robot; Stair climbing; Rover..

## I. INTRODUCTION

Over the past decade, the rocker-bogie suspension design has become a proven mobility application known for its superior vehicle stability and obstacle-climbing capability. Following several technology and research rover implementations, the system was successfully flown as part of Mars Pathfinder's Sojourner rover. When the Mars Exploration Rover (MER) Project was first proposed, the use of a rocker-bogie suspension was the obvious choice due to its extensive heritage. The challenge posed by MER was to design a lightweight rocker-bogie suspension that would permit the mobility to stow within the limited space available and deploy into a configuration that the rover could then safely use to egress from the lander and explore the Martian surface. When building a robot you'd like it to be as simple as possible. In most cases you'd never need a suspension system, but there were several instances when a suspension system cannot be avoided. The term "bogie" refers to the links that have a drive wheel at each end. Bogies were commonly used as load wheels in the tracks of army tanks as idlers distributing the load over the terrain. Bogies were also quite commonly used on the trailers of semi-trailer trucks. Both applications now prefer trailing arm suspensions. The rocker-

bogie design has no springs or stub axles for each wheel, allowing the rover to climb over obstacles, such as rocks, that are up to twice the wheel's diameter in size while keeping all six wheels on the ground. As with any suspension system, the tilt stability is limited by the height of the centre of gravity.

## II. 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 complexity 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.

## III. DISCUSSION

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°. 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  $90^\circ$ . 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.

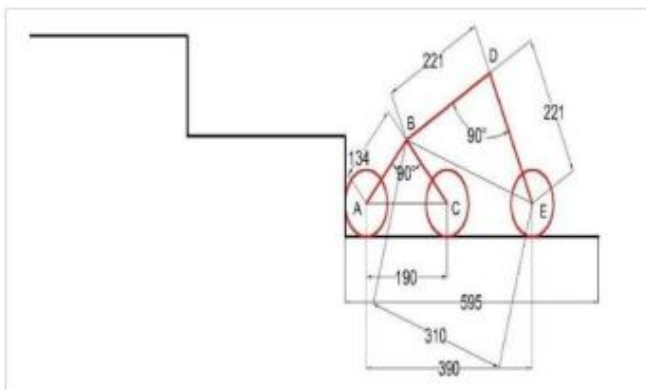


Fig. 1. Cad drawing for first triangle

#### IV. 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

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