Cite this as: Jin-rong WANG, Yong-xin XI, Chen JI, Jun ZOU, 2022. A biomimetic robot crawling bidirectionally with load inspired by rock-climbing fish. *Journal of Zhejiang University-SCIENCE A (Applied Physics & Engineering)*, 23(1):14-26. https://doi.org/10.1631/jzus.A2100280

# A biomimetic robot crawling bidirectionally with load inspired by rock-climbing fish

**Key words:**

Fish kinematics; Adhesive locomotion mechanism; Fin rays motion; Climbing model; Bio-inspired robot

**Related research by same authors:**

Wang J, Ji C, Wang W, et al., 2019. An adhesive locomotion model for the rock-climbing fish, Beaufortia kweichowensis Sci Rep-Uk 9(1). https://doi.org/10.1038/s41598-019-53027-2

Zou J, Wang J, Ji C, 2016. The Adhesive System and Anisotropic Shear Force of Guizhou Gastromyzontidae Sci Rep-Uk 6(1). https://doi.org/10.1038/srep37221

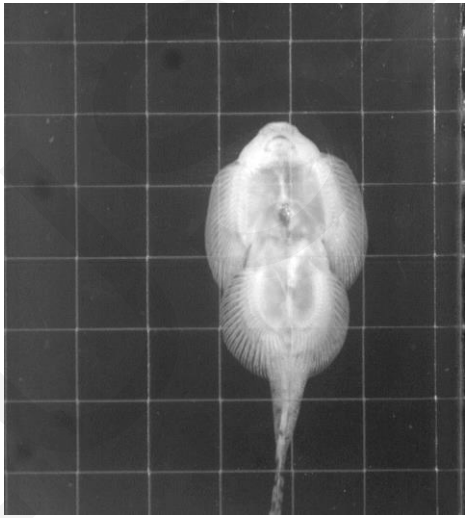
