

## Design and Fabrication of Flexible Wing UAV

Selvakumar, R. Ramasamy

Department of Aeronautical Engineering  
Nehru Institute of Technology, Coimbatore.  
nitsaranya@nehrucolleges.com<sup>1</sup>

### Introduction

Multi-purpose, compact unmanned aerial vehicles have been gaining remarkable capabilities in the last decades. They are important due to their abilities to replace manned aircrafts in many routine and dangerous missions, and to reduce costs of many aerial operations. These aerial robots can be utilized in a variety of civilian missions such as surveillance in disasters, traffic monitoring, law enforcement and power line maintenance. They are already being benefitted in military applications such as intelligence, surveillance, target acquisition, reconnaissance and aerial attacks. These application areas lead to more advanced research for increasing the level of autonomy and reducing the size of UAVs. UAVs can be classified into three main categories: fixed-wing UAVs, rotary-wing UAVs, and hybrid design UAVs. [14]

### Existing models

Fixed wing UAVs constitute the richest group among these categories both in terms of research and utilization. They are able to fly for long duration at high speeds and their design is simple in comparison with the other types of UAVs. These advantages lead to a broad range of fixed wing UAV designs from RQ-4 Global Hawk with 39.8 m wingspan to Aero Vironment Wasp with 72 cm wingspan. However, these UAVs suffer from the requirement of runways or additional launch and recovery equipment for takeoff and landing. Rotary wing UAVs, on the other hand, are advantageous since they do not require any infrastructure for takeoff and landing. They also do not need any forward airspeed for flight and manoeuvring, which makes them useful particularly in urban areas and indoors. This leads to a large variety of rotary wing UAVs ranging from Boeing A160 Hummingbird with 2948 kg flight weight to Seiko-Epson I Flying Robot with only 12.3 g flight weight. But they are mechanically complex and have low flight speeds and durations.[14]



Fixed Wing UAV



Rotor wing



Hybrid wing

Hybrid design UAVs join the vertical flight capabilities of rotary wing UAVs with the high speed long duration flight capabilities of fixed wing UAVs. Despite their increased mechanical complexity and more difficult control, they are very desirable for their ability to act like both fixed wing and rotary wing UAVs, since this ability is very useful in various missions. Among these hybrid designs, tilt-rotor UAVs constitute an attractive research area due to their stability, energy efficiency and controllability. A large proportion of the research on these vehicles is on dual tilt-rotors such as Bell Eagle Eye, Smart UAV of KARI and BIROTAN and dual tilt-wings such as HARVee and the UAV of University di Bologna. The dual rotor UAVs generally require cyclic control on propellers, which adds to the mechanical complexity, for stabilization and manoeuvring. To solve this problem there are also studies on tilt-wing UAVs such as Vz-22 experimental aircraft of US Aerospace.[14]

### **Disadvantages of Existing Models.**

#### **Fixed wing UAV's**

The UAV's are used military for surveillance and intelligence process. The fixed wing requires runway for takeoff and landing, during surveillance the UAV will be loitering at target point to collect data. The collected data will not be clear and gives less information.

#### **Rotary wing UAV's**

It has less manoeuvrability compared to fixed wing UAV's. The velocity of the rotary less, In order to escape from enemies sight it should have high velocity to escape.

#### **Tilt-Rotor UAV's**

In Tilt-Rotor UAV's drag produced will be more during Takeoff and Landing. It has Lesser stability to climbing and descending.

### **Advantages of Tilt -Wing VTOL UAV**

In order to overcome the disadvantages of the existing model we have chosen hybrid UAV. In hybrid acts as fixed wing as well as rotor wing. In surveillance, to attain the target the fixed wing manoeuvring is used. After reaching the target the wing tilted upward and hovers near the target and capture clear data. After the data are collected it return to fixed wing manoeuvring to escape from the target.

### **Selecting of Model**

We have chosen 3D- Free style aerobatic model UAV for higher manoeuvrability and higher speed.



**Figure: 1**

### Design parameters

Overall length	: 100cm
Wing span	: 100cm
Wing area	: 1851.85cm <sup>2</sup>
Aspect ratio	: 5.4
Root chord	: 24cm
Tip chord	: 12cm
Overall weight: 1.1Kg	
Aileron area	: 462.96cm <sup>2</sup>
Vertical stabilizer area	: 185.18cm <sup>2</sup>
Horizontal stabilizer area	: 370cm <sup>2</sup>
Elevator area	: 925.9cm <sup>2</sup>
Ruder area	: 925.9cm <sup>2</sup>
Airfoil	: NACA 23018

### Construction Material Used

#### Electronic System

**Engine:** Motor If 2212/13 1000KV Up to Model Weight 800Gms

#### Specification

Motor size	: 28*26mm
Shaft size	: 3.175*37mm
Weight	: 50g
Rpm	: 1000
Max Power	: 150W
ESC	: 18A
Propeller	: 11x7/10x5
Battery	: 3s Li-Po



**Figure:1** Electric Motor

**Electronic Speed Control: ESC RCFORALL 30 AMPS**

**Specification**

Input voltage : DC 6-16. 8V (2-4S Lixx)

BEC : 5V 2amp

Running current : 30A (Output: Continuous 30A, Burst 40A up to 10 Sec.)

