International Journal on Recent Researches In Science, Engineering & Technology

(Division of Electronics and Communication Engineering)

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Research Paper

Available online at: www.jrrset.com

ISSN (Print) : 2347-6729
ISSN (Online) : 2348-3105

Volume 4, Issue 5, May 2016.

JIR IF : 2.54
DIIF IF : 1.46
SJIF IF : 1.329

AUTOMATED PATTERN MOVEMENT TO REDUCE FALLING RISK FOR ROBOT USING MODIFIED SELECTION ALGORITHM

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Abstract **-** Robot locomotion are wheel based that are found to be hard in certain areas like complex terrains slope. In composite location Robot movements varies like in alteration and combination. The proposed project consists of Bayes Algorithm used to resolve the Issues for selection algorithm locomotion. Using culling algorithm locomotion to cutoff the dynamic falling and improve the performance. Different types of locomotion, such as bipedal and Quadra pedal walking, have specific and different capabilities. Most frequent falling of two leg robot is unavoidable on different terrains such as slopes, steps, gravel paths etc. My proposed System on robot navigation on challenging surfaces using Bayesian algorithm and optimal selection. Narrow algorithm may not solve directional needs. Multiple algorithm and selecting of needed algorithm could solve all the issues of robot navigation. A real time model based on embedded controller and MEMS (Micro Electro Mechanical Systems) may provide effective solution to this Issue.

Keywords **–** Bayes algorithm, MEMS, Quadra pedal walking, Robot navigation, power dissipation.