## ❖ Rock climbing fish



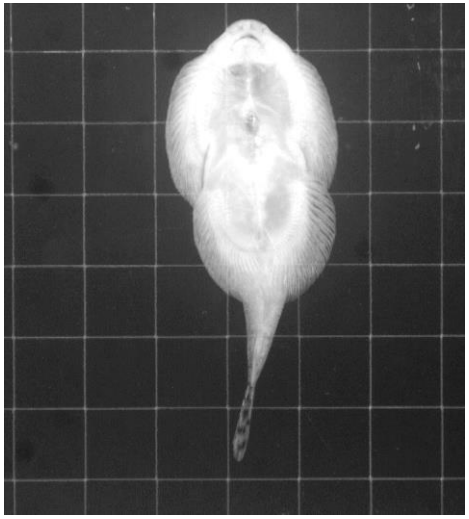
*Beaufortia kweichowensis*

Live fish climbing on vertical surface

forward



backward

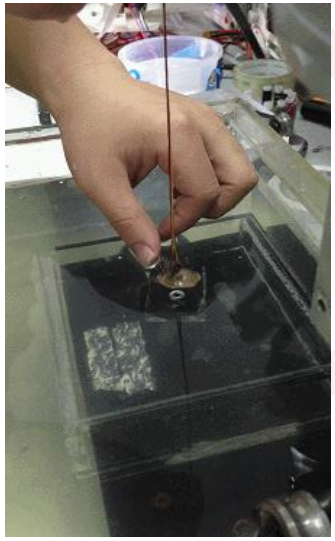


Dead fish

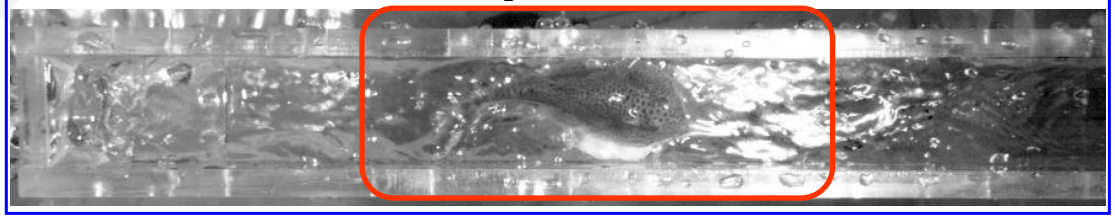
Wet surface



Submerged surface

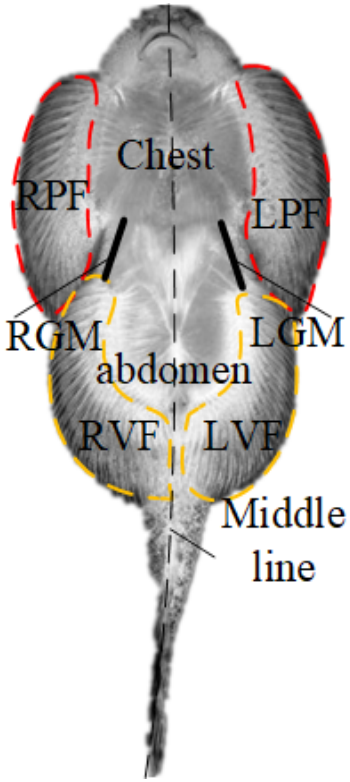


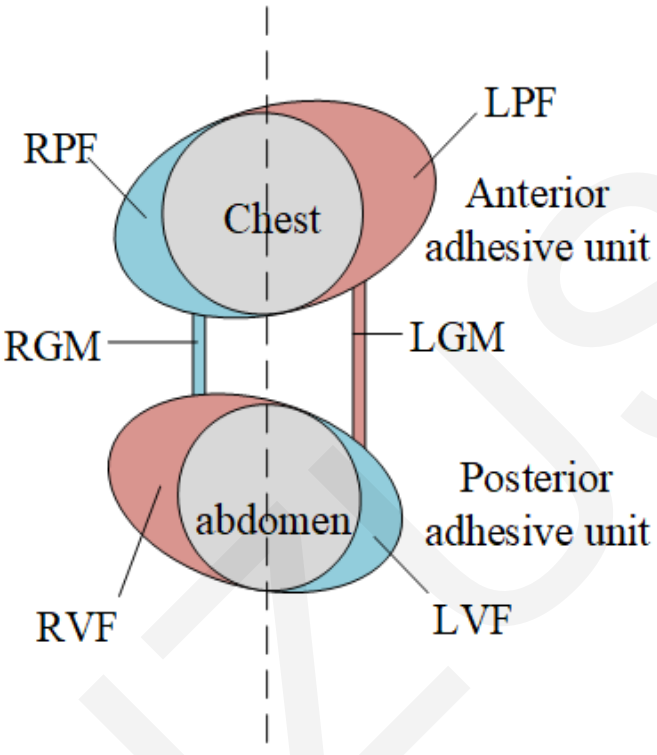
upstream

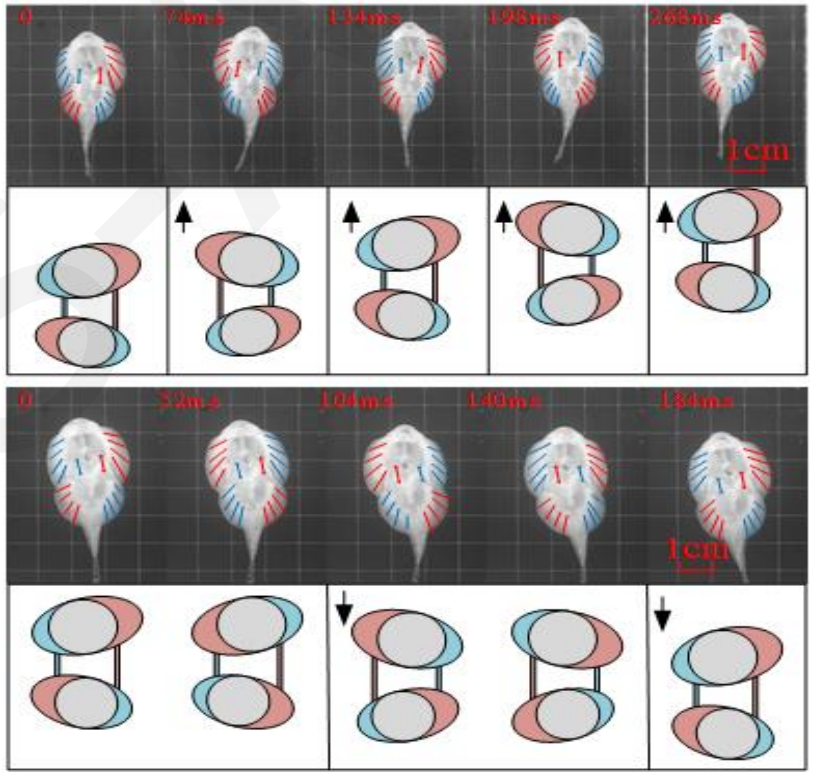


Rock climbing fish own adhesion and locomotion properties

## ❖ Crawling locomotion modeling

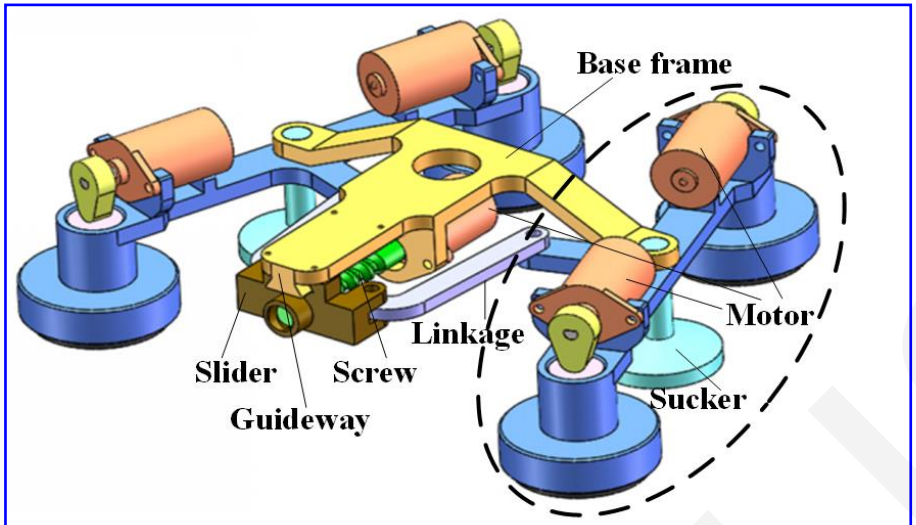


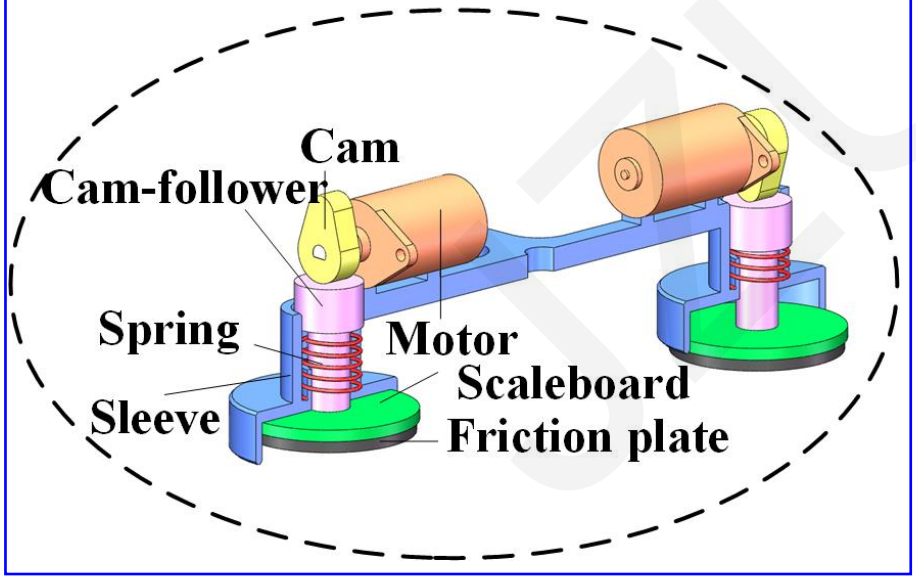



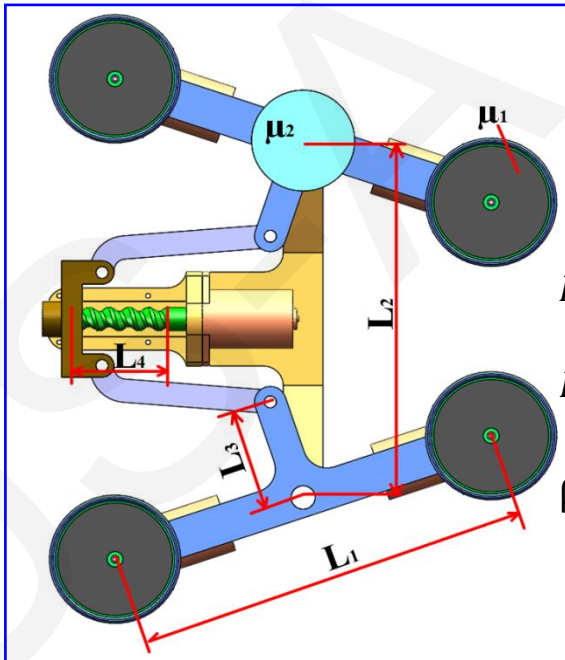




1. Anterior adhesive unit: bilateral pectoral fins (PF) and chest
2. Posterior adhesive unit: bilateral ventral fins (VF) and abdomen
3. Extensible cylinders: girdle muscles (GM)
4. Red area: Unfolded fin
5. Blue area: folded fin

