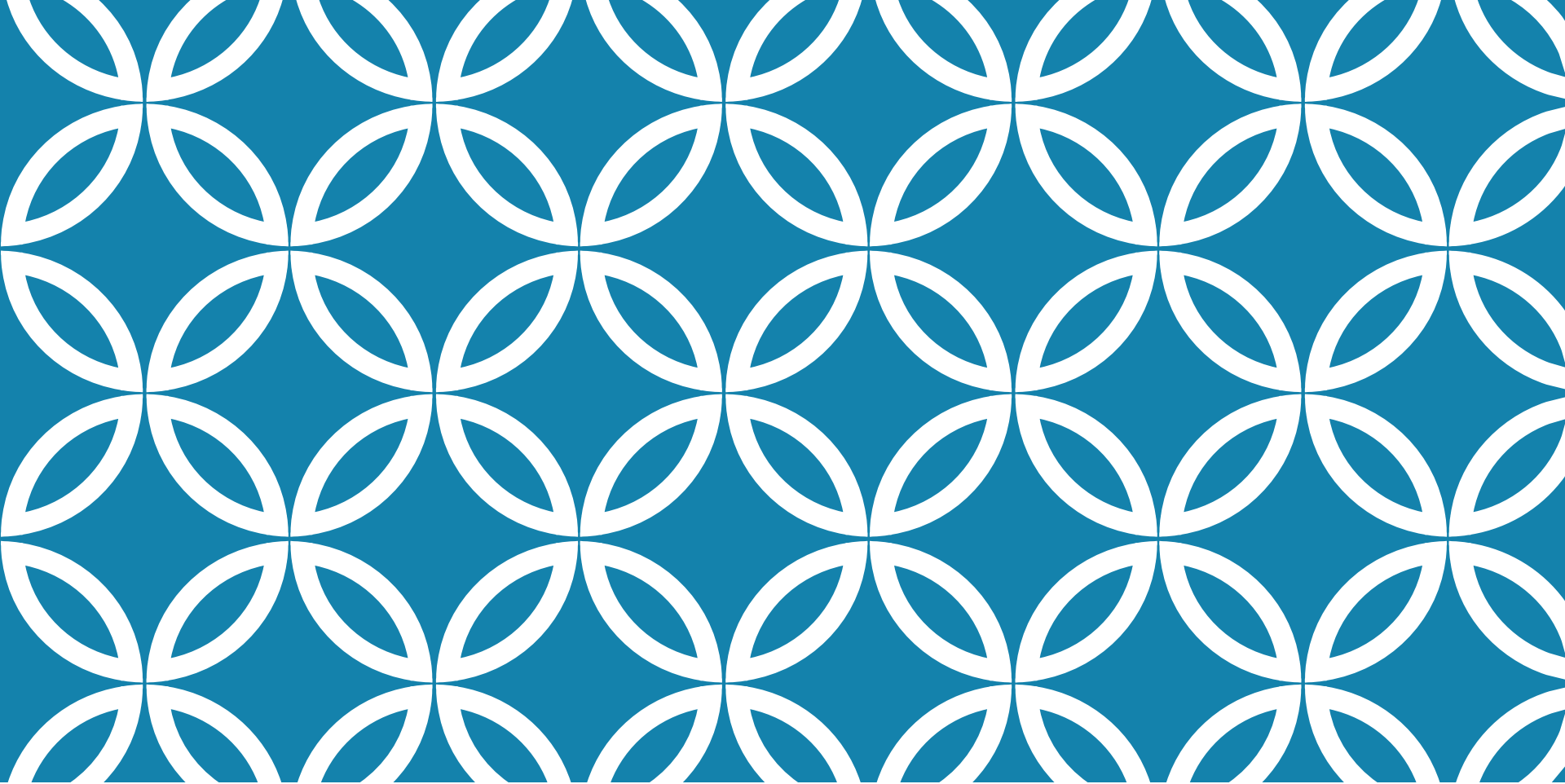
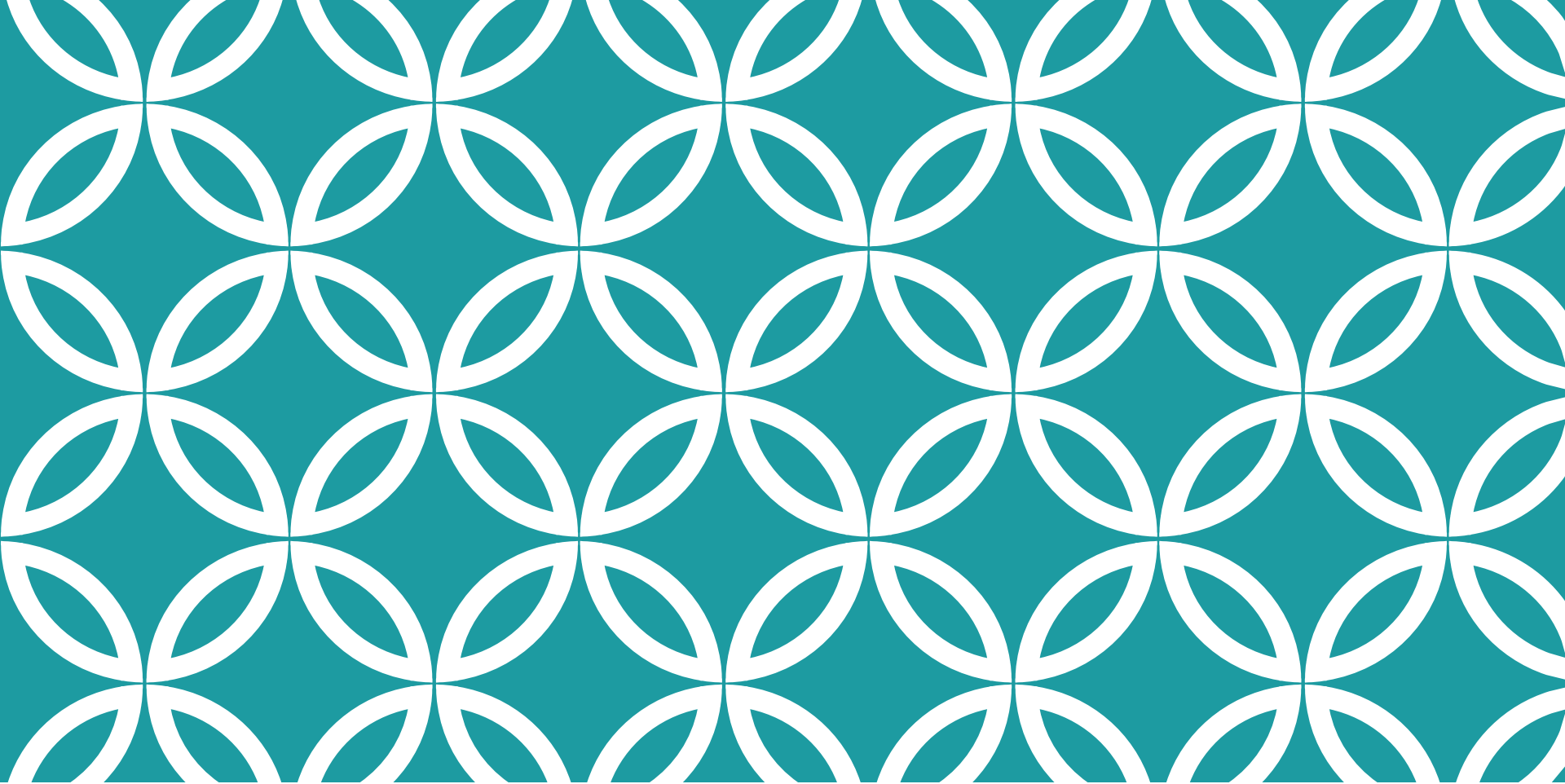




