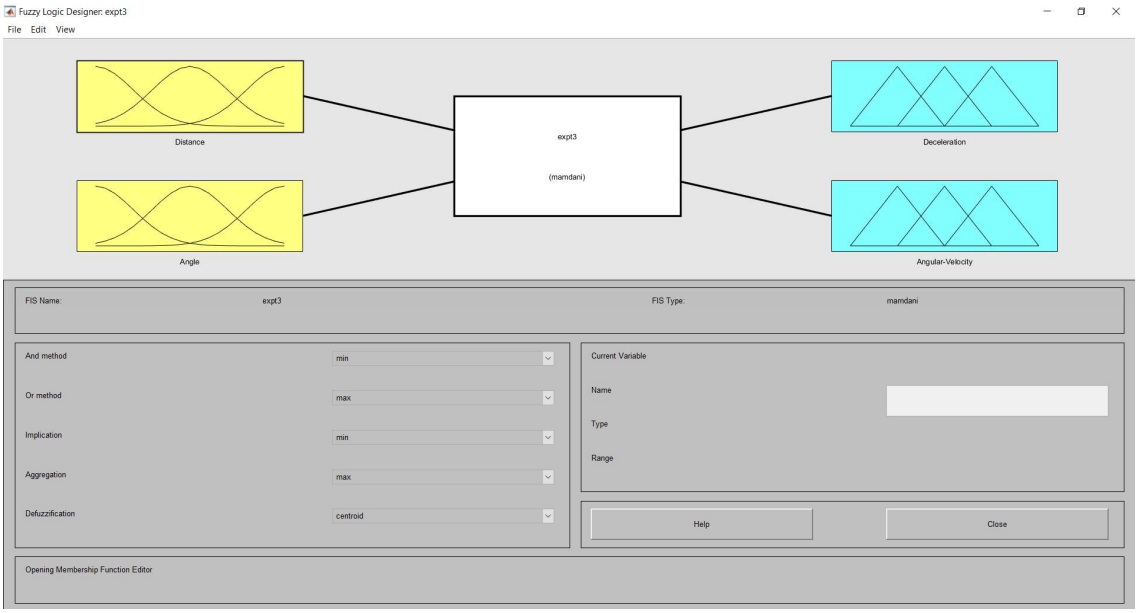
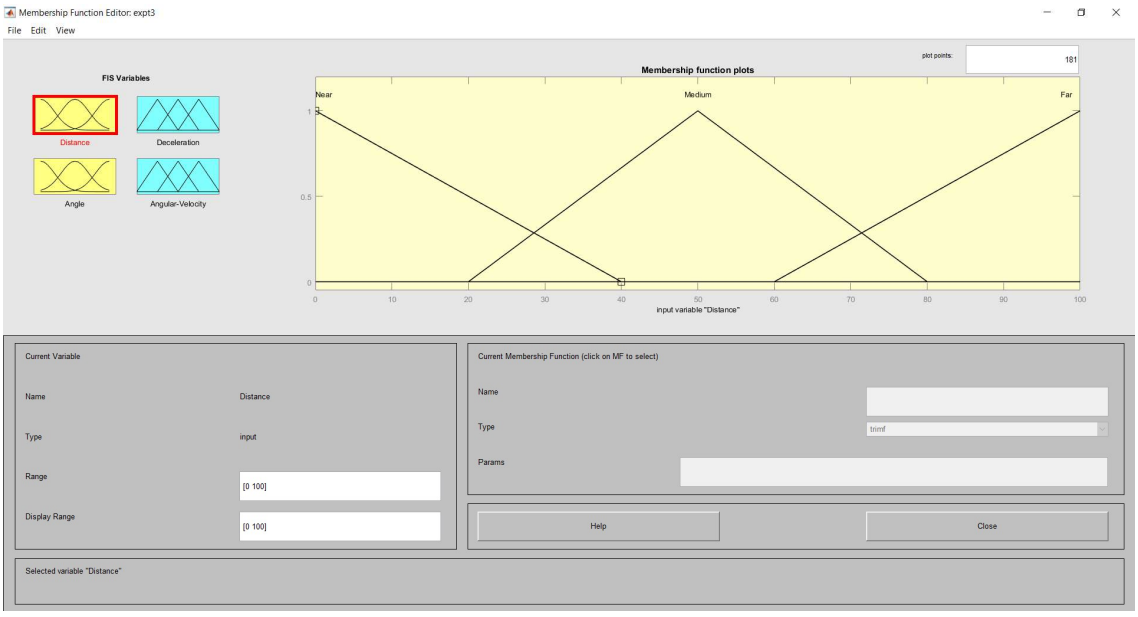
NNFL EXPT-3