## ❖ Robot design



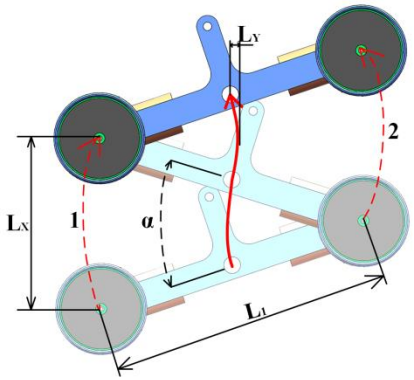



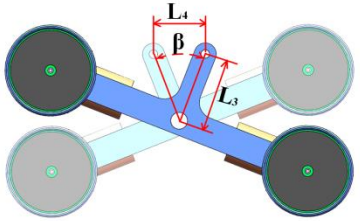

$$L_X = 2 \times L_1 \sin\frac{\alpha}{2}$$

$$L_Y = \frac{L_1}{2} - \frac{L_1}{2} \times \cos\frac{\alpha}{2}$$

$$\beta = 2 \times \sin^{-1}\frac{L_4}{2 \times L_3}$$

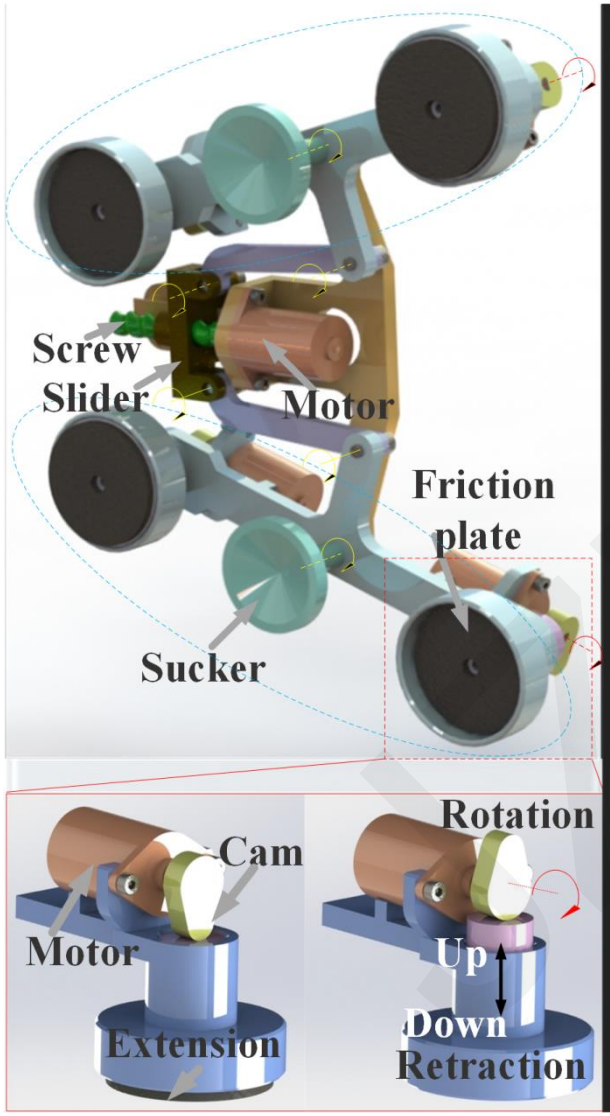
$$L_X = \frac{L_1 \times L_4}{L_3}$$

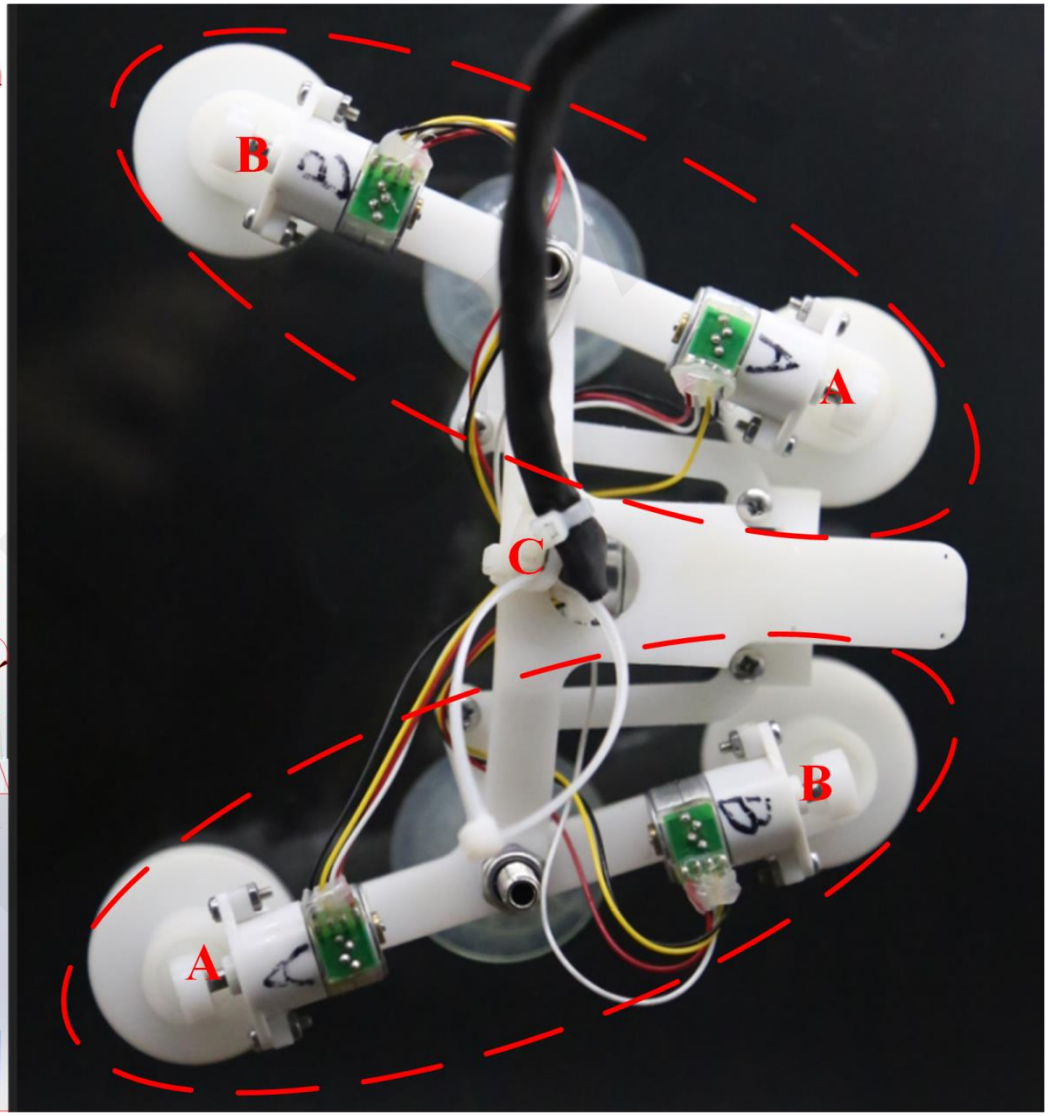



$L_X$ means axial displacement, $L_Y$ means radial displacement of the robot.

