

عنوان مقاله:

Increasing the defect and destruction of independent moving robots

محل انتشار:

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خلاصه مقاله:

Experience has shown that autonomous moving robots run on the ground in a dynamic environment are often spoiled and degraded. Generally, robots are not designed to manage and control effectively the failure or unpredictable conditions. But there is, however, a lack of a general approach that actually integrates the reliability and, in particular, the failure of the robot with the design of a robot. This paper presents a methodology that aims to integrate the principles of tolerance failure in designing a real-time robot control plan. An analysis of the method or type of failure has been performed to identify and identify the relevant failures. Therefore, mechanisms for identifying and detecting failures are justified. The failure identification is based on the behavioral failure test of the specified software components. The detection is based on the remaining principle and the analysis of the symptoms to identify the components of the software or hardware that is corrupted and the failure behavior. Finally, the improvement mechanism, based on the principle of quality, is proposed to adopt a robot control loop in accordance with current robot operating conditions and roles. This method has been used to control a 3D moving robot moving forward

کلمات کلیدی:

reliability, fault tolerance, recovery, detection, mobile robots

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