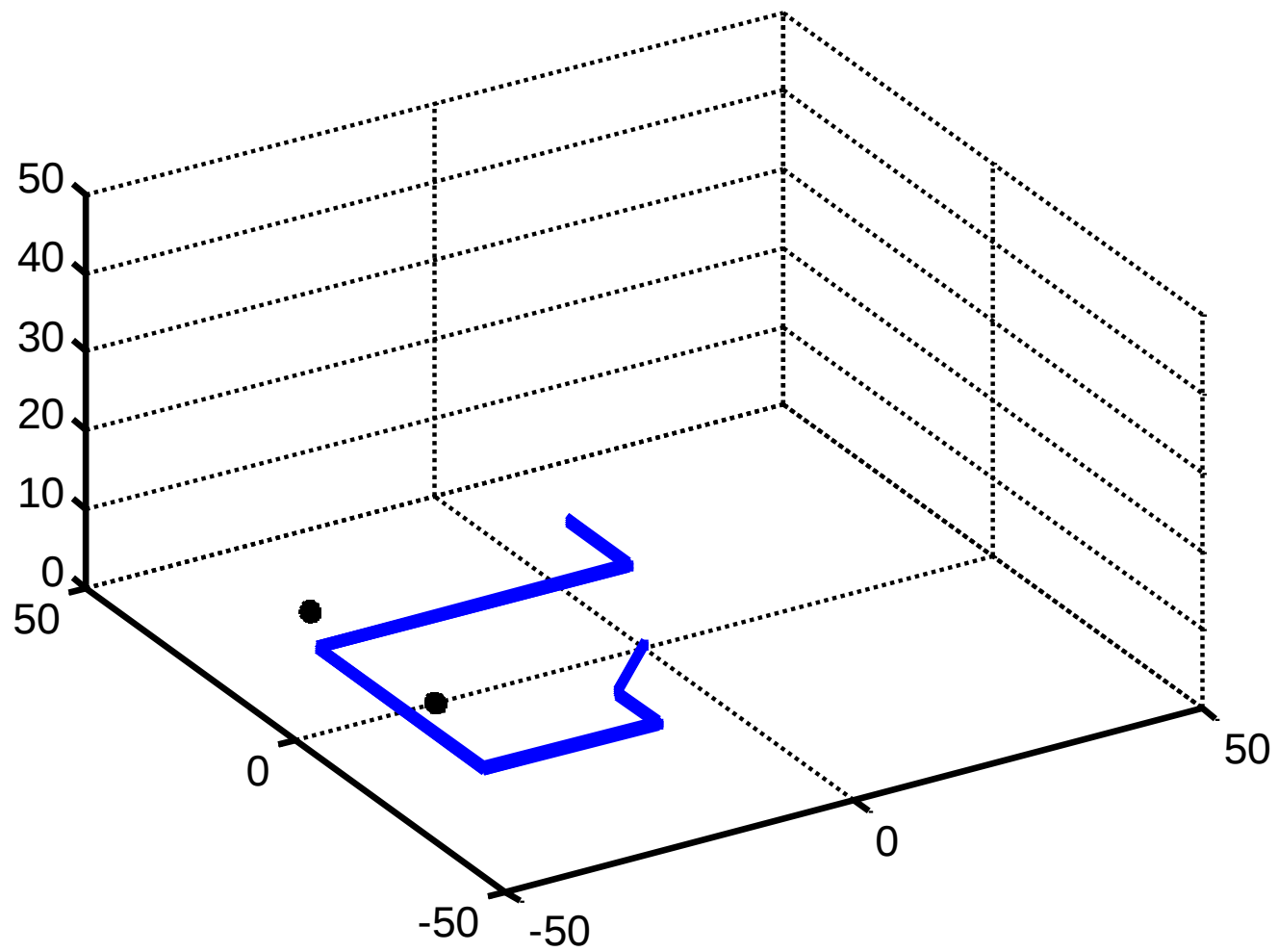
MOBILE ROBOT

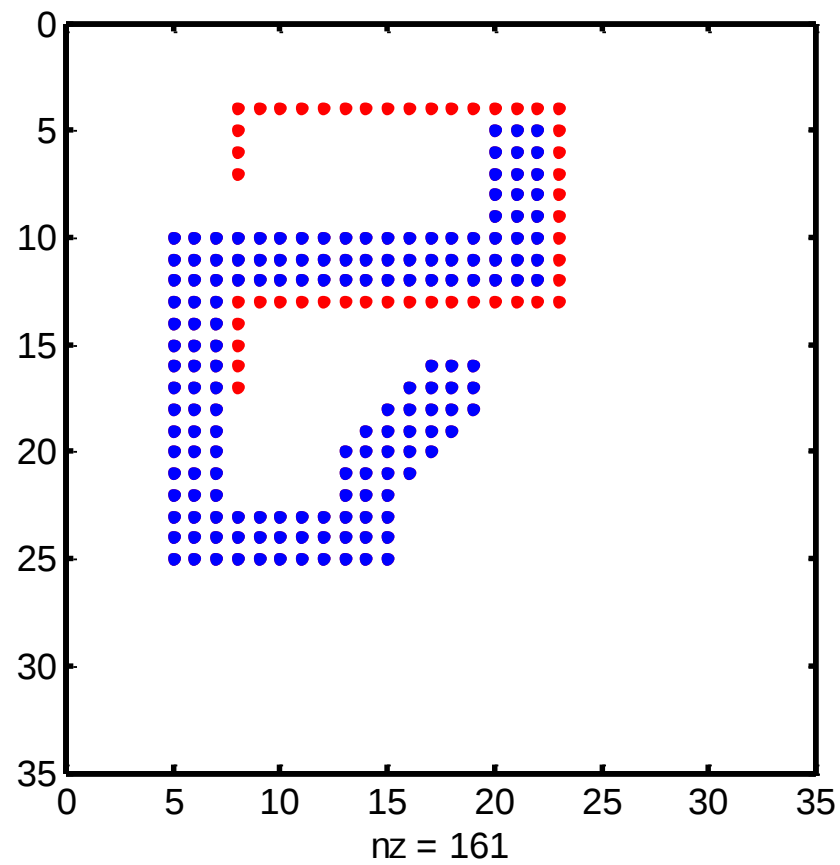
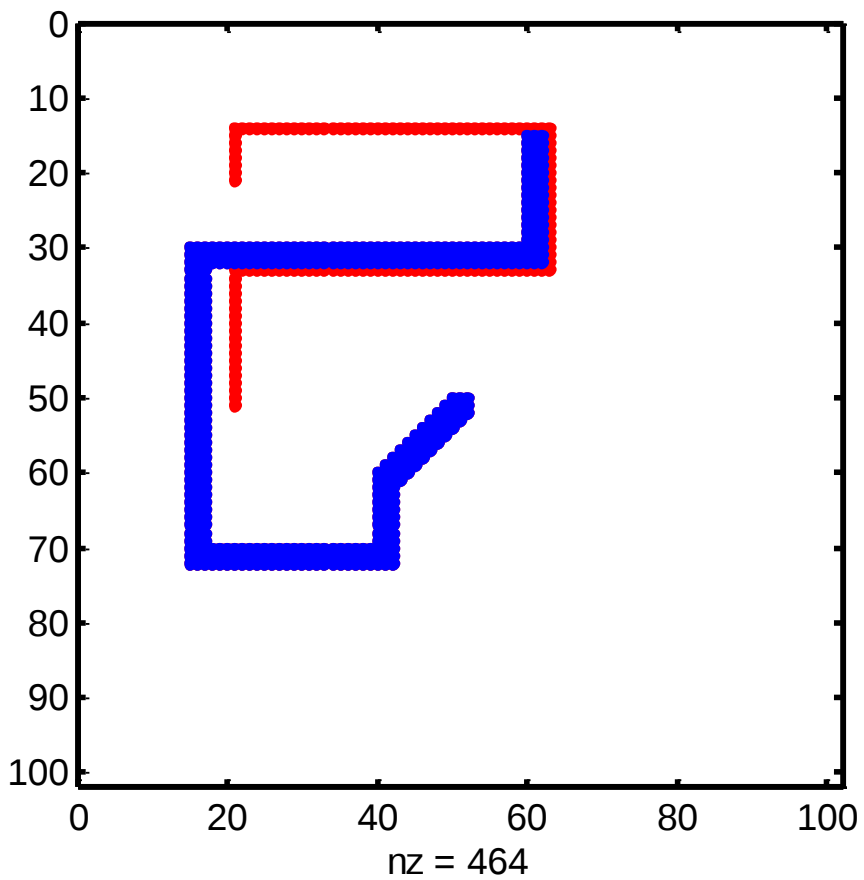
Simulation

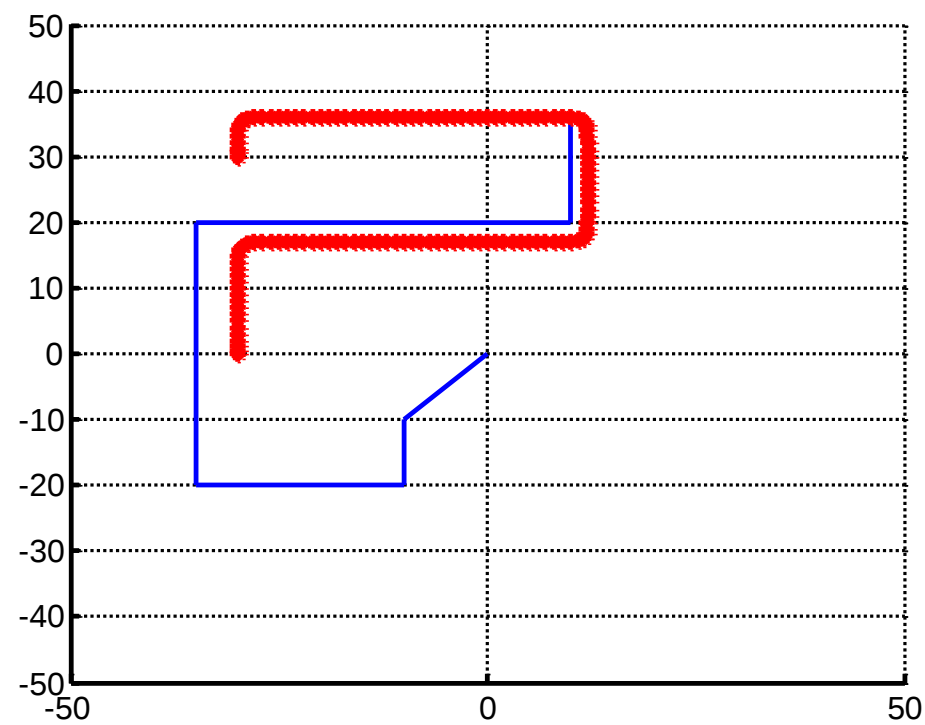
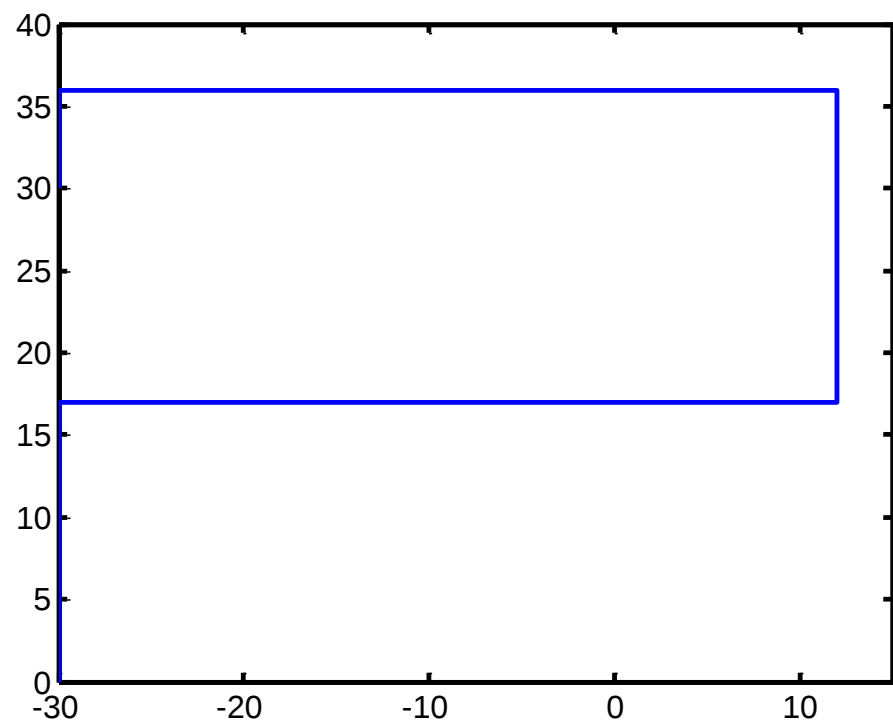


