pulse gun. The payload can also be an explosive, equipped with a means for propelling at a distance away.

In **figure 9**, it is a range finder 3001 which is attached to the end of the arm 1040, via the base 3010. The range finder is rotatably mounted for a continuous multi-turn rotation with respect to the base. The figure shows the deployed configuration of the arm 1040. Instead of the range finder, a camera can also be installed. The robot also has an automatic function for protecting the arm, controlling the retraction thereof to the storage configuration when it is detected that the robot has a speed or acceleration higher than a security threshold.

The robot can also have a control such that, when the robot is immobilized in a blocked position, due to an obstacle on the ground, it uses its arm to unblock itself, by passing from the storage configuration RX to one of the deployment configurations D1 or D2.

In **figure 10**, an alternative embodiment of the arm of the robot is shown. Here, the arm, denoted 4040, is in translation with respect to the body 1030 of the robot, perpendicularly to the plane defined by the wheels. It has a large dimension shorter than the distance between both planes of motion P1 and P2. In the folded position, it does not go beyond the plane P1 or the plane P2. In the deployment configuration, it protrudes through the first or second of these planes. The robot can use its arm for releasing itself from a situation in which it is blocked on a rock or an obstacle.

It is specified that the robot can be equipped with two tracks or with wheels, in particular with three, four or six wheels. The body of the robot can comprise a shell made of polyurethane or ABS, the polyurethane being preferred for its strength properties. The wheel tires are

CLAIMS

1. Rolling robot ~~(1000; 2000)~~ comprising moving means ~~(1010, 1020; 2010, 2020)~~ allowing it to move in parallel to a first plane of motion ~~(P1)~~ or, alternatively, in parallel to a second plane of motion ~~(P2)~~, as well as a body ~~(1030; 2030)~~, the volume of which is confined between both planes of motion ~~(P1, P2)~~, ~~characterized in that~~ ~~it~~ the rolling robot also ~~comprises~~ comprising an arm ~~(1040; 2040)~~ mounted on the body and adopting either a storage configuration ~~(R)~~, in which it is confined between both planes of motion, or a first deployment configuration ~~(D1)~~, in which it protrudes through the first plane of motion ~~(P1)~~, or a second deployment configuration ~~(D2)~~ in which it protrudes through the second plane of motion ~~(P2)~~, wherein the arm has a function for disengaging the robot from a position in which it is blocked and is further equipped to receive a payload.

2. The rolling robot according to claim 1, wherein the arm ~~(1040; 2040)~~ is rotatably articulated around an axis ~~(X)~~.

3. The rolling robot according to one of the preceding claims, wherein the arm ~~(1040; 2040)~~ is moved by a motor, the power of which is transmitted by a planetary or endless screw speed reducer.

4. The rolling robot according to one of the preceding claims, equipped with flat brushless motors ~~(1011, 1021)~~ for its propulsion.

5. The rolling robot according to one of the preceding claims, comprising also a function for protecting the arm ~~(1040; 2040)~~, controlling the storage thereof to the integrated configuration when it is detected that the robot has a speed or acceleration higher than a security threshold.

6. The rolling robot according to one of the preceding claims, having a control so that, when the robot is

immobilized in a blocked position, it uses the arm ~~(1040, 2040, 4040)~~ to unblock itself, by passing from the storage configuration ~~(X)~~ to one of the deployment configurations ~~(D1, D2)~~.

7. The rolling robot according to one of the preceding claims, wherein the arm ~~(1040; 2040)~~ comprises a clamp structure for receiving a payload ~~(3000)~~.

8. The rolling robot according to one of the preceding claims, wherein the arm ~~(1040; 2040)~~ comprises an electrical connector ~~(3012)~~ for transmitting information from or to a payload ~~(3000)~~ installed on the arm, or electrical power to the payload ~~(3000)~~.

9. The rolling robot according to the preceding claim, comprising also a rotating manifold ~~(3013)~~ for operating a payload ~~(3000)~~ installed on the arm ~~(1040; 2040)~~ with a multi-turn free rotation.

10. The rolling robot according to one of the preceding claims, comprising also an angular position sensor ~~(3014)~~ for a payload ~~(3000)~~ rotatably installed on the arm ~~(1040; 204)~~.

11. The rolling robot according to one of the preceding claims, wherein the arm ~~(1040; 2040)~~ is equipped to receive a payload ~~(3000)~~ to be attached by clipage.

12. The rolling robot according to one of the preceding claims, wherein the arm ~~(1040; 2040)~~ is equipped with a payload ~~(3000)~~ such as a person neutralization device, an explosive and a means for propelling said explosive, or a range finder.

13. The rolling robot according to one of the preceding claims, wherein the arm ~~(1040; 2040)~~ comprises a radio antenna.

14. The rolling robot according to one of the preceding claims, equipped with wheels ~~(1010, 1020; 2010, 2020)~~ or tracks.

15. The rolling robot according to one of the preceding claims, adapted for outside military operations.