CHAPTER 6
CONCLUSION

After the main goal of this project has been achieved, the Researcher found some conclusions, those are :

1. The spider's feet must be applied with right material to make it munch more less slipper than just relying Spider's bare feet.
2. Faster motion doesn't always mean it will be faster, especially on tilted grounds.
3. The walking algorithm of a spider robot plays a high role of the spider robot's capability to handle tilted grounds.
4. Spider robot design and it's material are also take a high part.
5. Only modifying the servo with a fixed value to handle tilted grounds is not enough.
6. The ground where will the spider robot walk will also determine the success or failure of the walking algorithm.
7. In the future, this spider robot is ready to be installed with gyroscope sensor to make the spider robot can adjust the slope angle by itself, since this walking algorithm has 5 defined codes that will determine the angle, the value given by the gyroscope sensor can be mapped to give 5 possible values.

There are some some suggestions from the Researcher of this project for those who will do something similar to this project :

1. Using more legs than four, because more legs means easier to balance robot.
2. Develop a better walking algorithm, using Inverse Kinematic method is recommended for easiness on development.