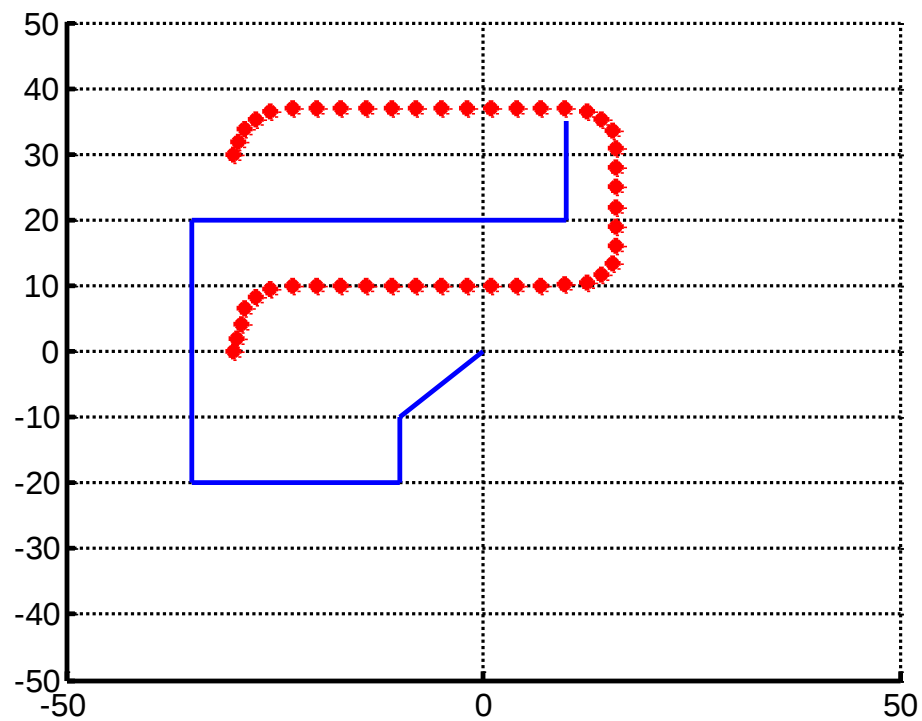
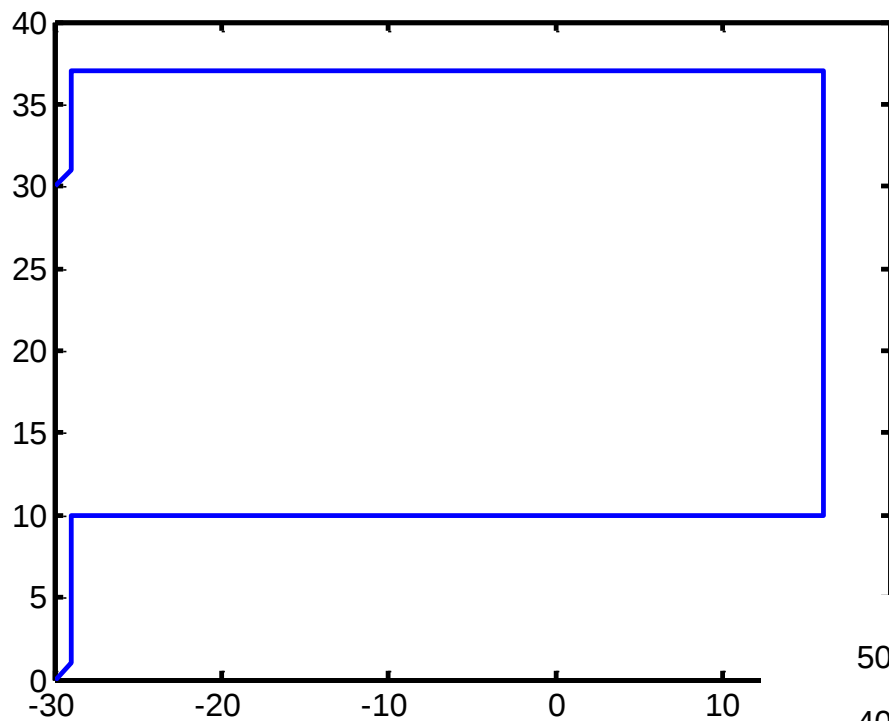
TEAM 1. THE ENVIRONMENT MODEL, TRAJECTORY DESIGN

