**CLAIMS**

1. A UAV for detecting cracks in a wall of a building, the UAV comprising
- a propulsion means for flying the UAV,
- a digital camera for capturing pictures of the wall,
- a flight control module, the flight control module being operative to control the propulsion means based on image data of the digital camera, such that the UAV flies along the wall of the building along a pre-determined flight path,
- an image capturing module, wherein the flight control module is operative to control the propulsion means and wherein the image capturing module is operative to control the digital camera such that adjacent pictures captured by the digital camera have an overlap in a predetermined range,
wherein the UAV further comprises a processor for identifying at least one no-scan area of the wall to determine the pre-determined flight path.

2. The UAV of claim 1, wherein the image capturing module is operative to control the digital camera to capture pictures of the wall from pre-determined capturing positions.

3. The UAV of claim 2, wherein a motor control module is operative to slow down the movement of the UAV at the pre-determined capturing positions.

4. The UAV of claim 2 or claim 3, wherein a distance between two adjacent capturing position is equal to an extension of a capturing area of a captured picture in a

flight direction of the UAV minus a pre-determined overlap in the flight direction, wherein the predetermined overlap is within the pre-determined range.

5. The UAV of claim 4, wherein the motor control module controls the propulsion means such that the pre-determined flight path results in a corresponding scanning path, the scanning path comprising a meandering path, the meandering path comprising capturing segments in a first direction and connecting segments in a second direction, the capturing segments being joined by the connecting segments.

6. The UAV according to one of the preceding claims, wherein the digital camera comprises a visible light sensor.

7. The UAV according to one of the preceding claims, wherein the digital camera comprises a radar sensor.

8. The UAV according to one of the preceding claims, wherein the digital camera comprises an infrared sensor.

9. The UAV according to one of the preceding claims, wherein the digital camera comprises an acoustic transducer.

10. Method for controlling a UAV with a digital camera, the method comprising:
- identifying at least one no-scan area of a wall of a building to determine a pre-determined flight path,
- controlling a propulsion means of the UAV to move the UAV along the pre-determined flight path,
- controlling the digital camera to capture pictures of the wall at pre-determined capturing positions, such

that adjacent pictures of the captured pictures have an overlap in a predetermined range.

11. The method according to claim 10, comprising
- controlling the propulsion means to slow down the movement of the UAV at the pre-determined capturing positions.

12. The method according to claim 10, comprising
controlling the propulsion means such that a distance between two adjacent capturing positions is equal to an extension of a capturing area of a captured picture in a flight direction of the UAV minus a pre-determined overlap in the flight direction, wherein the predetermined overlap is within the pre-determined range.

13. The method according to one of the claims 10 to 12, comprising
controlling the propulsion means such that the predetermined flight path results in a corresponding scanning path, the scanning path comprising a meandering path, the meandering path comprising capturing segments in a first direction and connecting segments in a second direction, the capturing segments being joined by the connecting segments.