

Research on autonomous movement of the rescue robot : MINORI 2002

Satoshi Muraishi, Hiroshi Masui, Takezou Suzuki, Yuuzou Honda

Nippon Institute of Technology HV
Intelligent Agent Research
Gakuendai4-1, Miyasiro, Saitama 345-8501, Japan

ci985260@uhura.nit.ac.jp
<http://www.nit.ac.jp/>

We introduce ourselves with description of team background, image of robot system, photos of member, the outline system and specification of robot as a participant of RoboCup 2002 Rescue Robot Competition.

1 Introduction

The severe Hanshin - Awaji earthquake struck our Koube area in the January of 1995 and it was killed on the race of 6,500.

When we got such a disaster up, this research was also begun one person to the - that saves many victims.

We made a total autonomy rescue robot to a robot so that we might prevent the disaster of the second of rescue person.

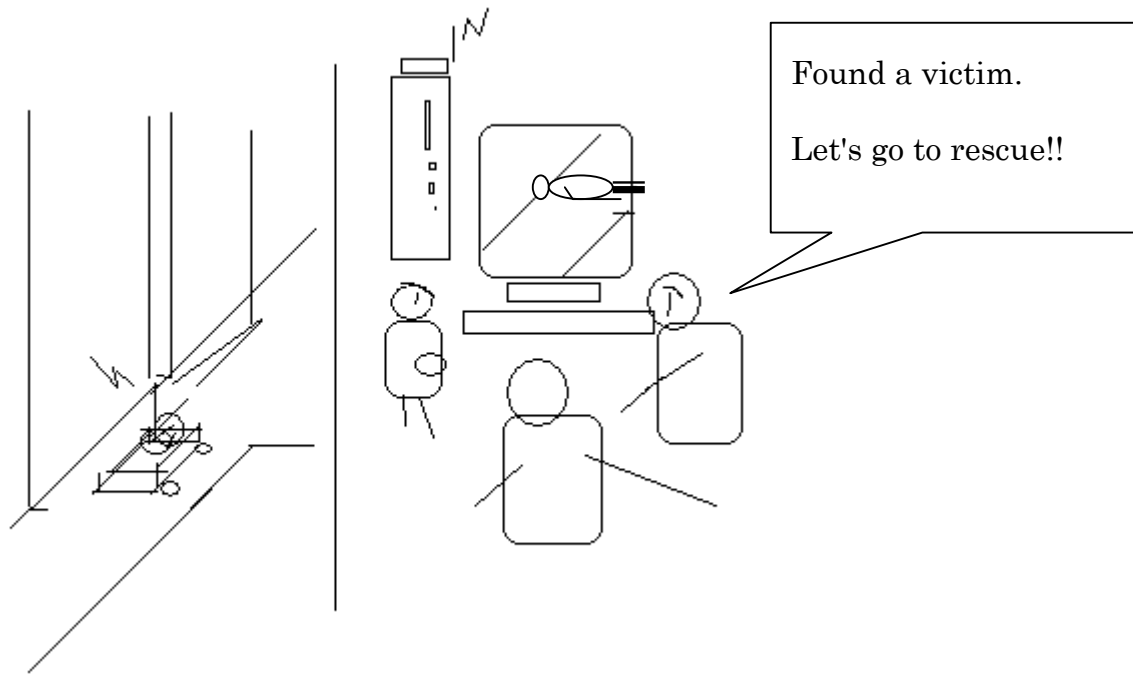


Figure 1 Image of Rescue Robot System.

2 Team Member

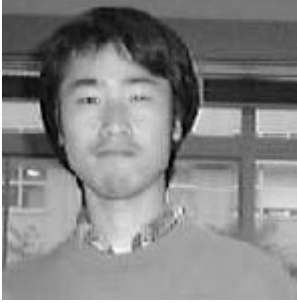
Leader: Satoshi Muraisi



Member: Hiroshi Masui



Member: Takezirou Suzuki



Member: Yuuzou Honda



3 Robot detail

At the time this paper is preparing, the robot is still under developing and has a possibility to make major specification change. To the following shows the target major specification of this prototype robot MINORI 2002

Dimension(L*W*H)	: 300*240*100[mm]
Weight	:10[kg]
Battery Unit	:1.5V*20
Drive Unit	:Two Motors (9W)
Camera system	:NTSC(Color)
Transceiver system	:Frequency Hopping system spectrum diffusion