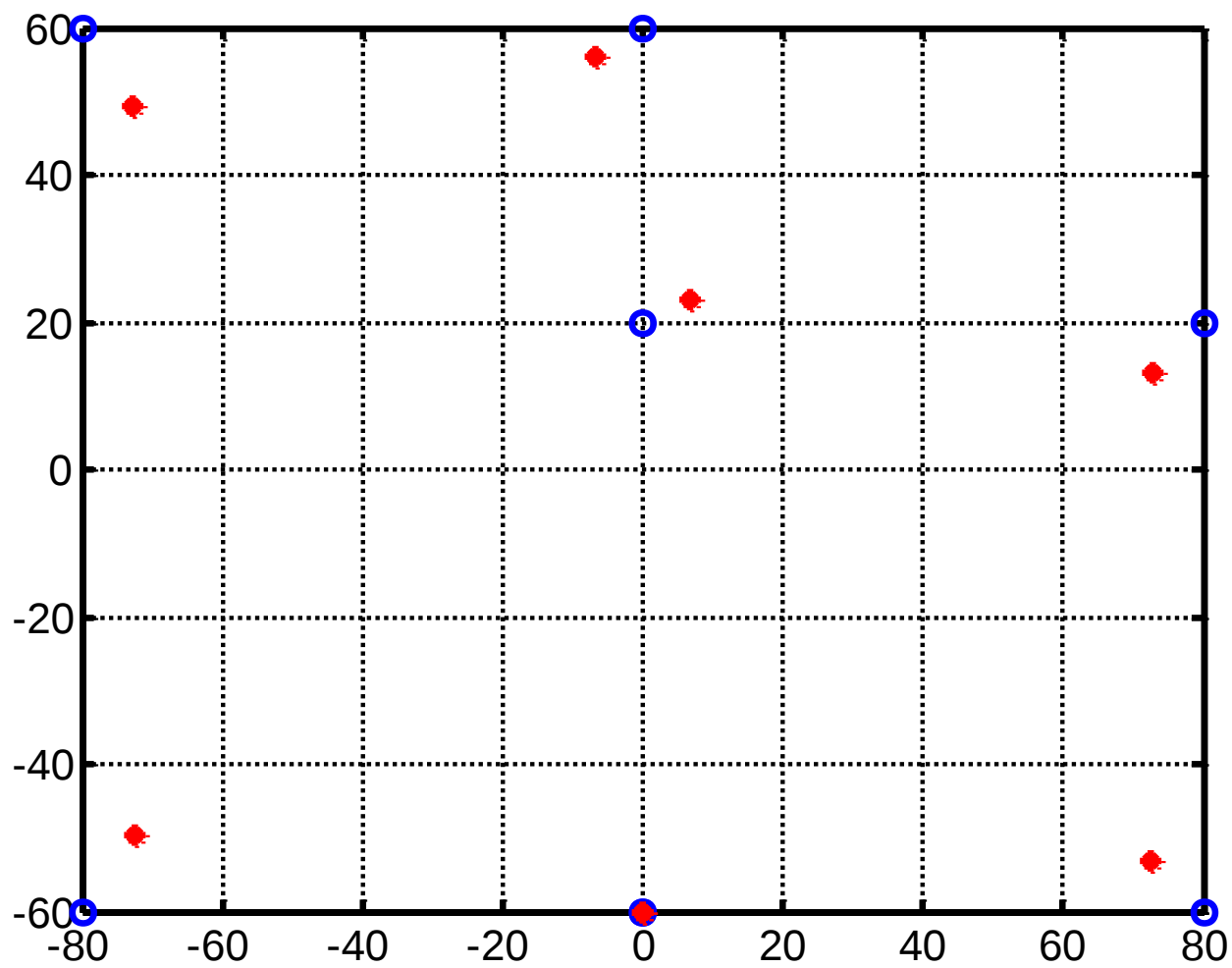


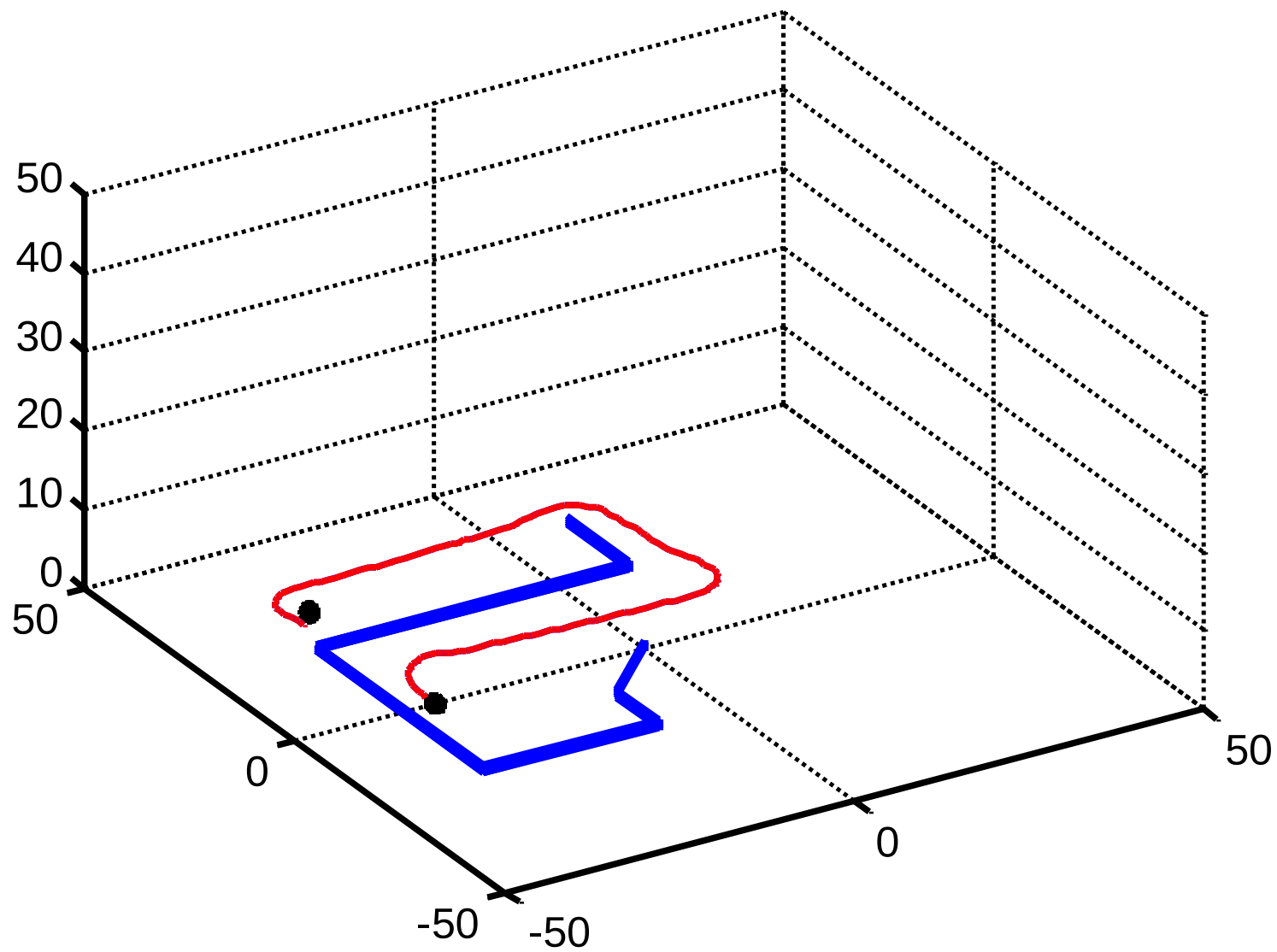


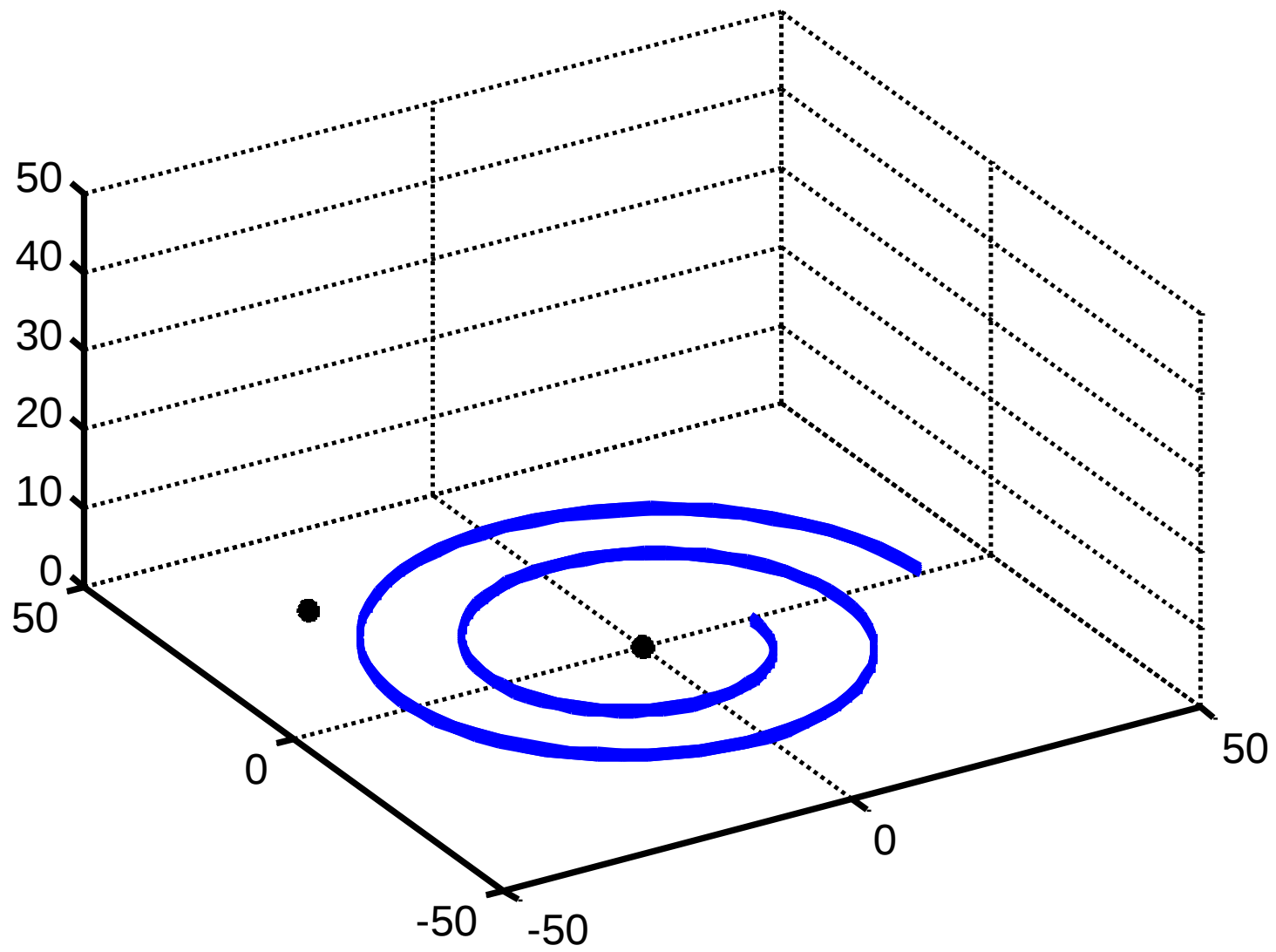


