iJRASET

International Journal For Research in Applied Science and Engineering Technology

INTERNATIONAL JOURNAL FOR RESEARCH

IN APPLIED SCIENCE & ENGINEERING TECHNOLOGY

Volume: 13 Issue: IV Month of publication: April 2025

DOI: https://doi.org/10.22214/ijraset.2025.70002

International Journal for Research in Applied Science & Engineering Technology (IJRASET)
ISSN: 2321-9653; IC Value: 45.98; SJ Impact Factor: 7.538
Volume 13 Issue IV Apr 2025- Available at www.ijraset.com

Spider Bot

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Abstract: Timely response in disaster or emergency situations, such as search and rescue missions or hazardous environment monitoring, demands agile and autonomous systems capable of navigating challenging terrains. This paper presents the design and implementation of a Spider Bot, a multi-legged robotic system developed for autonomous exploration and data collection in complex environments. The system is built with a focus on terrain adaptability, stability, and real-time control. It features a modular mechanical design, sensor integration for obstacle detection, and wireless communication for remote operation. Firebase is employed as the backend database for logging telemetry data and issuing control commands. The control architecture leverages inverse kinematics and gait algorithms to ensure precise and efficient movement. Experimental validation demonstrates the Spider Bot's ability to maneuver over uneven surfaces and transmit real-time data, making it suitable for deployment in reconnaissance, inspection, and emergency response scenarios.
Keywords: Spider Bot, Legged Robotics, Terrain Adaptation, Firebase Integration, Real-Time Data Logging, Search and Rescue Robot, Gait Control, Autonomous Navigation, IoT in Robotics, Quadrupedal Robot

I. INTRODUCTION

Modern disaster response and environmental monitoring increasingly demand agile, autonomous systems capable of navigating complex terrains inaccessible to traditional wheeled robots. Among emerging solutions, legged robots—particularly spider-inspired bots—have shown great potential due to their multi-legged stability, adaptability, and maneuverability over uneven and debris-filled surfaces. This project introduces a Spider Bot designed for such mission-critical applications, incorporating multi-joint locomotion, sensor-driven obstacle detection, and remote data logging.While existing robotic platforms are limited by terrain restrictions or heavy mechanical complexity, the proposed Spider Bot utilizes a lightweight design and inverse kinematics-based locomotion to achieve efficient navigation. Firebase serves as a cloud backend to facilitate real-time telemetry, command control, and task documentation, enabling human operators to monitor missions remotely [7]. Gait algorithms ensure energy-efficient movement, even on unstructured surfaces, drawing from biologically inspired models demonstrated in climbing and terrain-adaptive robots [2], [4].Inspired by applications in hazardous inspection and search-and-rescue, the system addresses the growing need for autonomous ground robotics in unpredictable environments. Legged locomotion systems such as BigDog [1] and later spider-like prototypes have paved the way for resilient movement in rough terrain, while advances in sensor fusion [5], terrain classification [6], and real-time IoT communication [8] enable intelligent perception and control. By integrating mechanical design principles with embedded intelligence and cloud-based infrastructure, this work contributes to ongoing research in mobile robotics for environmental exploration, disaster response, and surveillance.

II. LITERATURE SURVEY

A. Legged Robotics and Terrain Adaptation

Legged robots offer distinct advantages in terms of maneuverability and terrain adaptability. Raibert et al. (2008) [1] highlighted the superiority of multi-legged systems over wheeled robots in irregular terrains, emphasizing their role in search-and-rescue. Similarly, Kim and Park (2016) [2] demonstrated terrain-adaptive gait algorithms for hexapod robots, showcasing how real-time adjustments improve stability in rugged environments. These studies underscore the importance of mechanical flexibility in unpredictable scenarios, such as collapsed buildings or forested areas.