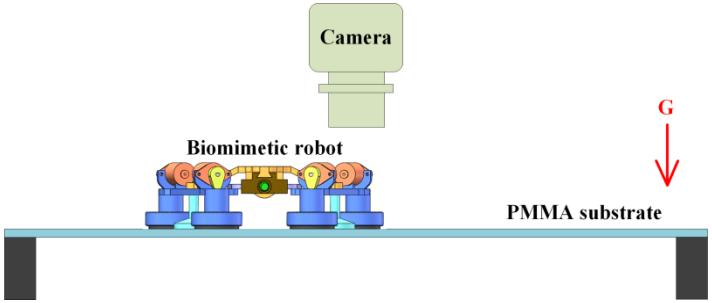
## ❖ Real robot

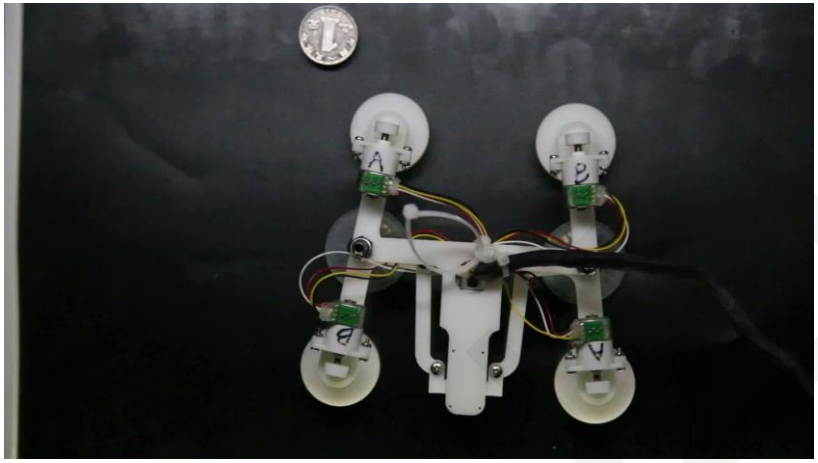


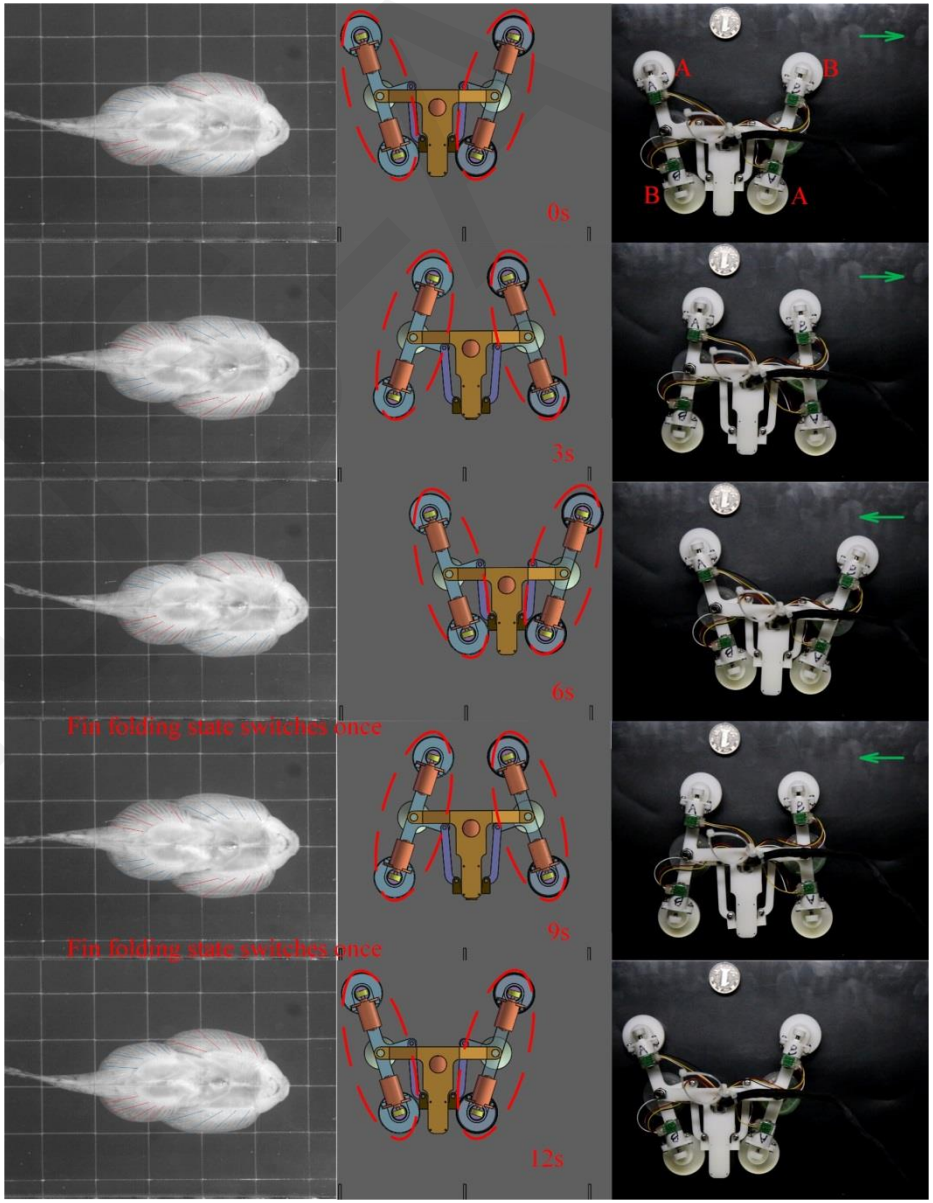




One motor drives body swing through screw and four motors drive adhesive units through cam