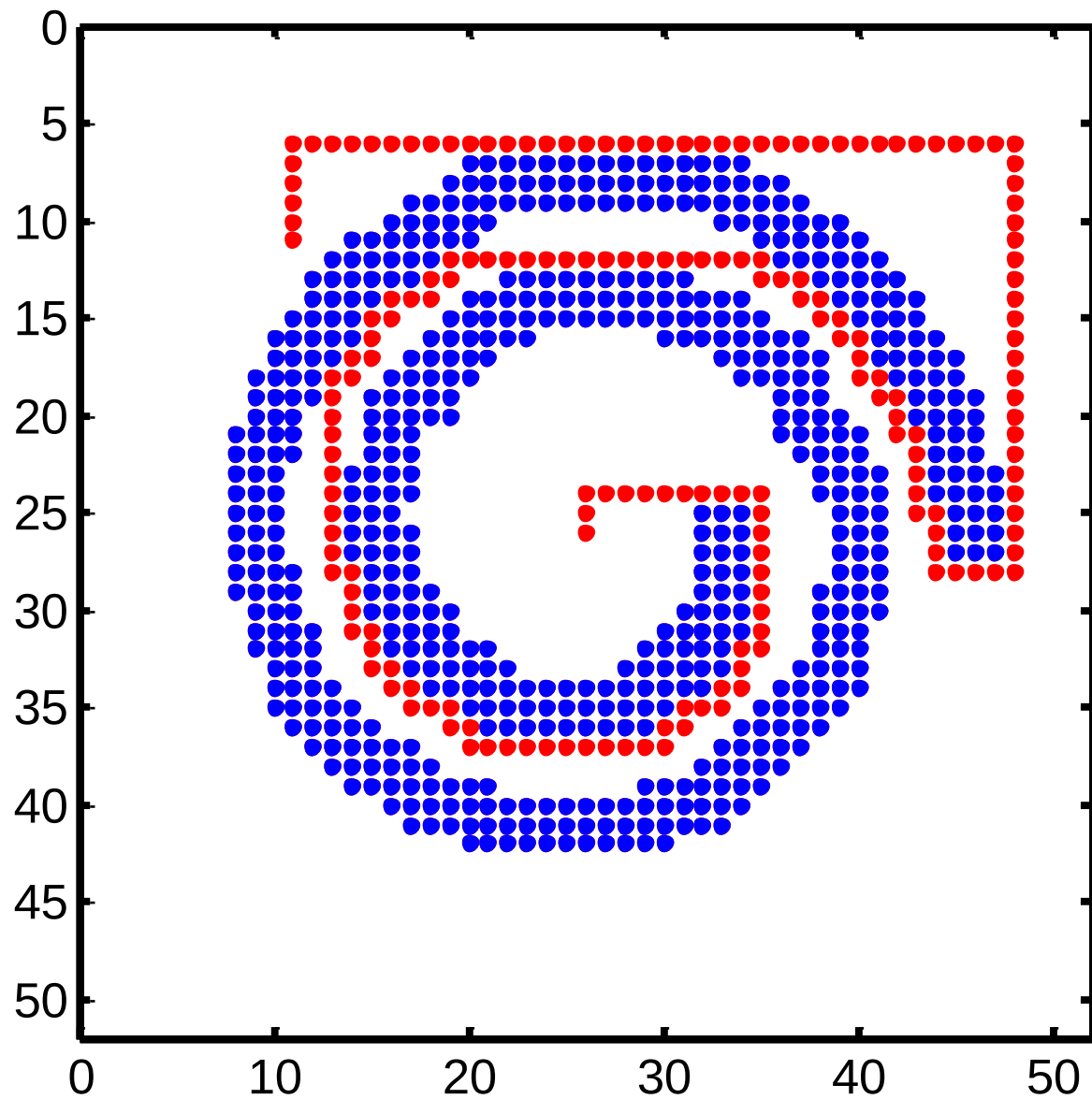


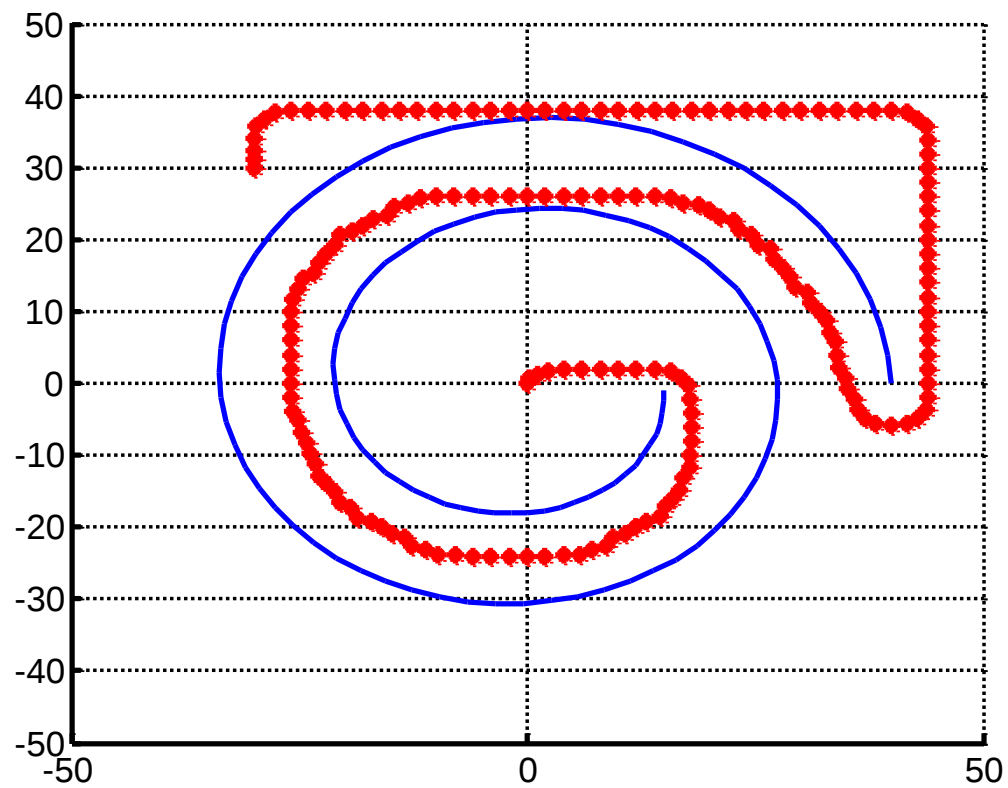
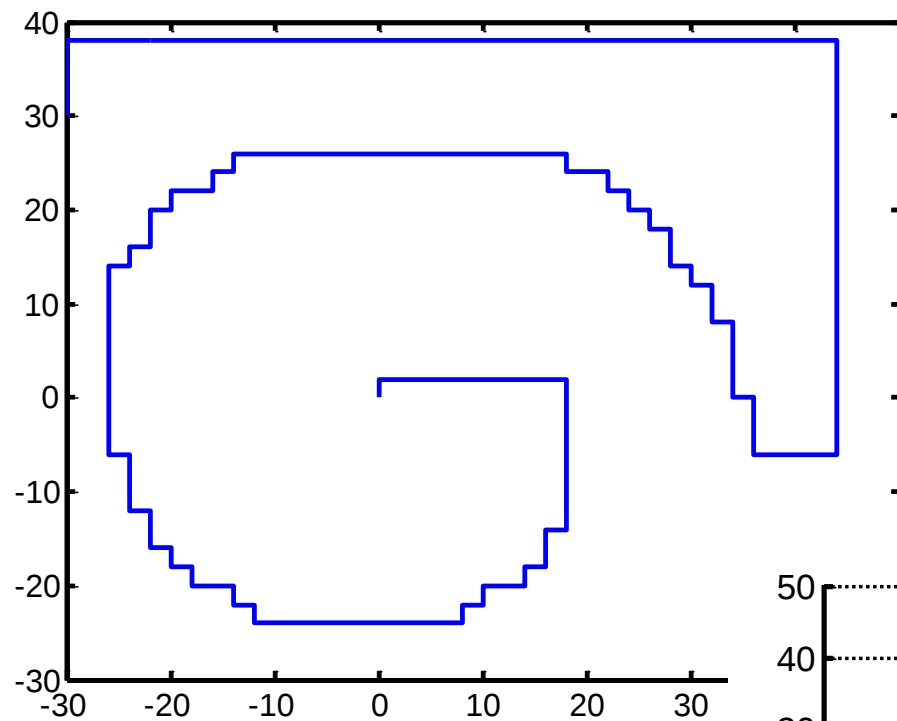