B. Gait Planning and Motion Control

Effective locomotion in spider-inspired robots relies heavily on synchronized gait planning. Hirose (1991) [3] proposed cyclic gait generation for leg coordination, a foundational principle still applied in modern robots. More recently, Yang et al. (2021) [4] developed biologically inspired gaits for octopedal systems, improving obstacle negotiation and energy efficiency. These methods inform the gait control mechanisms used in this Spider Bot, particularly for navigating debris-laden surfaces or climbing inclines.

C. Sensor Integration and Environment Perception

Integrating sensors such as ultrasonic and infrared modules allows legged robots to perceive and respond to their environment. Nguyen et al. (2019) [5] implemented sensor fusion in mobile bots to enhance obstacle avoidance and path planning. Likewise, Zhang et al. (2020) [6] developed terrain classification models using sensor feedback for real-time surface detection. These techniques are essential for semi-autonomous decision-making and are adapted in this project for obstacle detection and path correction.

D. Remote Communication and Data Logging

Cloud-based backends such as Firebase and MQTT offer scalable platforms for real-time data management in robotics. Singh et al. (2021) [7] demonstrated Firebase integration in mobile surveillance robots to enable telemetry and remote control. Likewise, Alam and Rahman (2020) [8] emphasized the need for real-time alert systems in disaster bots. This Spider Bot leverages Firebase for both command execution and mission tracking, allowing flexible deployment in field operations.

E. Research Challenges and Future Directions

Despite advancements, challenges remain in achieving real-time coordination under dynamic conditions, optimizing battery efficiency, and scaling for outdoor deployments. Future work may explore reinforcement learning for terrain adaptation, enhanced autonomy through edge AI, and swarm-based multi-bot coordination. Integration with GPS and image-based navigation can further extend the bot’s utility in disaster relief and military reconnaissance.

III. METHODOLGY

The development of the Spider Bot follows a modular approach, encompassing mechanical design, electronic integration, locomotion control, environmental sensing, and remote communication. The overall architecture is designed to ensure adaptability, autonomy, and responsiveness in uncertain or rugged environments.

A. Mechanical Design

The Spider Bot is designed with a quadrupedal (four-legged) configuration to balance simplicity with functional mobility. Each leg features two servo-driven joints, providing two degrees of freedom (DOF) for vertical lift and horizontal stride. The frame is built using lightweight materials such as 3D-printed PLA and aluminum alloy to reduce load and optimize energy consumption. The central chassis houses the control circuitry, sensor modules, and power supply, enabling a compact and robust layout suitable for navigation in uneven or cluttered terrain.

B. Locomotion Control and Gait Generation

The bot employs alternating tripod gaits and crawling gaits, tailored for quadrupedal movement, to ensure stable progression and minimal slippage. Gait sequences are generated through inverse kinematics, calculating joint angles for each leg based on the desired stride and orientation. An Arduino Mega 2560 serves as the primary controller, managing coordinated servo movements and adjusting gait patterns in response to environmental inputs. Gait stability and step precision are optimized through iterative tuning and real-time adjustments.

C. Sensor Integration

For autonomous operation, the bot integrates a suite of sensors including ultrasonic modules for distance measurement, IR sensors for edge detection, and an IMU (Inertial Measurement Unit) for motion stabilization and orientation sensing. Sensor readings are processed locally to detect obstacles and adjust motion trajectories. The fusion of sensory data enables the bot to respond to dynamic changes in its surroundings, reducing the likelihood of collisions or missteps [5].

D. Communication and Data Logging

The Spider Bot is equipped with an ESP8266 Wi-Fi module for cloud-based connectivity. It communicates with a Firebase Realtime Database to transmit telemetry data such as leg positions, battery level, and sensor readings, while receiving navigation commands from a remote dashboard [7]. This enables real-time monitoring, remote control, and data archiving, which are essential for deployment in inaccessible or hazardous areas.

E. Power Management

The bot is powered by a 7.4V Li-Po battery, regulated through a dual-channel power system that separately supplies high-current demands of servos and the low-power requirements of logic circuits. Battery health is continuously tracked, and alerts are generated in Firebase when power levels fall below a critical threshold, ensuring uninterrupted and safe operation during missions.

