



DESIGN AND MOTION PLANNING OF A TWO MODULE COLLABORATIVE PIPELINE INSPECTION ROBOT

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Abstract: Pipelines are very significant tool as they are used in many different industries for various applications such as transportation of gas, water, fuel, oils, etc. Over time, they are prone to aging, corrosion, cracks, mechanical damage etc., and ignorance of these problems leads to accidents which incurs huge losses in terms of both economy and lives.

This highlights the inevitable need to inspect pipes at a regular interval for the purpose of security and improved efficiency in industrial plants. Now there is many ways of inspecting pipes such as X-rays, magnetic particle inspection method etc., but these methods do not give a full proper internal inspection of pipes. This pipe inspection robot aims at detecting the exact location of leakage and clearing the blockages and thus removing human factor from labour intensive and dangerous work, thereby reducing the number of accidents that happen due to the lack of regular inspection.

Keywords: Pipeline inspection, Crack detection and Blockage clearance.

I. INTRODUCTION

The growth of robots is tremendous in this technologically advanced era. Robots are conceptualized to eliminate the human factor from labour intensive or dangerous and inaccessible work environment. The use of robots is very common in this age of automation and it is no longer exclusively used by manufacturing industries.

Since the dawn of industries, pipelines are tools for transporting oils, gases and other fluids. Many defects occur in pipelines and a majority of them are caused by aging, corrosion, cracks, mechanical damages due to improper installations. If ignored, these troubles translate into major chemical disasters which harm both human life and environment equally.

Thus, the inspection of pipes is extremely important for improving the reliability and security of the industries. The pipelines are the major tools for the transportation of drinkable water, effluent water, fuel oils and gas. A lot of troubles caused by piping networks aging, corrosion, cracks, and mechanical damages are possible.

II. METHODOLOGY

Designing a methodology for a pipeline inspection robot involves several key steps that should be followed to ensure that the robot can effectively and efficiently inspect the pipeline. Here are some steps that can be followed:

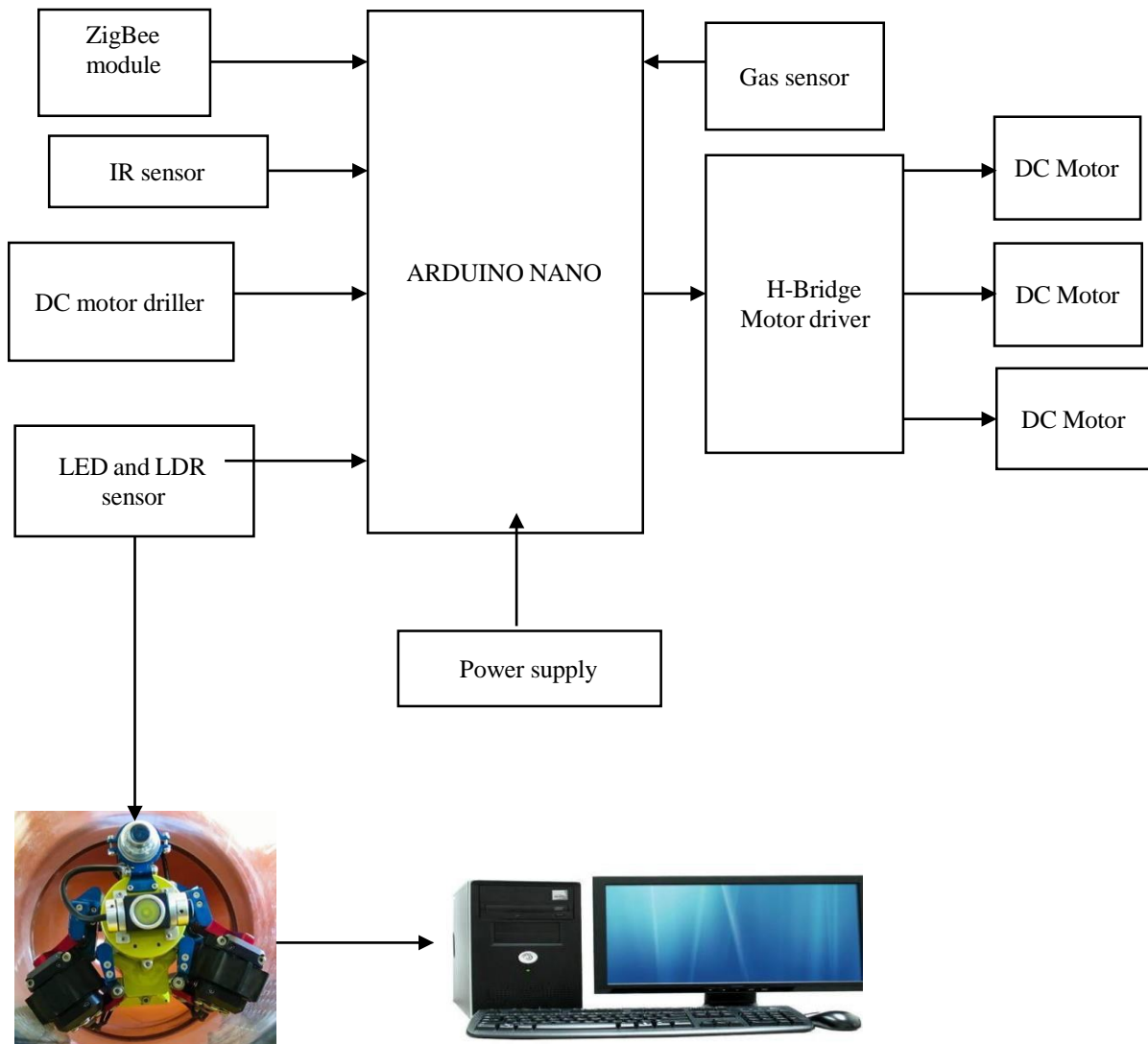


Fig 1: Block Diagram of the system.

Define the objective of the pipeline inspection robot, such as what type of inspection is required, what type of data needs to be collected, and what are the end goals of the inspection. Based on the objective, determine the specifications of the robot, such as the size, weight, shape, and mobility. Choose the appropriate sensors for the robot, such as Cameras, Ultrasonic sensors, LDR and IR sensors to collect the required data. Develop the control system for the robot, which includes the software and hardware components, to control the movement and data collection of the robot. Test the robot in a controlled environment to ensure that it can move through the pipeline, collect data, and transmit data to the control system. Optimize the robot based on the test results to improve its performance and efficiency and finally, Deploy the robot in the pipeline to perform the required inspection.



Analyze the data: Analyze the data collected by the robot to identify any issues or anomalies in the pipeline.

Take necessary actions: Based on the data analysis, take necessary actions to fix any issues or anomalies found in the pipeline.