## ❖ Robot test on horizontal surface

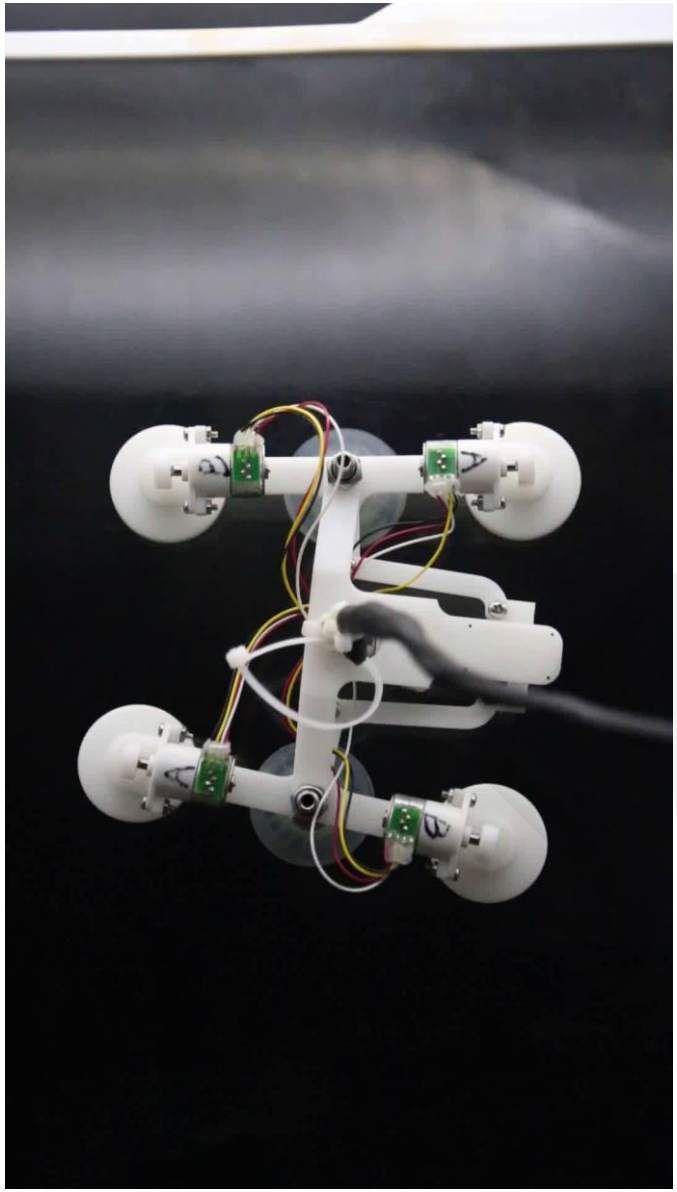


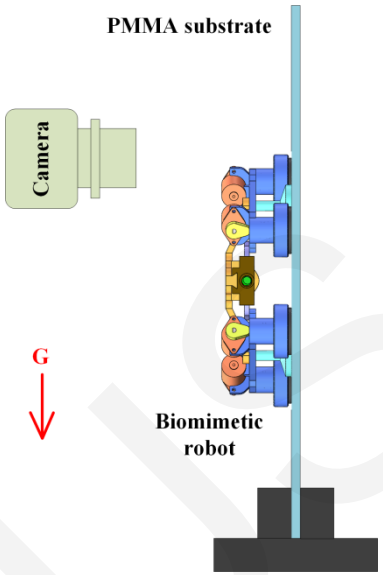





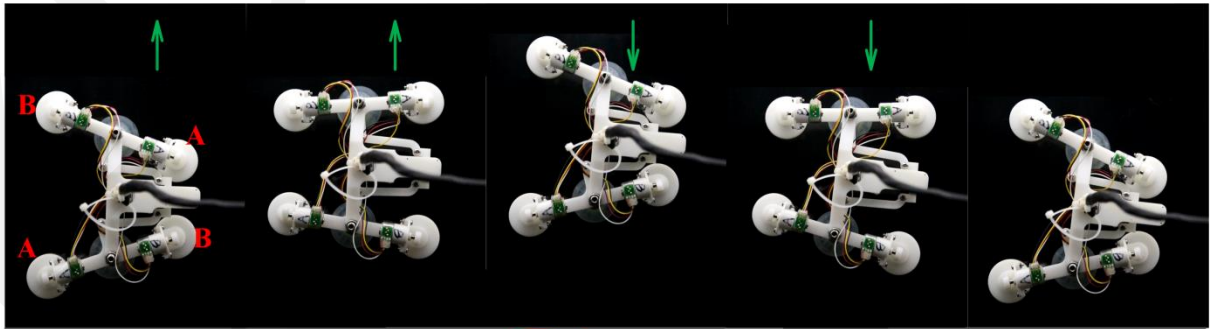

(1) Forward state (0-3s)
(2) Forward state (3-6s)
(3) Backward state (6-9s)
(4) Backward state (9-12s)