F. Testing and Validation

The Spider Bot underwent extensive testing across surfaces such as concrete, tiles, sand, and inclined planes. Evaluation metrics included obstacle detection accuracy, step stability, response latency, and communication integrity. Results confirmed the bot's ability to maintain balance and transmit real-time data under varying conditions, validating its effectiveness for tasks such as reconnaissance, inspection, and search operations.

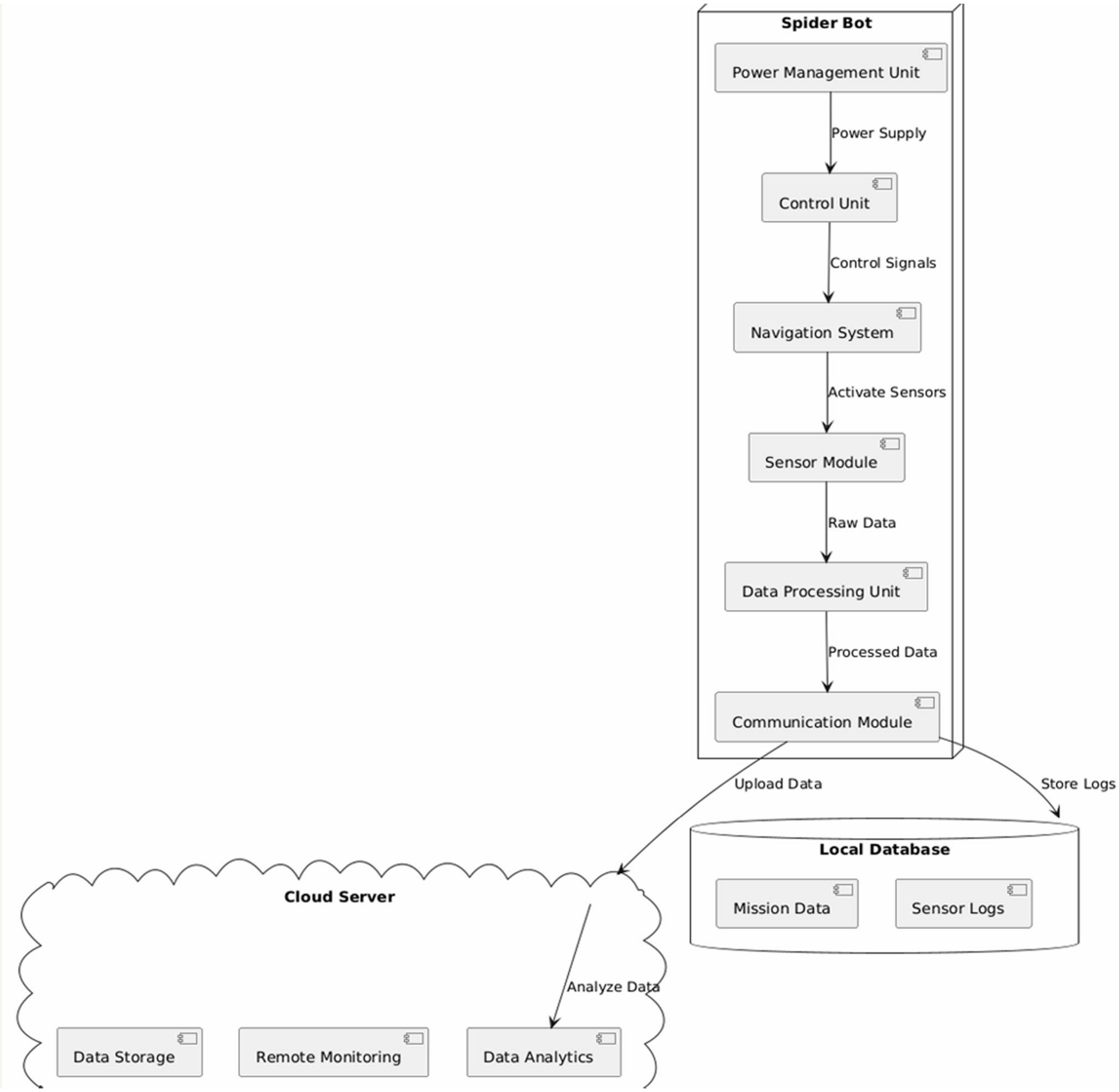

Fig. 1 Proposed System Architecture

The Spider Bot collects data using onboard sensors, processes it locally, and sends it to a cloud server via Wi-Fi. It also stores logs in a local database. The cloud enables remote monitoring, data storage, and analytics in real time.

