12. The pipeline inspection robot of claim 11, further comprising:

a radial arm extension slidably attached to the radial arm and configured to extend further around the circumference of the pipeline than the radial arm.

13. The pipeline inspection robot of claim 11, further comprising:

first and second leg motors controlling the first and second legs, respectively, the first and second leg motors configured so that when the first wheel encounters an obstacle in front of the first wheel in the direction of movement of the body, the second leg motor rotates the second leg upward away from the surface of the pipeline and radially around the body until the second wheels contacts the surface of the pipeline on an opposite side of the obstacle, after which the first leg motor rotates the first leg upward away from the surface of the pipeline and radially around the body until the first ~~pair of~~ wheels contacts the surface of the pipeline, thereby causing the robot to pass over the obstacle.

14. The pipeline inspection robot of claim 11, wherein the first and second wheels are attached to the first and second legs by first and second wheel hubs, respectively, wherein the wheel hubs contain a separate wheel motor for each wheel, and wherein the course of the robot can be adjusted by increasing or decreasing the speed of each wheel with its corresponding wheel motor.

15. The pipeline inspection robot of claim 11, further comprising:

a downward facing camera attached to the body for collecting data about the surface condition of the pipeline and for guiding the robot.

16. The pipeline inspection robot of claim 11, wherein the robot is autonomous.

17. The pipeline inspection robot of claim 11, wherein the robot is remote controlled.

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2. The pipe inspecting robot of claim 1, wherein the first and second pairs of wheels are attached to the first and second articulating legs by first and second wheel hubs, respectively, and wherein the wheel hubs contain at least one wheel motor to power the wheels.

3. The pipe inspecting robot of claim 2, wherein each wheel is powered by a separate wheel motor, and wherein the course of the robot can be adjusted by increasing or decreasing the speed of each wheel with its corresponding wheel motor.

4. The pipe inspecting robot of claim 1, wherein the body contains at least one device selected from the group consisting of a control circuit, a communication circuit, a global positioning system (GPS) circuit, a GPS antenna, a camera, a camera circuit, and a battery pack.

5. The pipe inspecting robot of claim 1, further comprising:

a downward facing camera attached to the body for collecting data about the surface condition of the pipeline and for guiding the robot.

6. The pipe inspecting robot of claim 1, wherein the robot is autonomous.

7. The pipe inspecting robot of claim 1, wherein the robot is remote controlled.

8. The pipe inspecting robot of claim 1, further comprising:

pins attached to the body and having an extended and a retracted position, wherein when in the extended position the pins lock the position of the legs relative to the body, and when in the retracted position the pins allow the legs to articulate relative to the body.

9. The pipe inspecting robot of claim 1, further comprising:

a radial arm attached to the body and extending outward from the body around a portion of the circumference of the pipeline, the radial arm having a camera for inspecting the surface of the pipeline.

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10. The pipe inspecting robot of claim 9, further comprising:

a radial arm extension slidably attached to the radial arm and configured to extend still further around the circumference of the pipeline than the radial arm.

11. A pipeline inspection robot, comprising:

a body;

first wheels and second legs that articulate independently of one another, that are attached to the body, and that are articulable around a common central body axis;

first and second wheels attached to the first and second legs, respectively, at an opposite end of the legs from the body, the first leg articulable around the first wheel around a first wheel axis, and the second leg articulable around the second wheel around a second wheel axis, the first wheel axis and the second wheel axis oriented parallel to the central body axis, and the first and second wheels configured to move along the pipeline with the body;

the first and second legs and first and second wheels configured so that when the first wheel encounters an obstacle in front of the first wheel in the direction of movement of the body, the second leg rotates upward away from the surface of the pipeline and radially around the body until the second wheel contacts the surface of the pipeline on an opposite side of the obstacle, after which the first leg rotates upward away from the surface of the pipeline and radially around the body until the first wheel contacts the surface of the pipeline, thereby causing the robot to pass over the obstacle; and

a radial arm attached to the body and extending outward from the body around a portion of the circumference of the pipeline, the radial arm having a camera for inspecting the surface of the pipeline.

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