Fuzzy Controller for Avoiding obstacles

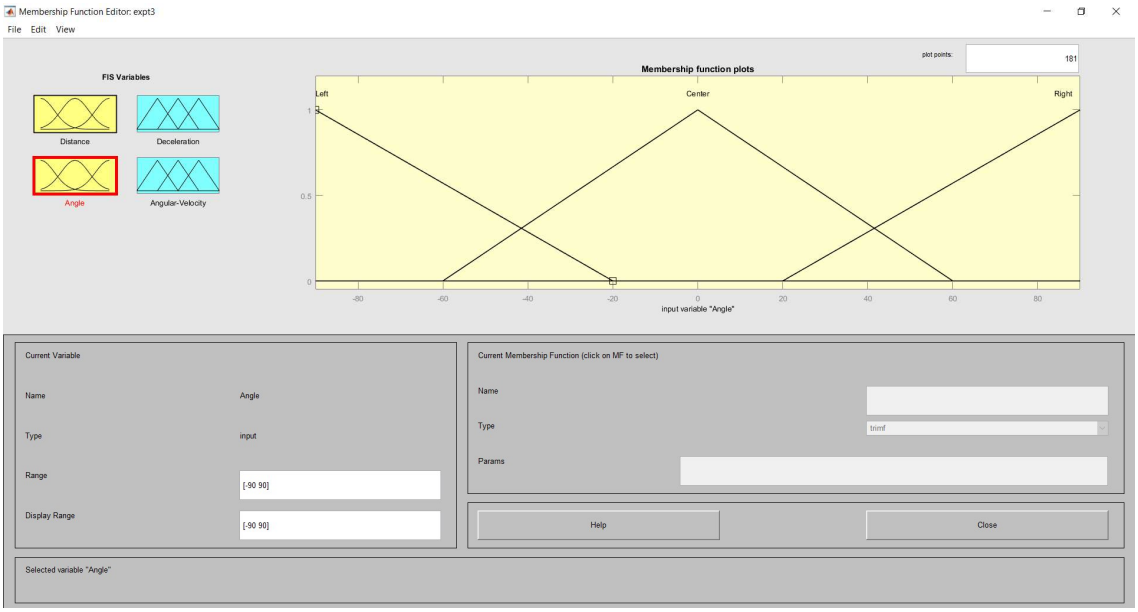


Inputs :