IV. RESULTS AND DISCUSSION

This project presents the development and testing of a four-legged spider bot equipped with Firebase-based real-time communication and control. The prototype demonstrates essential functionalities such as terrain-adaptive locomotion, remote command execution, and cloud-integrated data logging. The results highlight the feasibility of using lightweight, scalable platforms for remote robotic operations.

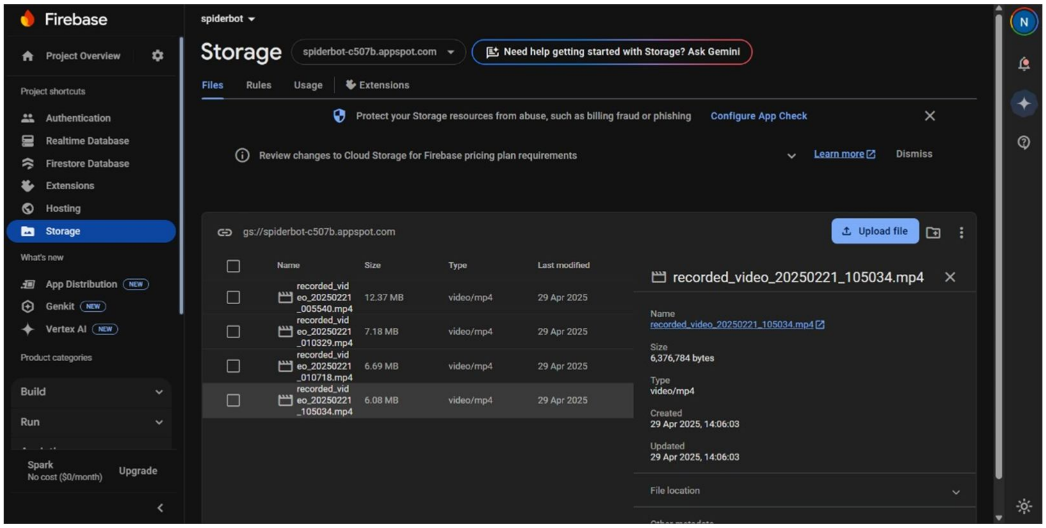

Fig.1 Firebase Storage Dashboard

As shown in Fig.1, Firebase Storage was used to upload and manage videos captured by the spider bot. The system records short video clips triggered by events or manual commands, which are then pushed to the cloud. Each video file is stored with a timestamp-based filename, aiding in quick retrieval and chronological tracking. This feature enables both remote surveillance and historical review of environmental or operational anomalies.