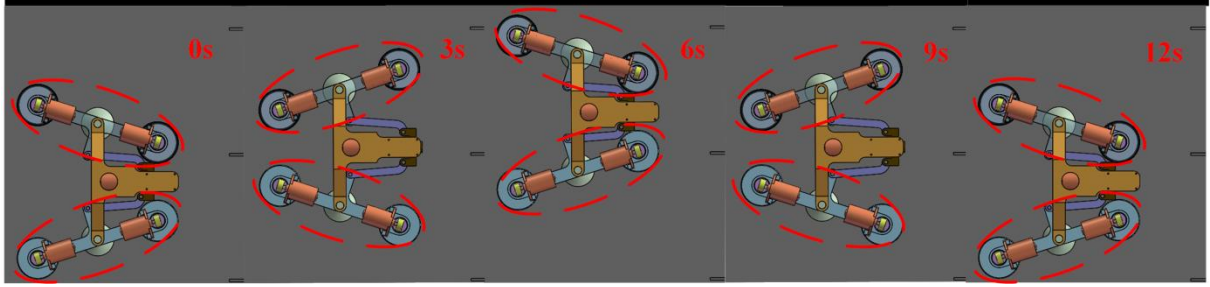
## ❖ Robot test on vertical surface



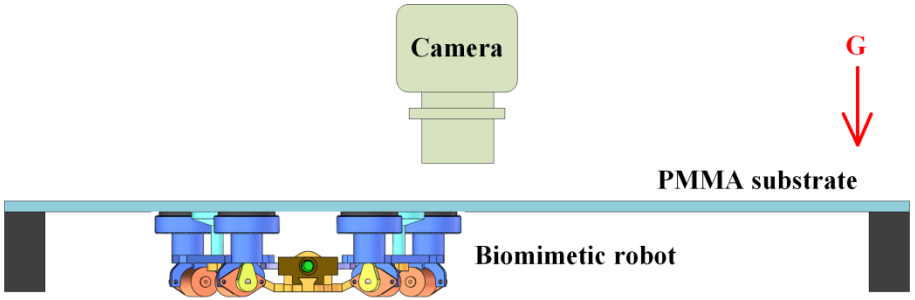


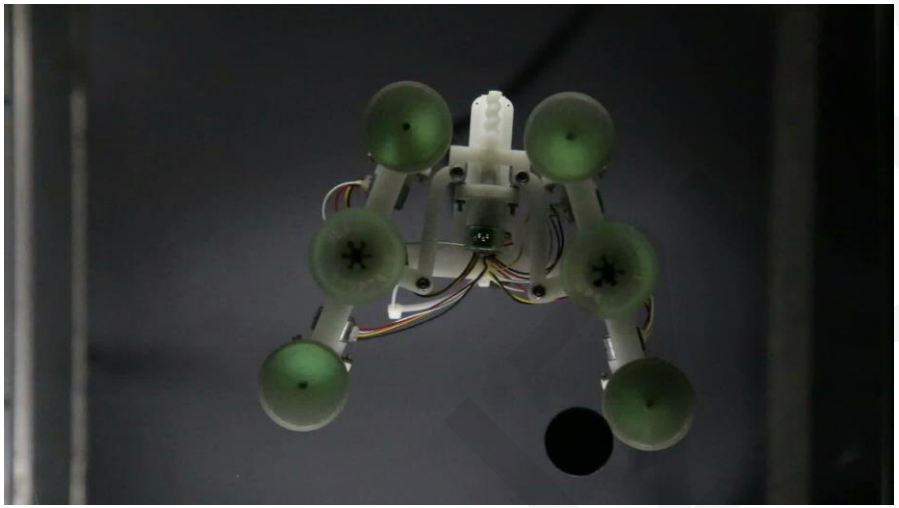

(1) Forward state (0-3s)
(2) Forward state (3-6s)
(3) Backward state (6-9s)
(4) Backward state (9-12s)