Membership Function of Distance from obstacle

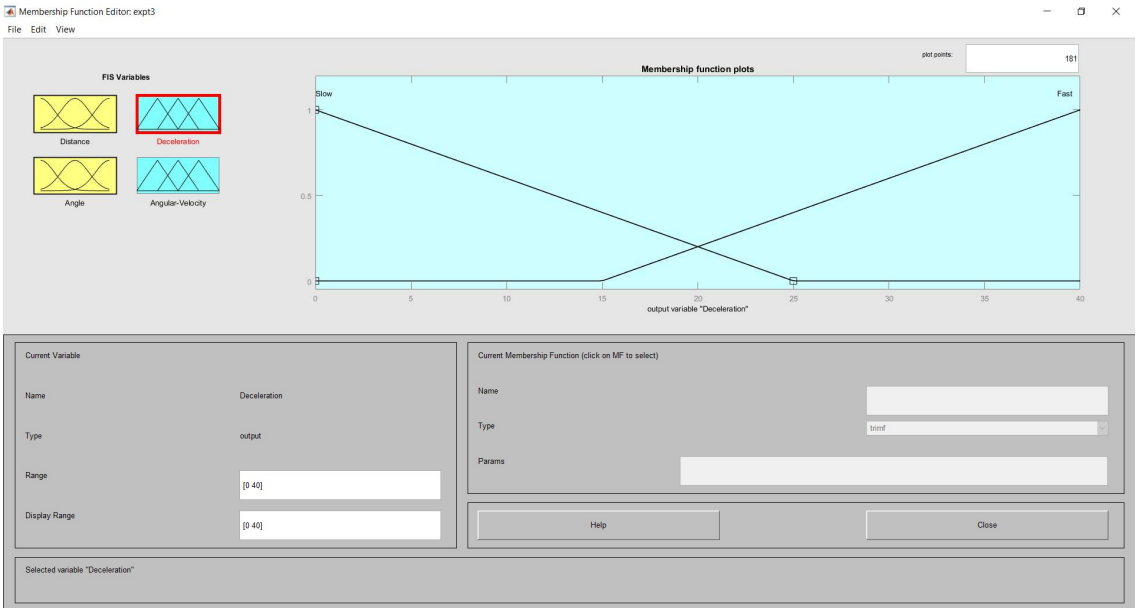


Membership Function of Sensor angle

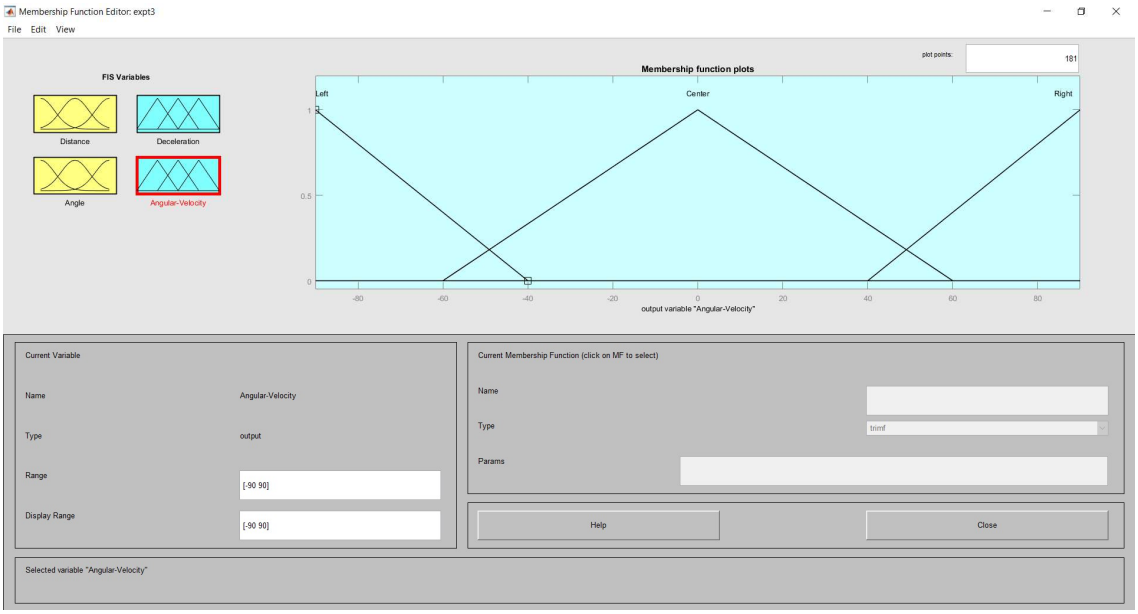


Output :