III. IMPLEMENTATION

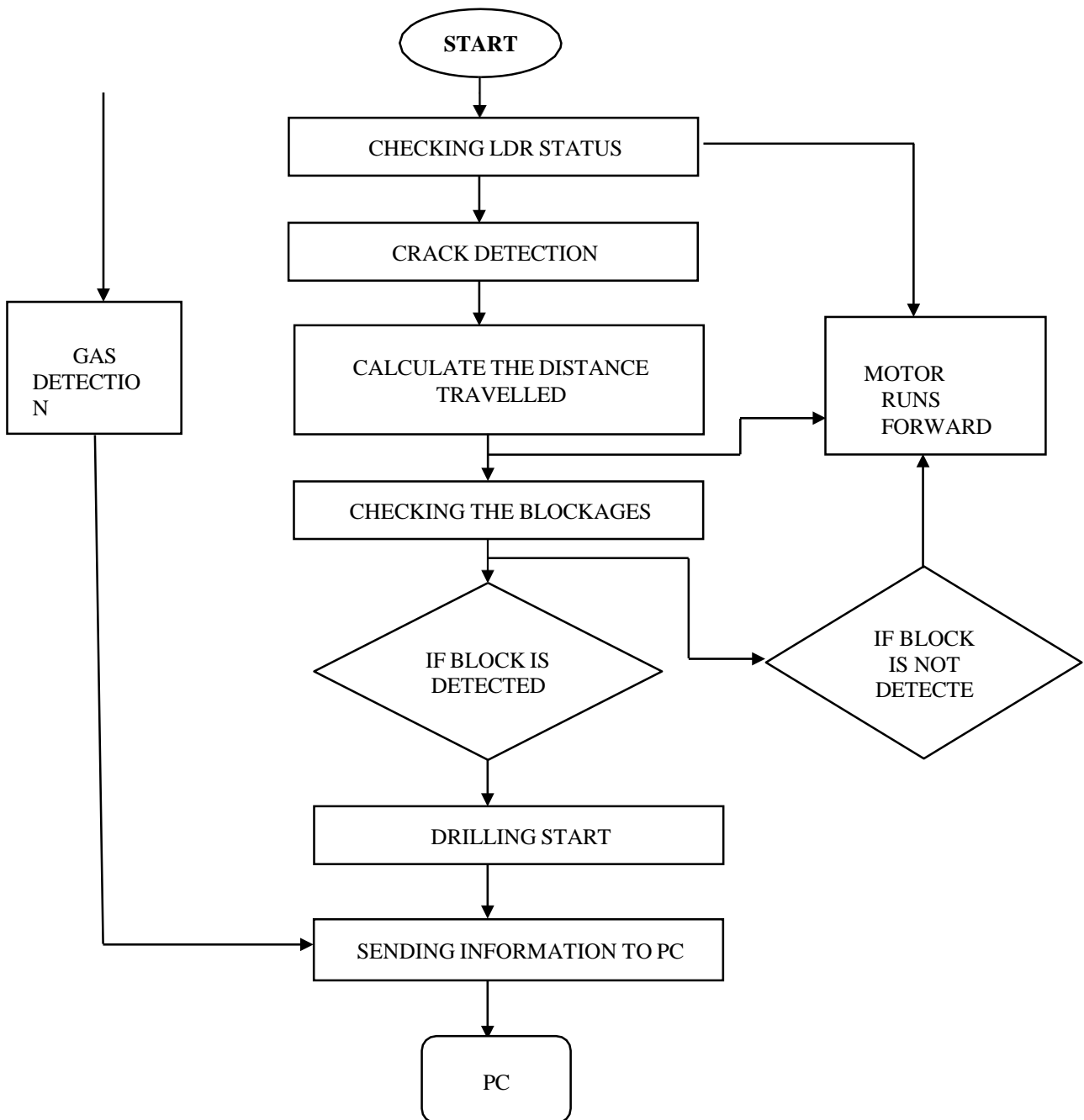


Fig 2: Implementation of Pipeline inspection robot



IV. RESULT ANALYSIS

**Fig 3.1: Proposed Pipeline Inspection Robot**

The robot is ready for the inspection of pipe.

**Fig 3.2: Pipeline Inspection**

The robot starts detecting the crack, gas and obstacles.

**Fig 3.3: Crack in the pipe**

The LDR sensor which is interfaced with the Arduino uno is used to detect the crack when the external light falls on it.

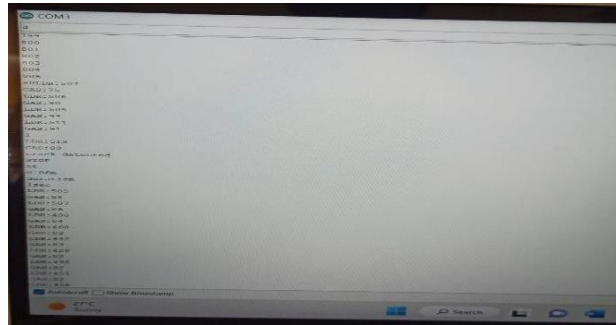


Fig 6.4 Crack detected.

Detection of crack can be seen through the Arduino IDE software i.e displayed on the monitor.

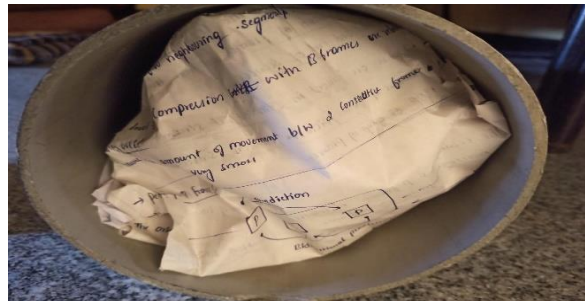


Fig 6.5 Blockage in the pipe.

IR sensor which is interfaced with Arduino uno is used to detect the obstacles/blockage.

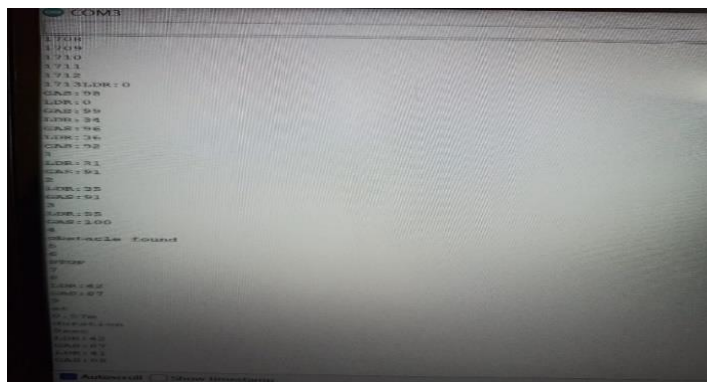


Fig 3.6: Obstacle detect

When the object is sensed immediately the message is displayed on the monitor.

V. CONCLUSION

We are implemented the pipeline inspection robot. Which is basically used to detect the crack, obstacle and blockage clearance in the pipe. Our robot can navigate through difficult terrains and perform inspections in hazardous environments without human risk. The data collected by the robot is analysed to identify the problems and plan maintenance or repair activities.



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