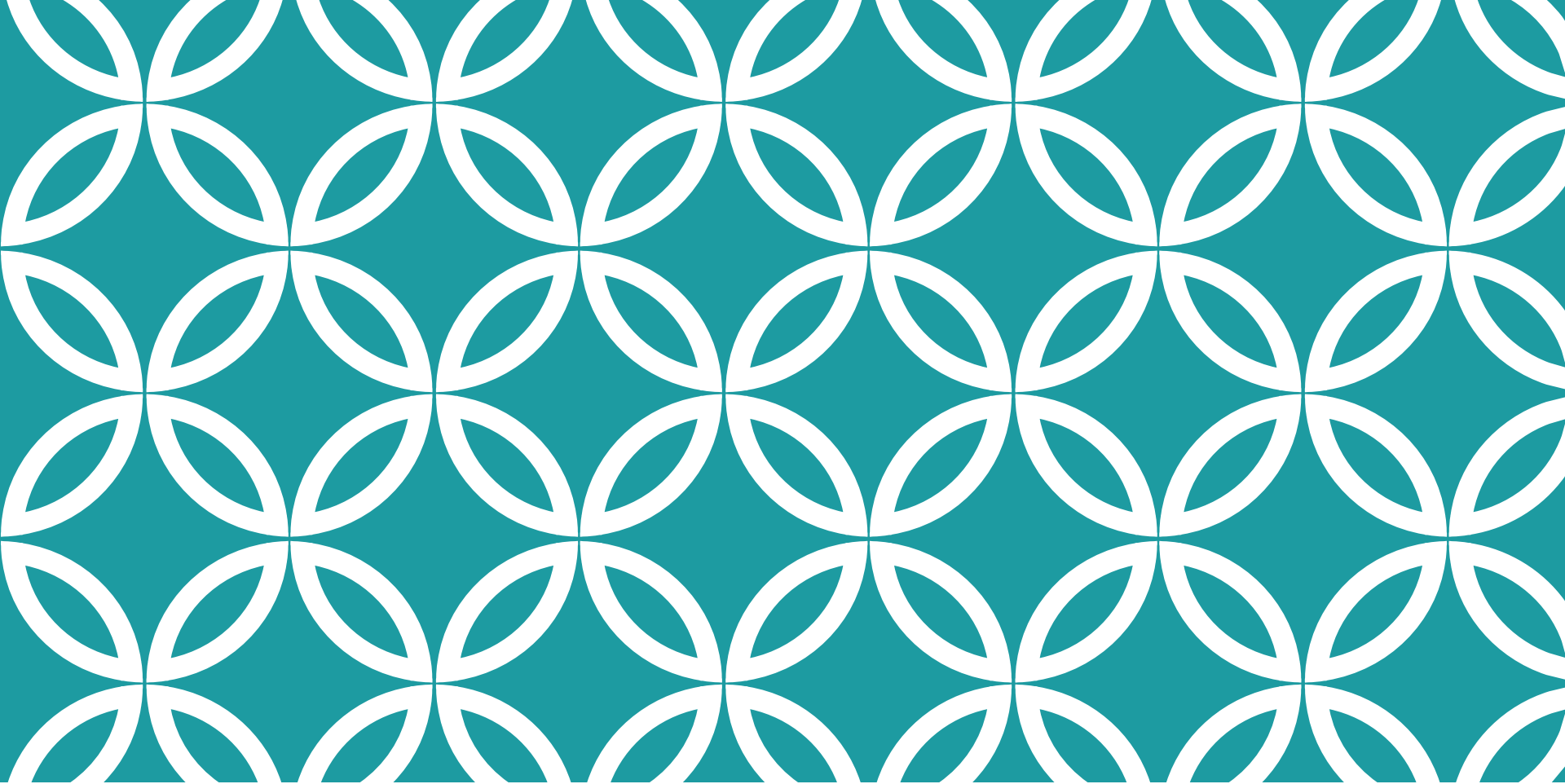






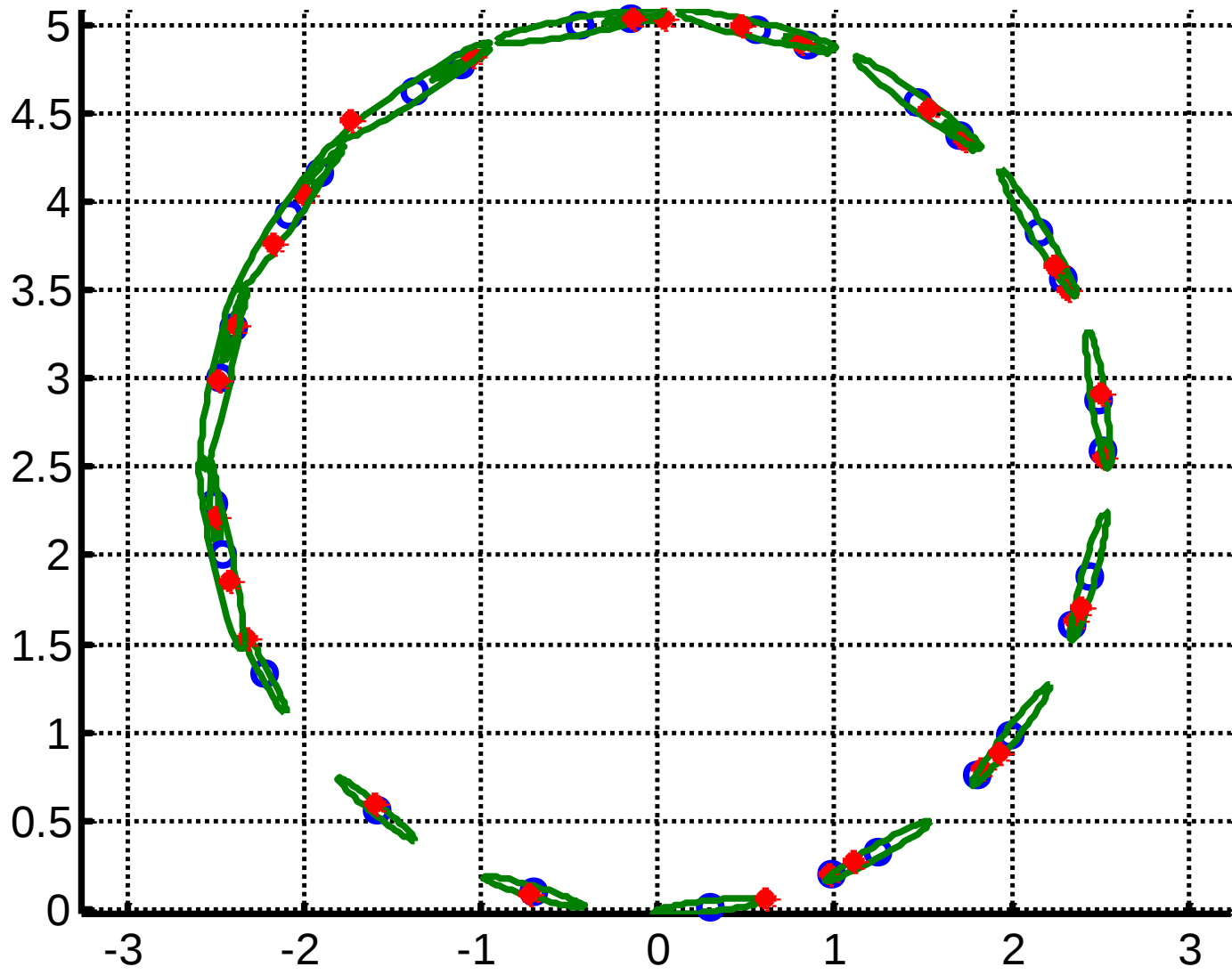


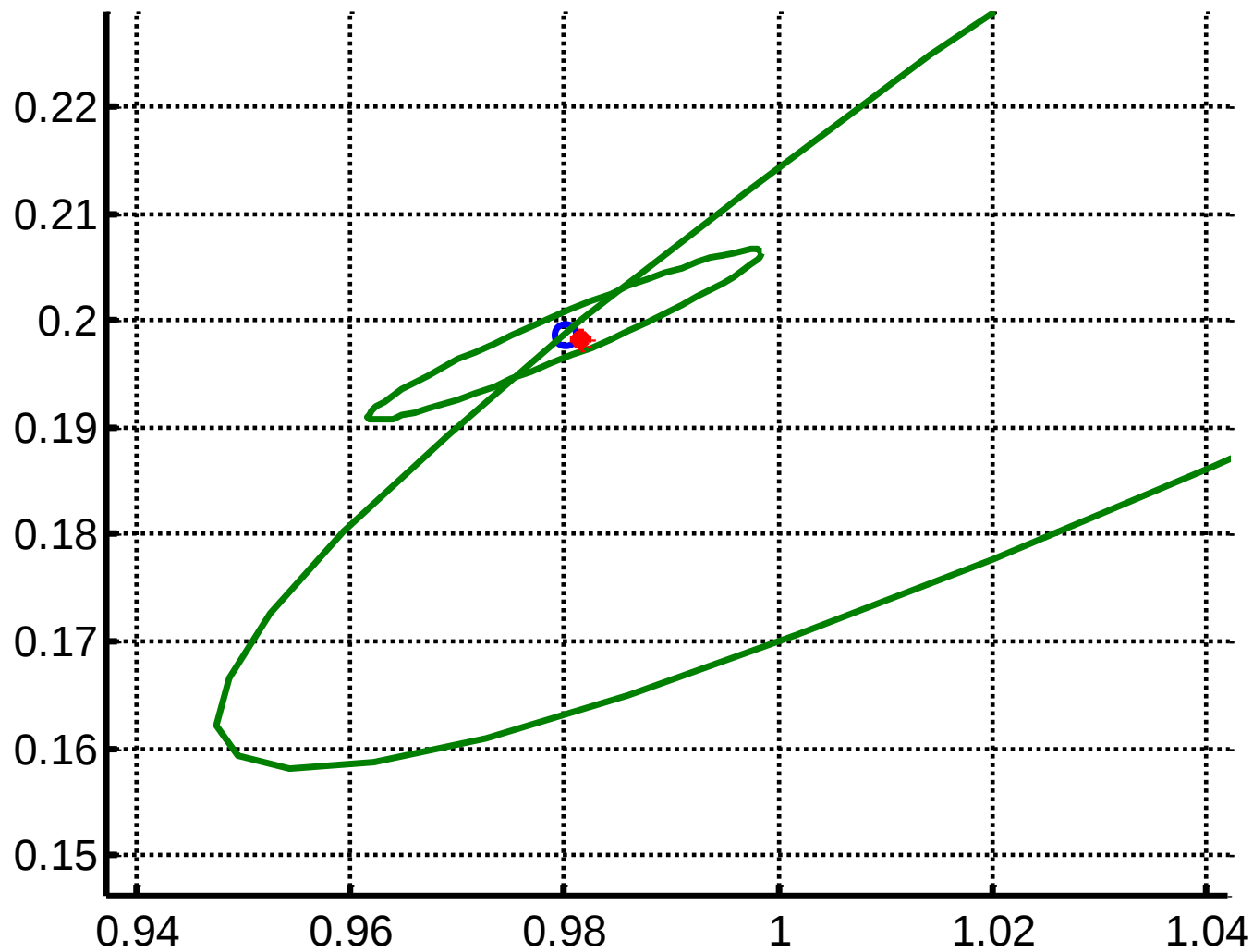