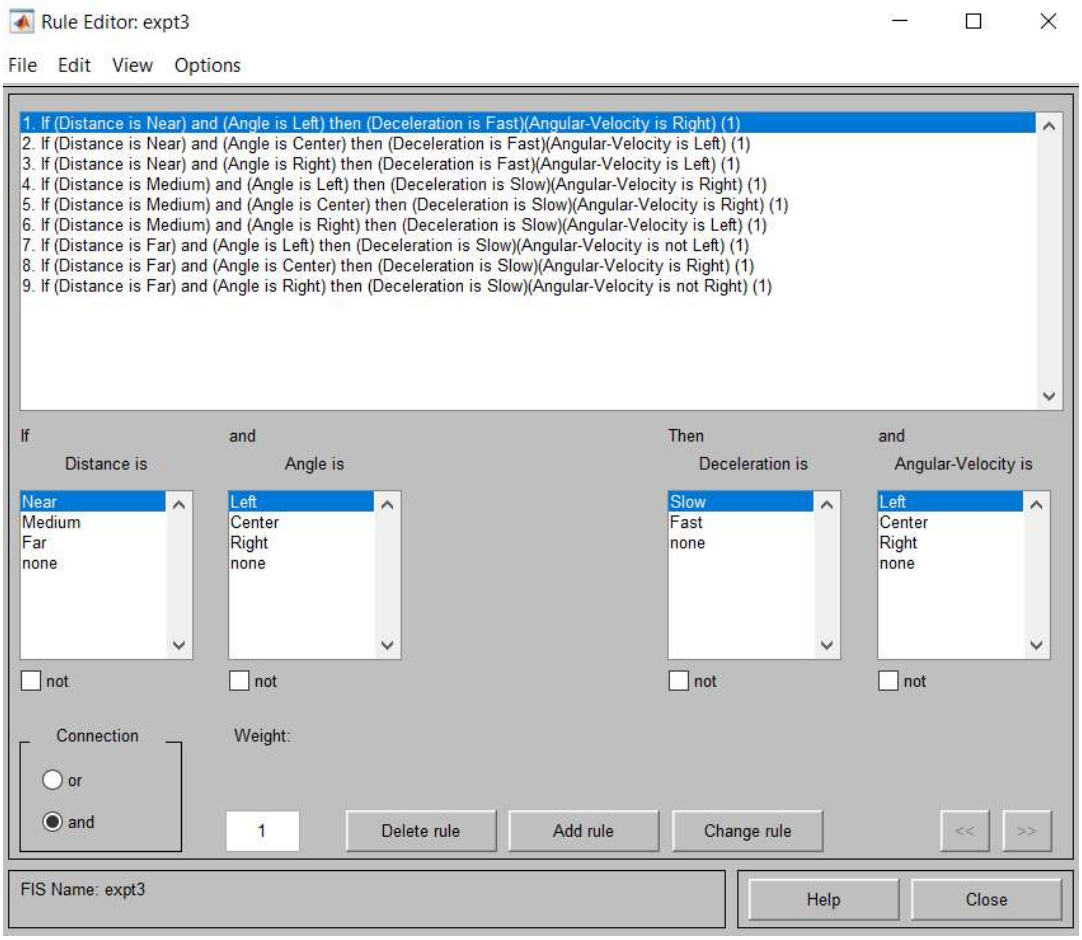
Membership Function of Deceleration



Membership Function of Angular Velocity

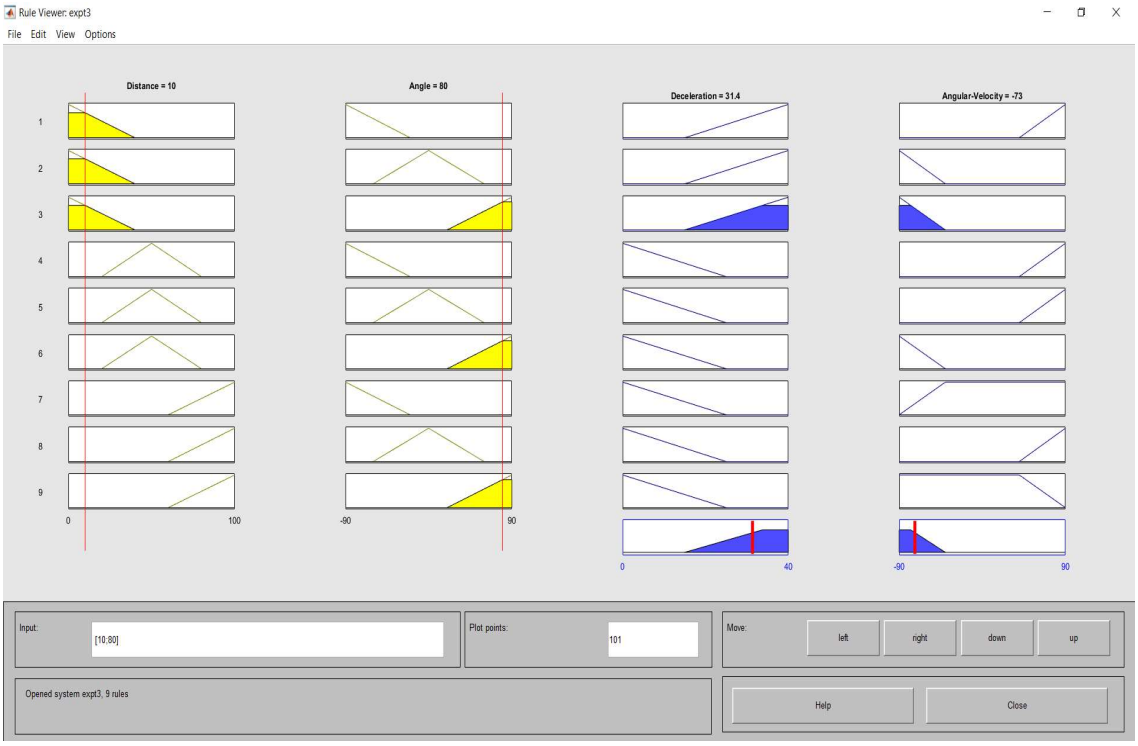


