CLAIMS:

1. An autonomous system (100) to execute a painting activity, comprising:

   at least one scanning unit (101) configured, to obtain topographical data for a geography to generate a primary scanning report;

   at least one remote device (107) configured, to generate a secondary scanning report based on one or more verification parameters;

   one or more mobile units (103) configured, to generate one or more tool reports based on status of respective one or more tools;

   a central control system (105) configured, to obtain the scanning report and the tool report and determine an action report based on the obtained scanning report and tool report; and

   the one or more mobile units (103) obtain, the action report to execute the painting activity,

   wherein the one or more mobile units (103) comprise a plurality of vacuum impellers (403) to enable anti-gravity motion of the one or more mobile units (103) on a vertical surface.

2. The autonomous system (100) of claim 1, wherein the scanning unit (101) comprises one or more sensors associated with an imaging device (205) to obtain one or more category of images associated with the geography to obtain the topographical data.

3. The autonomous system (100) of claim 1, wherein the one or more verification parameters include procedural analysis of the primary scanning report to detect one or more anomalies, irregularities in patterns associated with the primary scanning report.

4. The autonomous system (100) of claim 1, wherein the status of the respective one or more tools includes location data and resources data.

5. The autonomous system (100) of claim 1, wherein the action report comprises one or more instructions on multi-planar movement for the respective one or more mobile units (103) to execute the painting activity by eliminating one or more obstacles.

6. The autonomous system (100) of claim 1, wherein

each of the plurality of the vacuum impellers (403) comprise a first actuator; and

the plurality of the vacuum impellers (403) are connected based on a linear drive (405) associated with a worm gear and controlled by a second actuator to execute the painting activity based on the action report.

7. The autonomous system (100) of claim 1, further comprising a modular supply unit, configured to deliver resources to the one or more mobile units (103), wherein rate of delivery of the resources match with rate of execution of the painting activity.

8. The autonomous system 100 of claim 1, further comprising:

the central control system (105) obtaining, quality control data, transmitted by the at least one scanning unit (101) during execution of the painting activity;

the central control system (105) generating, a feedback data based on the quality control data; and

the central control system (105) transmitting, the feedback data to the respective one or more mobile units (103).

9. A method of executing a painting activity, the method comprising:

generating, a primary scanning report of a geography based on topographical data by a scanning unit (101);

generating, a secondary scanning report based on one or more verification parameters, by at least one remote device (109);

generating, one or more tool reports based on status of the respective tools by one or more mobile units (103);

obtaining, the secondary scanning report and the tool report to determine an action report, by a central control system (105); and

transmitting, the action report to one or more mobile units (103) to execute the painting activity,

wherein the one or more mobile units (103) comprise a plurality of vacuum impellers (403) to enable anti-gravity motion of the one or more mobile units (103) on a vertical surface.

10. The method of claim 9, wherein the scanning unit (101) comprises one or more sensors associated with an imaging device (205) to obtain one or more category of images associated with the geography to obtain the topographical data.

11. The method of claim 9, wherein the status of the respective one or more tools include location data and resources data.

12. The method of claim 9, wherein the action report comprises one or more instructions on multi-planar movement for the respective one or more mobile units (103) to execute the painting activity by eliminating one or more obstacles.

13. The method of claim 9, wherein

each of the plurality of the vacuum impellers (403) comprise a first actuator; and

the plurality of the vacuum impellers are connected based on a linear drive (405) associated with a worm gear and controlled by a second actuator to execute the painting activity based on the action report.

14. The method of claim 9, further comprises delivering, by a modular supply unit, resources to the one or more mobile units (103), wherein

rate of delivery of the resources match with rate of execution of the painting activity.

15. The method of claim 9, further comprising:

obtaining quality control data, by the central control system (105), transmitted by the at least one scanning unit (101) during execution of the painting activity;

generating , the central control system (105), a feedback data based on the quality control data; and

transmitting, the central control system (105), the feedback data to the respective one or more mobile units.