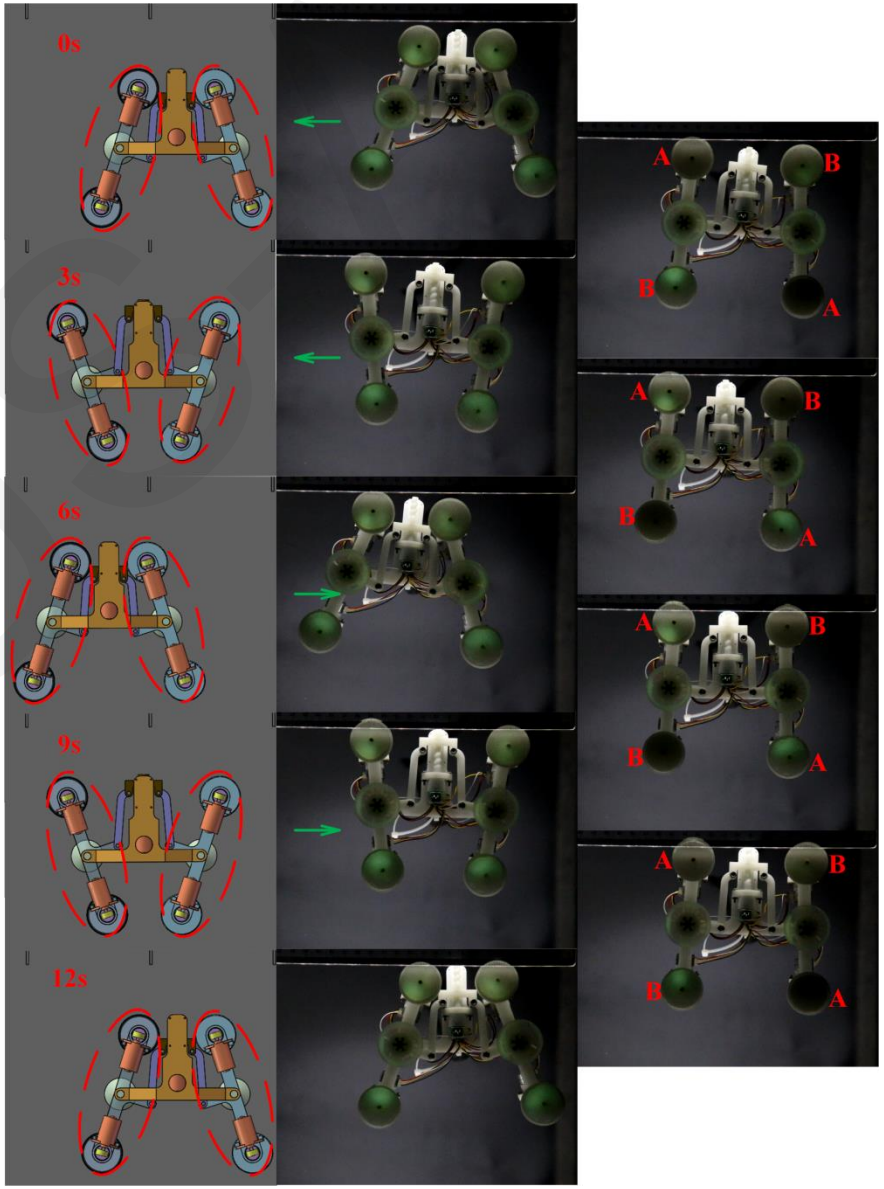



# ❖ Robot test on inverted surface

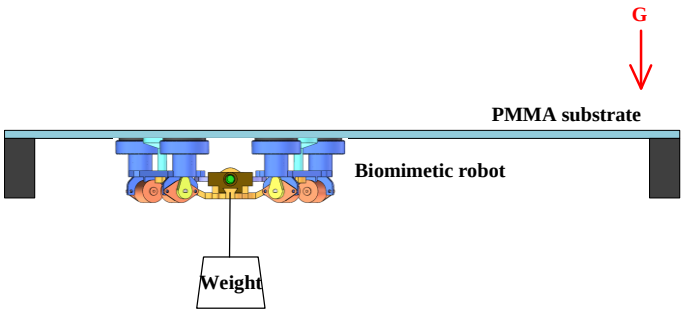


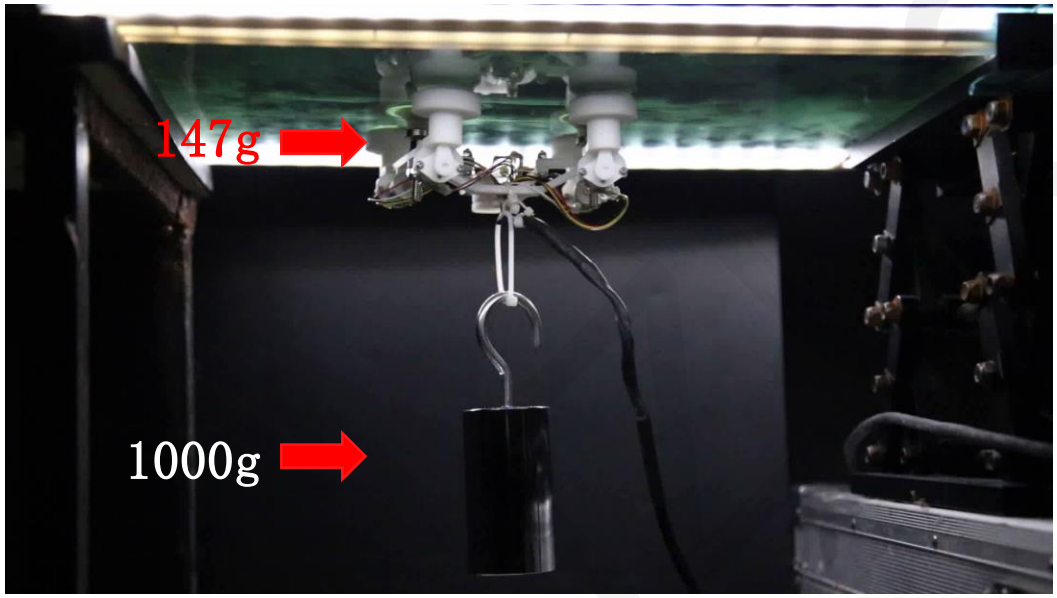



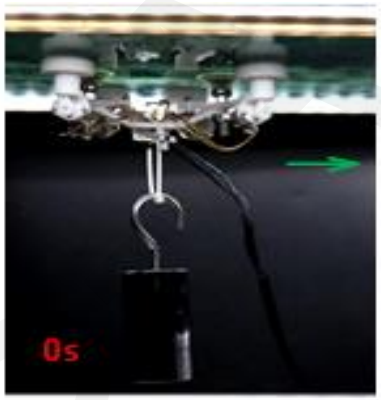
(1) Forward state (0-3s)
(2) Forward state (3-6s)
(3) Backward state (6-9s)
(4) Backward state (9-12s)

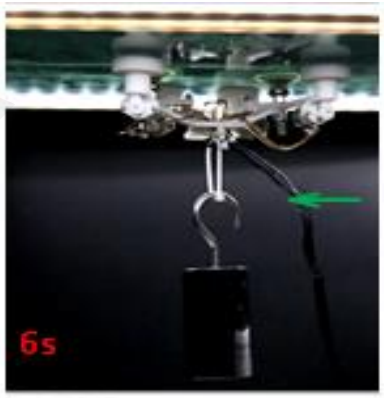


