

1. If (LS is Near) and (RS is near) then (ML is Fwd)(MR is Fwd) (1)

2. If (LS is Near) and (RS is close) then (ML is Off)(MR is Fwd) (1)

3. If (LS is Near) and (RS is Too_close) then (ML is Rev)(MR is Fwd) (1)

4. If (LS is close) and (RS is near) then (ML is Fwd)(MR is Off) (1)

5. If (LS is close) and (RS is close) then (ML is Rev)(MR is Rev) (1)

6. If (LS is close) and (RS is Too_close) then (ML is Rev)(MR is Fwd) (1)

7. If (LS is Too_close) and (RS is near) then (ML is Fwd)(MR is Rev) (1)

8. If (LS is Too_close) and (RS is close) then (ML is Fwd)(MR is Rev) (1)

9. If (LS is Too_close) and (RS is Too_close) then (ML is Rev)(MR is Rev) (1)

If

LS is

Too_close

close

Near

none

☐ not

and

RS is

Too_close

close

near

none

☐ not

Then

ML is

Rev

Fwd

Off

none

☐ not

and

MR is

Rev

Fwd

Off

none

☐ not

Connection

☐ or

☒ and

Weight:

1

Delete rule

Add rule

Change rule

<<

>>

FIS Name: Robotfuzzy_Bi

Help

Close