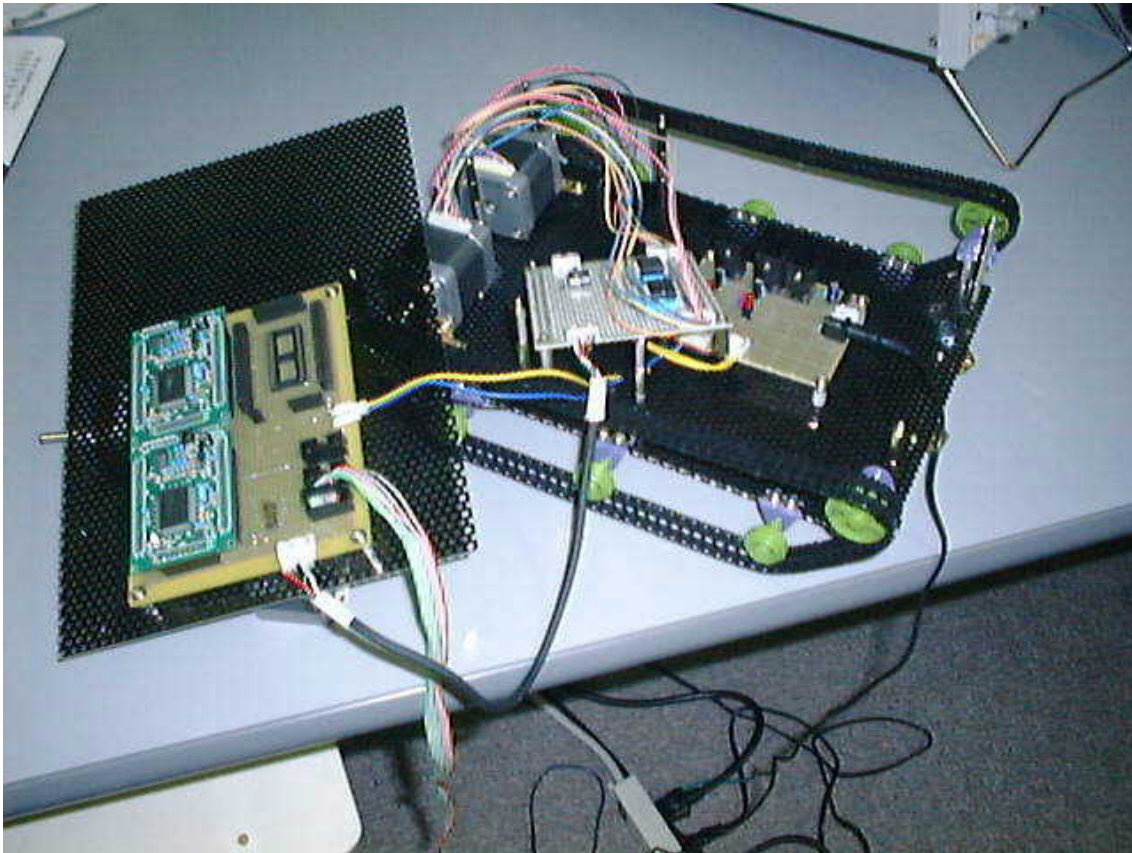


Figure 1 Side view of the robot

4 Man-Machine Communication System

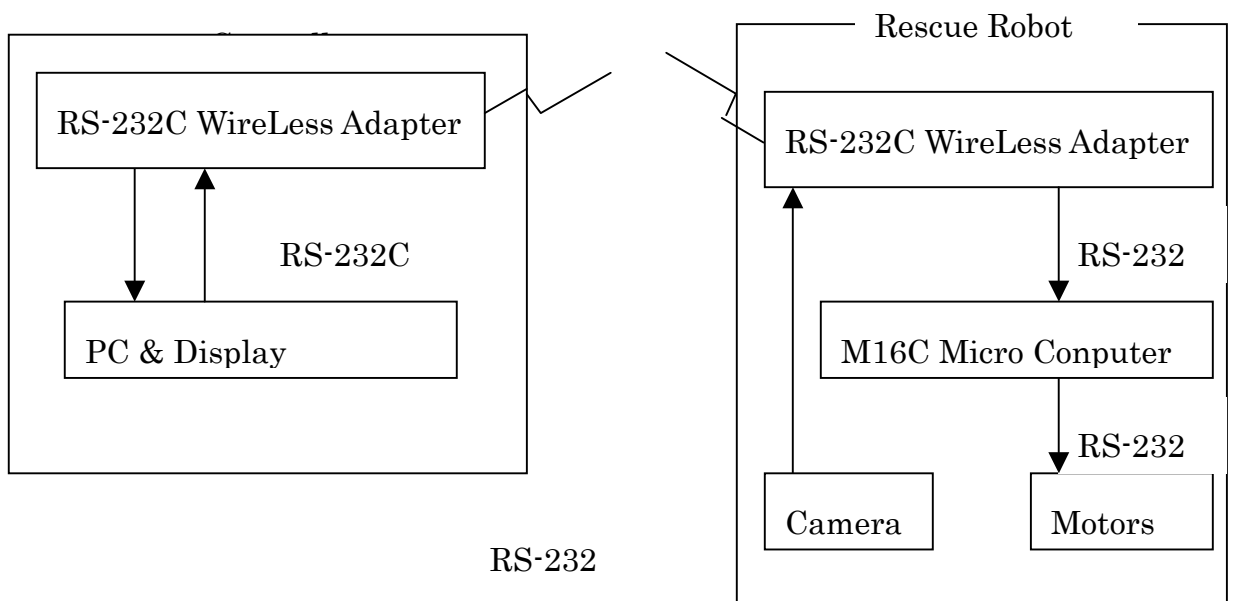


Figure 3 shows System outline