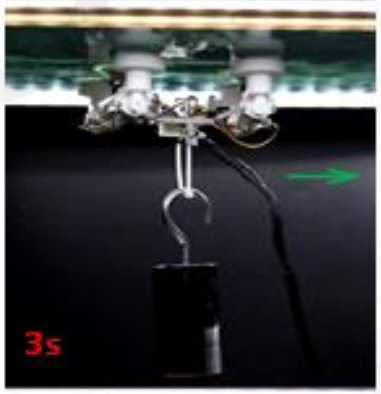
## ❖ Robot test on inverted surface with load

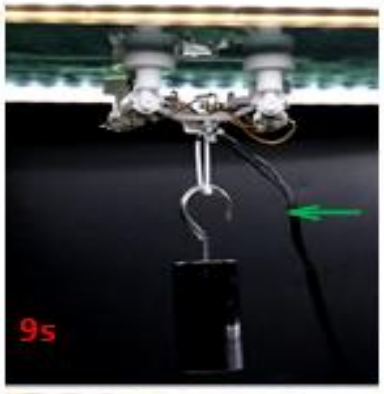


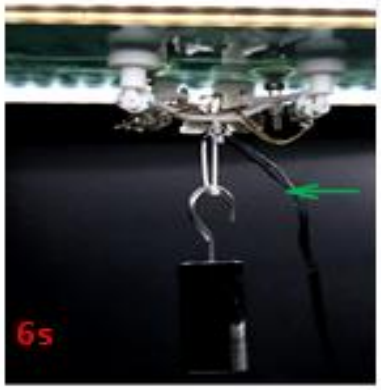



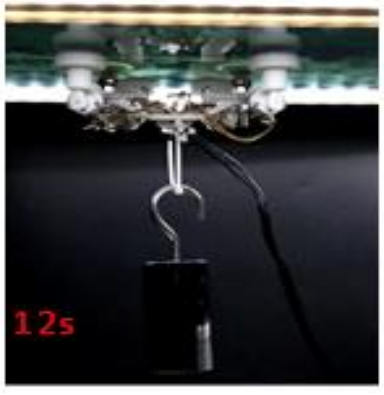




(1) Forward state (0-3s)
(2) Forward state (3-6s)
(3) Backward state (6-9s)
(4) Backward state (9-12s)