Size : 36mm (L) \* 26mm (W) \* 7mm (H).

Weight : 32g



**Figure: 2** Propeller: Paired 2 Blade Propellers Rotating & Counter Rotating 10×4.5



**Figure: 3** Extended Wire

**BATTERY:** Battery lipo Gens Ace 3S (Rechargeable) 11.1V 25 C 2200 mAh

**Specification**

Rechargeable Lipo (Lithium Polymer) High Discharge /Fast Charge Batteries 3S 11.1V 2200mAh



Capacity	: 2200mAh
Voltage	: 11.1V
Max Continuous Discharge	: 25C (55A)
Max Burst Discharge	: 50C (110A)
Weight	: 195 g
Dimensions	: 105.68*34.15*25.71 mm
Balance Plug	: JST-XH
Discharge Plug	: 4.0mm banana or T plug
Charge Rate	: 1-3C Recommended, 5C Max

## Structural Materials

### Balsa Wood:

- Light-weight wood.
- Stronger than coroplast, but not crash proof though.
- Stiffer than other available materials

### Ceroplactic (Sun pack)

- Durable material.
- Stronger than Styrofoam but a bit heavier.
- Good choice for fuselage and crash-prone areas

## Wing Construction

Several airfoils are cut from balsa wood

Airfoils are connected using balsa support rods the structure is partially covered with 1mm sheet balsa throughout the wing span (near the leading edge) Ailerons are also made in the similar way. Both the wings and ailerons are covered with heat shrinkcovering film (plastic film).

## Conclusion

By using VTOL UAV the performance characteristic will be enhanced compare to the fixed wing and rotary wing UAV's. This UAV will do better surveillance of collecting clear information of the target quickly. If this VTOL UAV is implemented we can collect good amount of information for surveillance and intelligence process.

## Reference

1. Erbil MA, Prior SD, Karamanoglu M, Odedra S, Barlow C, Lewis D. Reconfigurable unmanned aerial vehicles. In: Proceedings of the International Conference on Manufacturing and Engineering Systems; 2009. p. 392–6.
2. Puri A. A survey of Unmanned Aerial Vehicles (UAV) for traffic surveillance. In: Department of computer science and engineering, University of South Florida; 2008. <<http://www.csee.usf.edu/apuri/techreport.pdf>>.
3. ISTAR (Intelligence, Surveillance, Target Acquisition & Reconnaissance). General Dynamics. <<http://www.generaldynamics.uk.com/solutionsandcapabilities/istar>>.
4. Salazar S, Lozano R, Escareno J. Stabilization and nonlinear control for a novel Trirotor mini-aircraft. Elsevier Control Engineering Practice. vol. 17; February 2009. p. 886–94.

5. Latchman H, Wong T. Statement of work for airborne traffic surveillance systems – proof of concept study for florida department of transportation; 2002. <[http://www.list.ufl.edu/publications/atss\\_prop-oct-02-verb.pdf](http://www.list.ufl.edu/publications/atss_prop-oct-02-verb.pdf)>.
6. Coifman B, McCord M, Mishalani M, Redmill K. Surface transportation surveillance from unmanned aerial vehicles. In: 83rd Annual meeting of the transportation research board; 2004.
7. Murphy DW. The AirMobile Ground Security and Surveillance System(AMGSSS). In: 10th annual ADPA security technology symposium; September 2005.
8. Travers D. Brigade ISTAR operations. Arm Doctrine Train Bull 3 2000; 3(4):43–9.
9. McGuinness B, Ebbage L. Assessing human factors in command and control: workload and situational awareness metrics. In: Proceedings of the command and control research and technology symposium; 2002.
10. Crck E, Lygeros J. Sense and avoid system for a MALE UAV’’ AIAA guidance. In: Navigation and control conference and exhibit; August 2007.
11. Grigson P, Gray A. CFD analysis of the low-speed aerodynamic characteristics of aUCAV. In: 13th RPVs/UAVs international conference; 1999.
12. Carroll D, Everett HR, Gilbreath G, Mullens K. editors. Missions, technologies, and design of planetary mobile vehicles; 2006.
13. Snyder D. The quad tiltrotor: its beginning and evolution. In: Proceedings of the 56th annual forum, american helicopter society. Virginia Beach, Virginia; May 2000.
14. Design and construction of a novel quad tilt-wing UAV