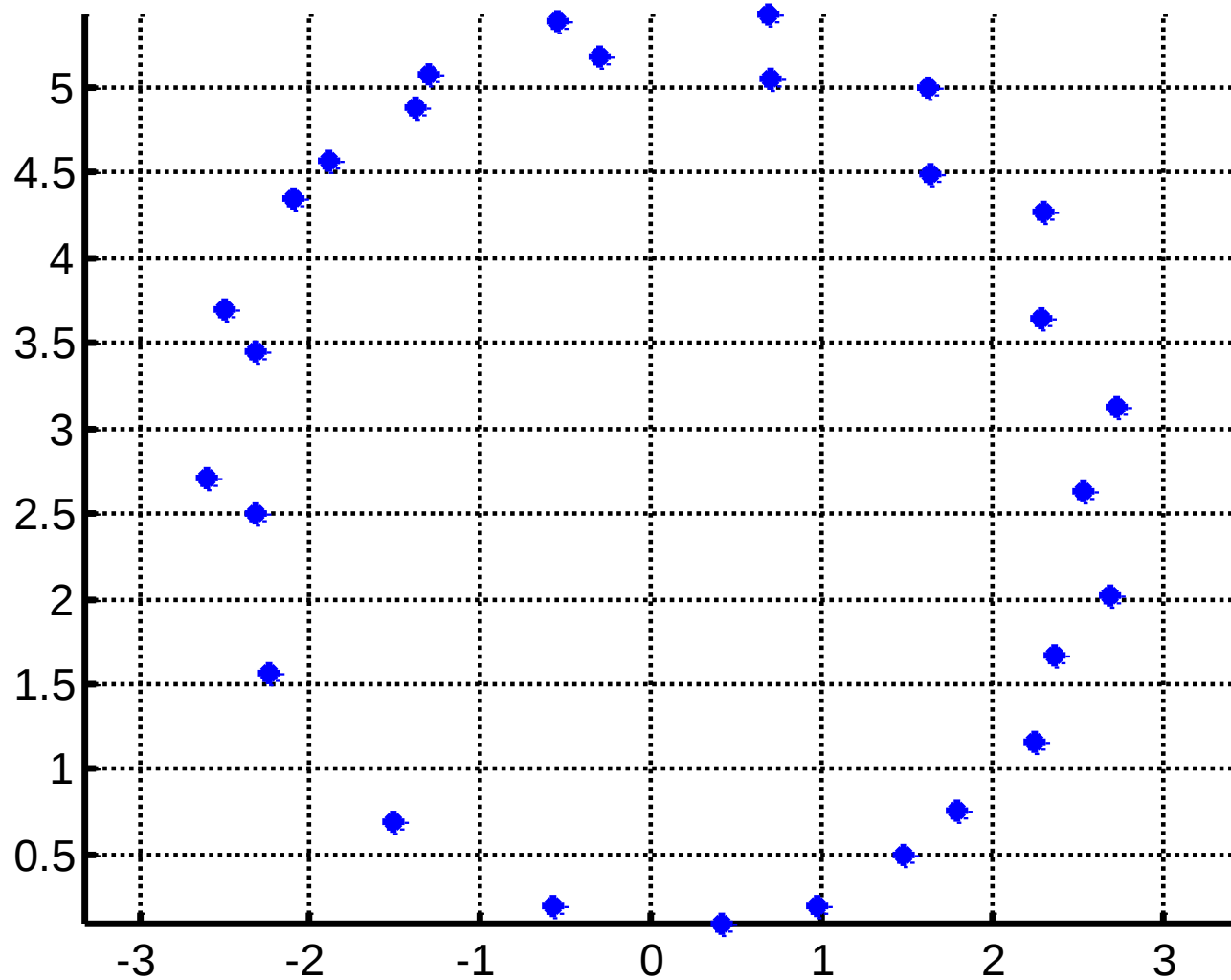


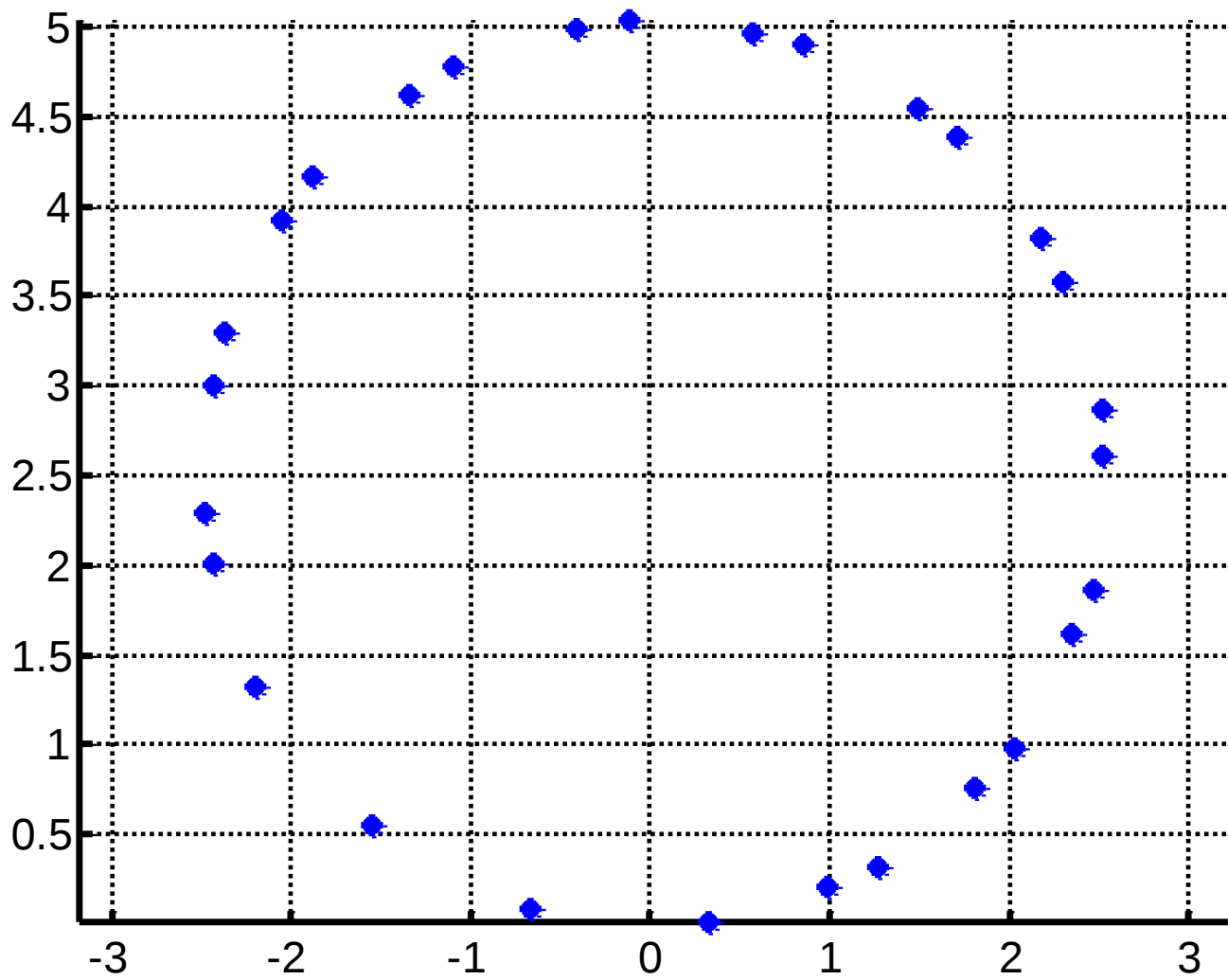
TEAM 4: ROBOT MODEL DESIGN

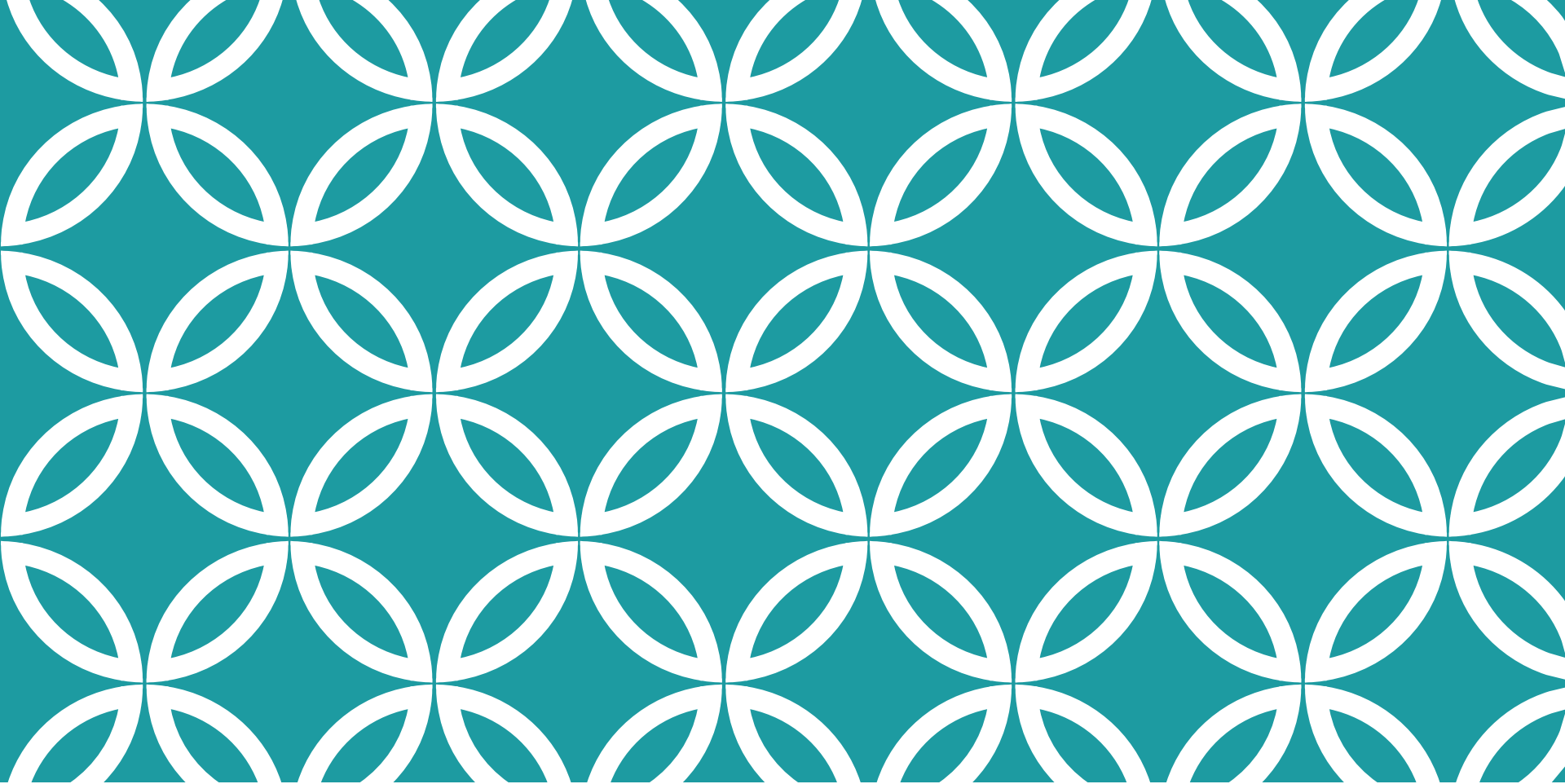