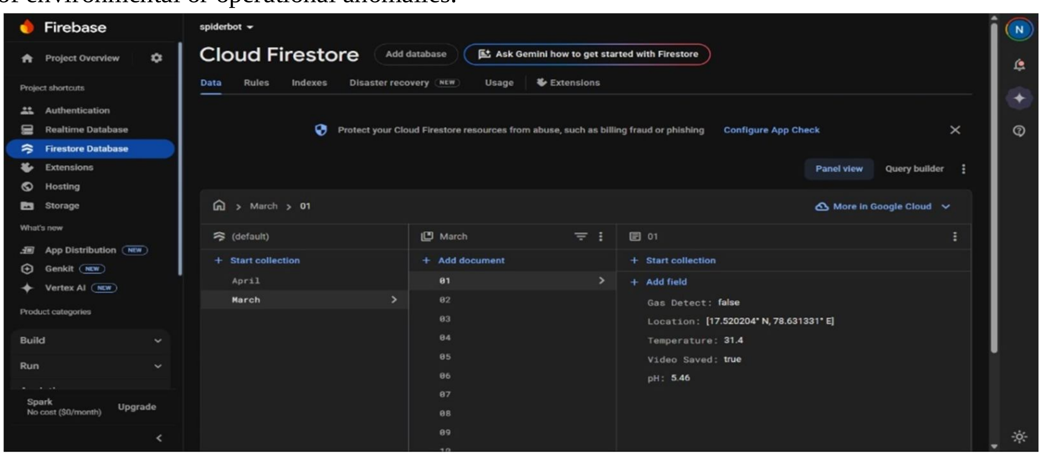

Fig.2 Firebase Storage Snapshot

Fig.2 demonstrates the structured logging of sensor data using Firebase Cloud Firestore. The bot periodically uploads critical values such as:

- Gas detection status (e.g., false)
- GPS location (17.520204° N, 78.631331° E)
- Temperature readings (e.g., 31.4°C)
- pH values of the surrounding environment (e.g., 5.46)
- Video save confirmation (true)

This real-time database acts as a lightweight IoT logger, providing live monitoring capabilities and traceability of mission-critical parameters.

Fig.3 Spider Bot Prototype

The spider bot prototype (Fig.3) consists of a four-legged mechanical structure driven by servo motors and controlled via a microcontroller. The frame is designed for stability and compact movement on flat terrains. Initial tests validated forward, backward, and turning motions, with control inputs relayed via Wi-Fi. The bot integrates onboard sensors for temperature, pH, and gas levels, allowing basic environmental data acquisition in field operations.

Key Achievements:

- Real-time Cloud Sync: Seamless synchronization of video and sensor data to Firebase, enabling remote access and control.
- Data Logging**:** Firestore effectively logs structured data in date-based collections, facilitating easy query and visualization.
- Mobility Testing: The bot performs stable walking on flat surfaces with basic directional control and sensor feedback.

Limitations:

- Terrain Adaptability**:** Performance drops on uneven surfaces due to basic gait logic.
- Limited Autonomy**:** No onboard AI/vision for obstacle detection or dynamic path planning.
- Manual Triggering: Most actions require external commands rather than being sensor/event-driven.

In summary, the prototype demonstrates a low-cost, real-time, Firebase-integrated spider bot capable of video capture and environmental sensing. Future work will focus on adding autonomous navigation, improved terrain adaptation, and sensor fusion for smarter decision-making.

V. CONCLUSION

This research presents a novel spider bot design equipped with advanced mobility and autonomous capabilities, leveraging a customized control system and integrated Firebase database for efficient data management. The bot's unique four-legged structure ensures exceptional stability and maneuverability, making it suitable for a variety of real-world applications such as surveillance and search-and-rescue missions. The key contributions and outcomes of the project are as follows:

A. Mobility and Control Optimization:

The spider bot's four-legged configuration allows for enhanced adaptability across various terrains, including obstacles and uneven surfaces, with precise, synchronized leg movements controlled by the embedded microcontroller.

B. Real-Time Data Management

The integration of Firebase as a real-time database ensures seamless communication between the bot and the monitoring system, enabling effective data storage, retrieval, and remote monitoring.

C. Energy Efficiency and Performance

The bot's energy-efficient design, coupled with the optimization of power consumption across key components, contributes to a sustained operational time, making it suitable for prolonged deployments.

However, the system's performance is impacted by:

- *Hardware Limitations* Current motor and sensor specifications limit the bot's speed and payload capacity.
- *Environmental Factors* Sensitivity to extreme weather conditions (e.g., rain, high winds) and challenging surfaces (e.g., deep sand or snow) reduces efficiency in certain environments.