Rules

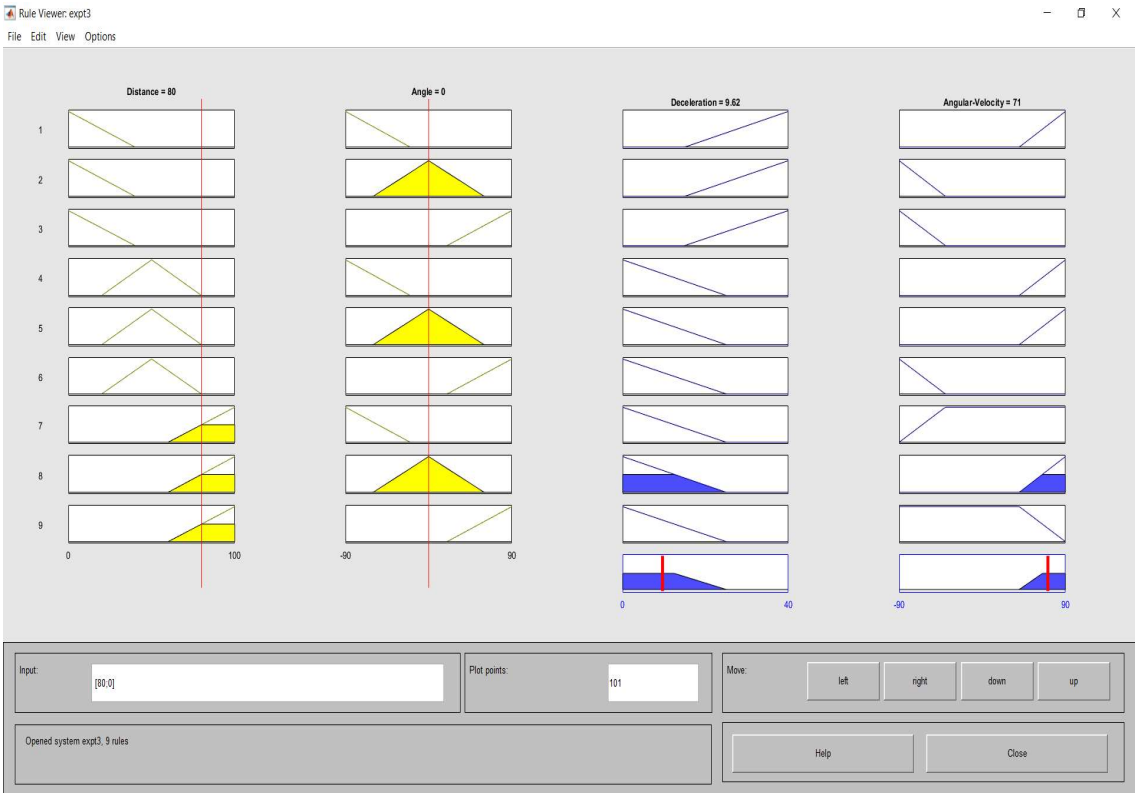


Output :

For Near obstacle and sensed at Right side of the vehicle

