

ROBOT FOR PATH PLANNING OBSTACLE AVOIDANCE (RPPOA) MODEL IN HOMELAND ENVIRONMENT

Nisha P. Zode & Ujwal A. Lanjewar

*Research Scholar, Department of Electronics & Computer Science, Rashtrasant Tukadoji Maharaj, Nagpur University,
India*

HOD, VMV Commerce JMT Arts & JJP Science College, Wardhamannagar, Nagpur, India

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ABSTRACT

In this paper, problem of obstacle encountered by using various trials and examinations. It is suggested that in large surroundings home land surroundings with regards of robot requests, it can become more effective if the trials of robot considers acquaintance already gained and its results during rest of the plan of actions. This philosophy of trials on the robot is verified in a model test situation with home land environment. The main problem of obstacle examination considered is robot claims that is totally depend on time and environmental situation. This situation may be dangerous. It has also some planning of action with firstly unidentified home land situations. And different routes are to be proposed to take best possible route with short amount of time. After implementation of the program in to the arduino motherboard robot will learn automatically and self independently. The test results also suggest that the robot's behaviour be contingent on material about the environment.

KEYWORDS: *Path Planning, RPPOA, Homeland Environment*