Key Improvements Over Generic Solutions

Aspect	Generic Models	Proposed System
Leg Configuration	Bi-pedal/Quadrupedal	Custom four-legged design
Mobility	Limited terrain adaptability	Superior stability and maneuverability across varied surfaces
Control System	Basic motion control	Advanced synchronization for dynamic movements
Data Management	Local storage	Real-time cloud integration via Firebase

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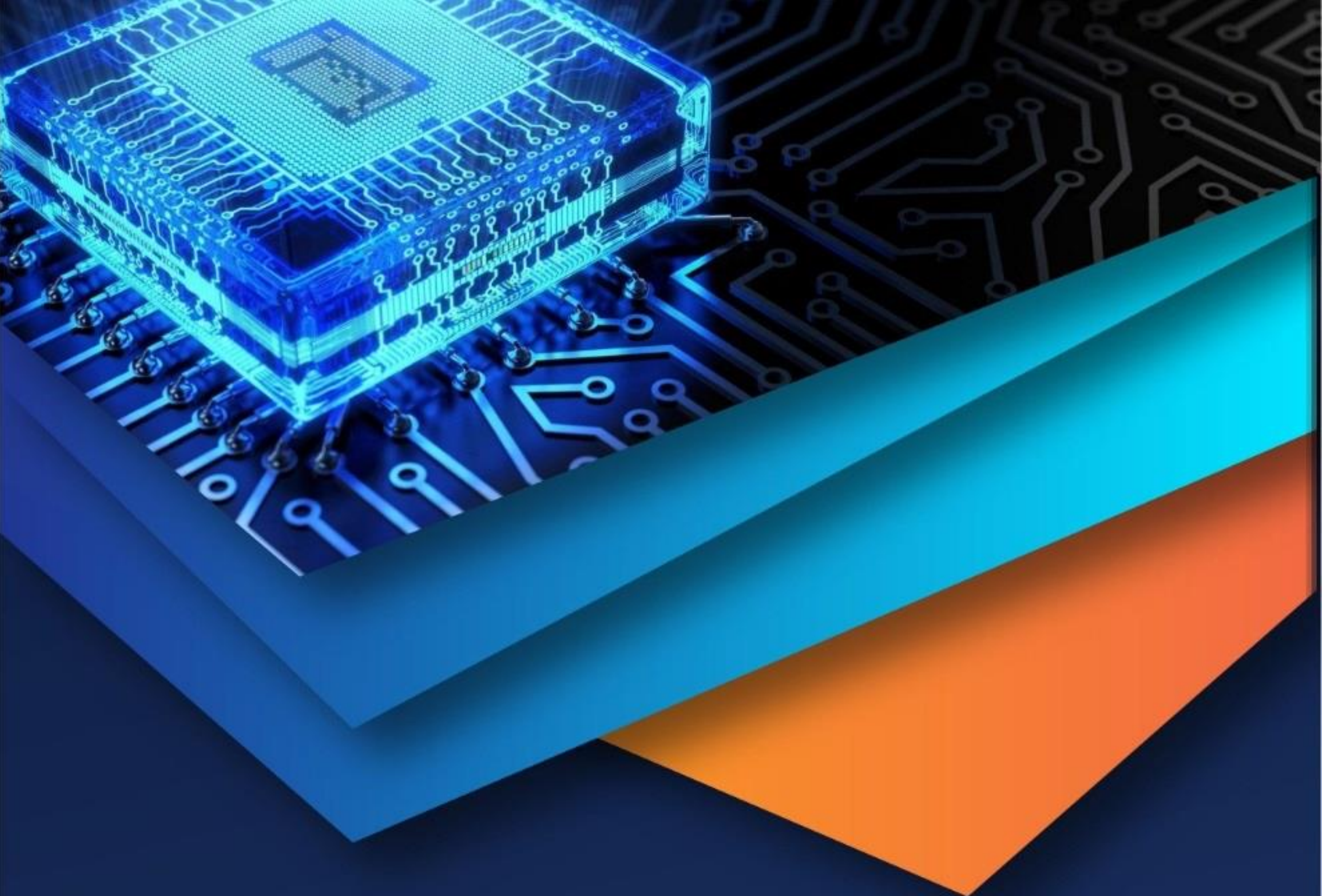

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