Adaptive Fuzzy Control for Autonomous Robot under Complex Environment

Tuong Phuoc Tho, Nguyen Truong Thinh, Nguyen Phuong Nam

Ho Chi Minh City University of Technology and Education, Viet Nam

In this paper, modeling and nonlinear fuzzy controller design for an autonomous robot are also presented. Based on the robot kinematics model, a nonlinear controller is designed and experiment with an autonomous robot are presented.