

Wheeled Mobile Robot: Design And Implementation Of Wheeled Mobile Robot Using Intelligent Controllers By Mohammed Zeki Al-Faiz

By Mohammed Zeki Al-Faiz

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The wheeled mobile robot has been widely used in various fields nowadays. Combining with a contest of mobile robot used for sorting and conveying objects, this paper

<http://www.scientific.net/AMR.902.207>

Author Paper Title Schedule; P0639: Dynamic Consensus of Multi-Agent Systems under Markov Packet Losses with Defective Transition Probabilities: We31.5: P0675

<http://www.icarcv.org/2012/cms/program/programSearchByAuthor.asp?Search=1>

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<http://researchr.org/publication/icra%3A2002>

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<http://www.worldcat.org/title/hybrid-control-design-for-a-wheeled-mobile-robot/oclc/465044518>

This paper presents a novel implementation of an integral sliding-mode controller (ISM) on a two-wheeled mobile robot (2 WMR). The 2 WMR consists of two wheels in

<http://ieeexplore.ieee.org/xpl/articleDetails.jsp?arnumber=6603306>

Mohammed Al-Shaboti. Design and implementation. Application of new braided soft actuator design in biomimetic robot locomotion. Adaptive Mobile Robotics

http://scival-expert.utm.my/orgaPubs.asp?o_id=2&order=&oe_id=1&selected_year=2012

model and control strategy for a Nonholonomic Wheeled Mobile Robot and intelligent controllers for the ship Al doped Si film was

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Wheeled mobile robots 77 system. The second approach is, however, more systematic and simpler, not least because of the conciseness of the notation used.

<http://www.tandfonline.com/doi/pdf/10.1163/1568553053020241>

Akram M. Zeki , Mohammed Z of concept design of a folding bicycle by using light on the obtained image using standard PI controllers.

http://www.iium.edu.my/irrie/11/info/Abstract_Jan_6.docx

Differential Drive Wheeled Mobile Robot (WMR) Control Using Fuzzy recognition of robots, the design and implementation of an internet-based smart

<http://dl.acm.org/citation.cfm?id=1825865&prelayout=flat>

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The considered two-wheeled mobile robot is shown in Fig. 1, Design of controller. For the robot shown in Fig. 1, the following controller is considered,

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