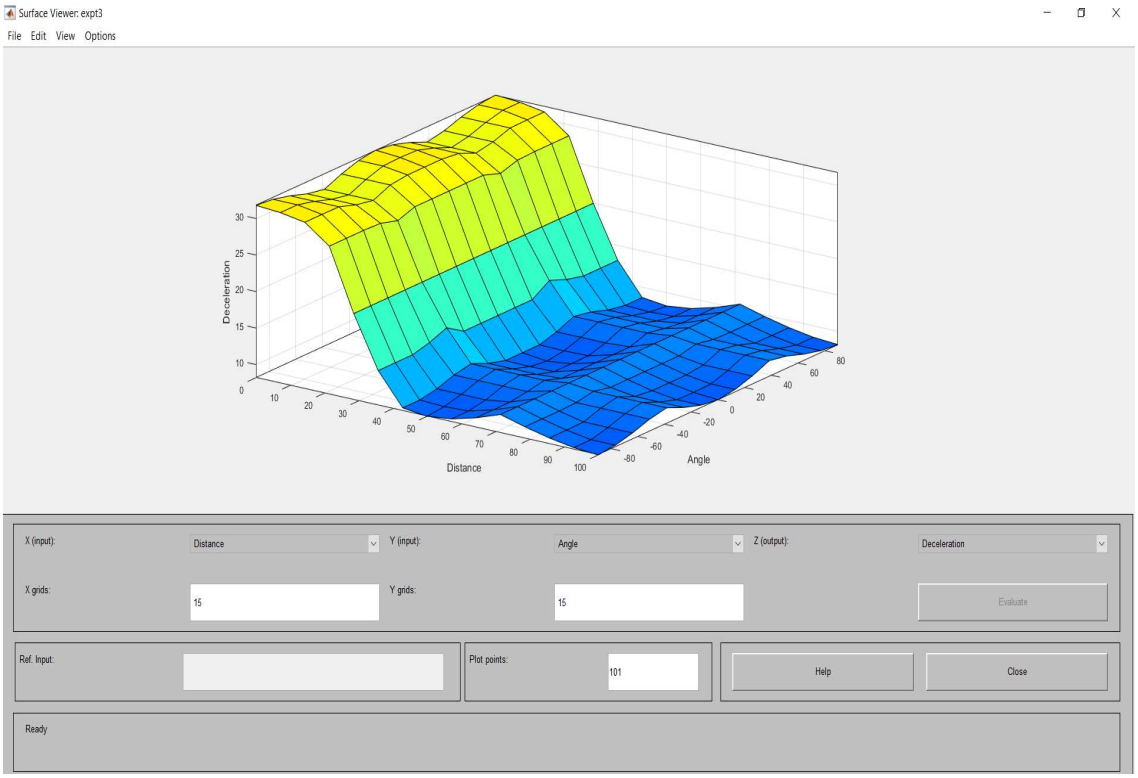


For Far obstacle and sensed at Center of the vehicle



Surface Viewer

Surface for Deceleration



Surface for Angular Velocity