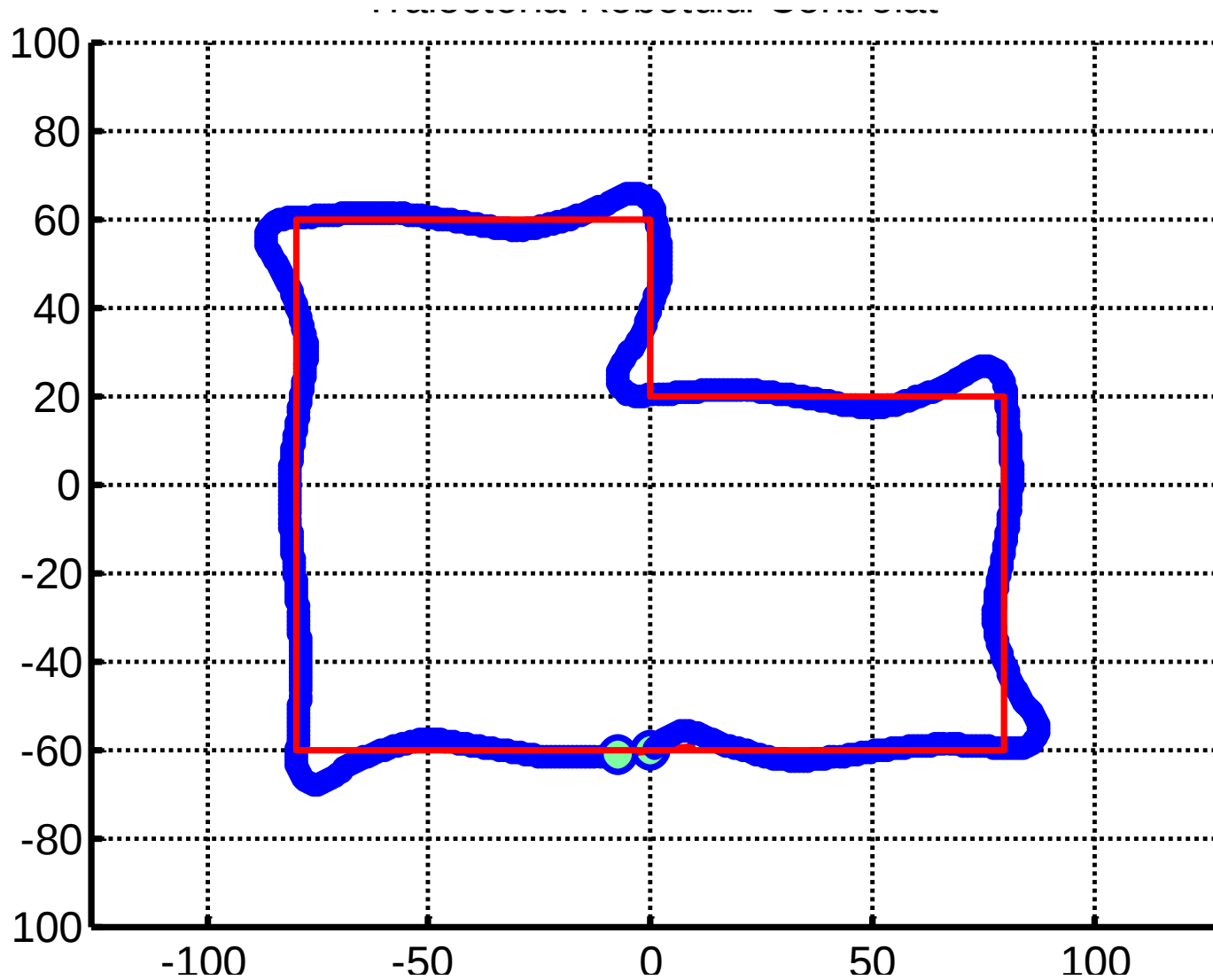


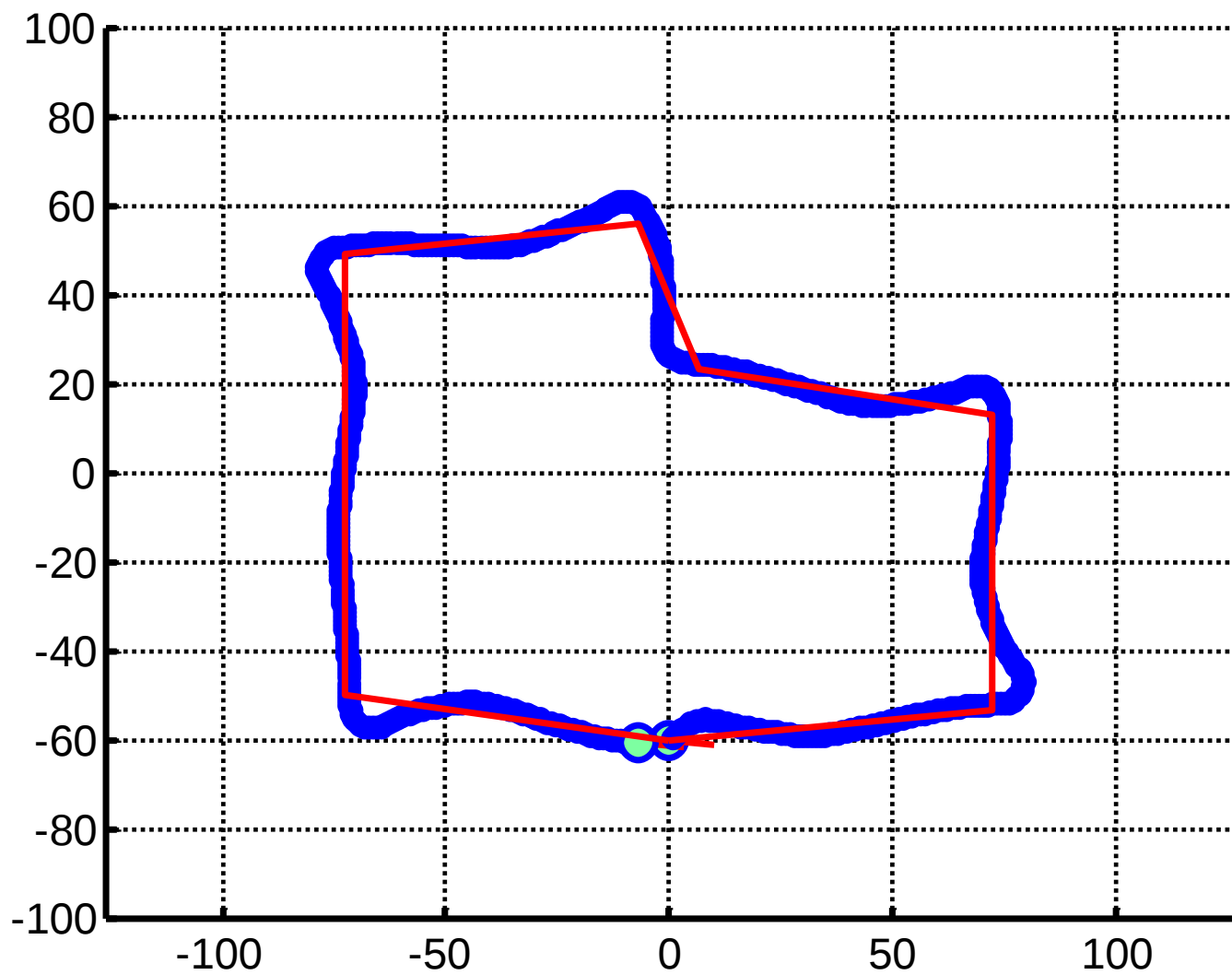


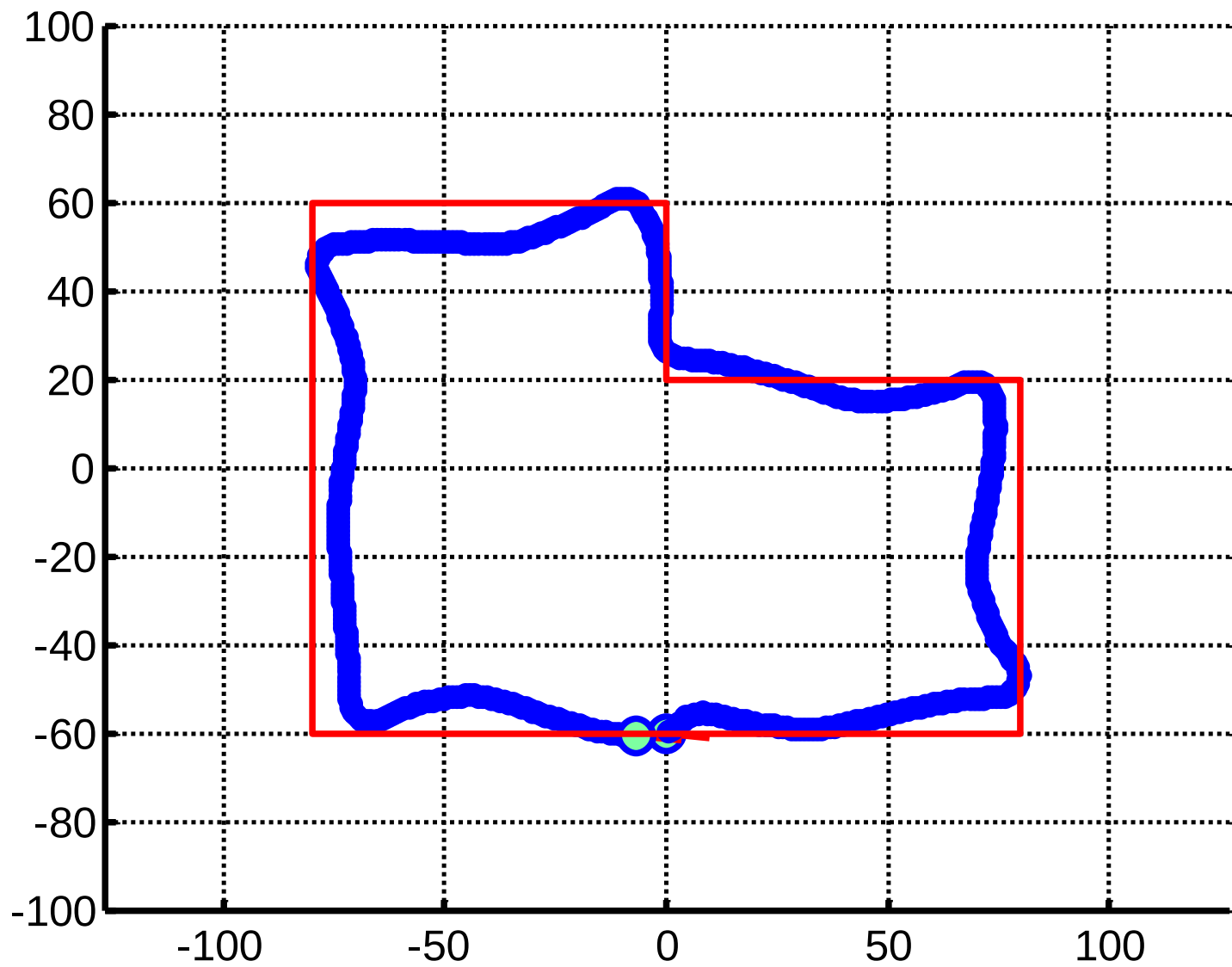


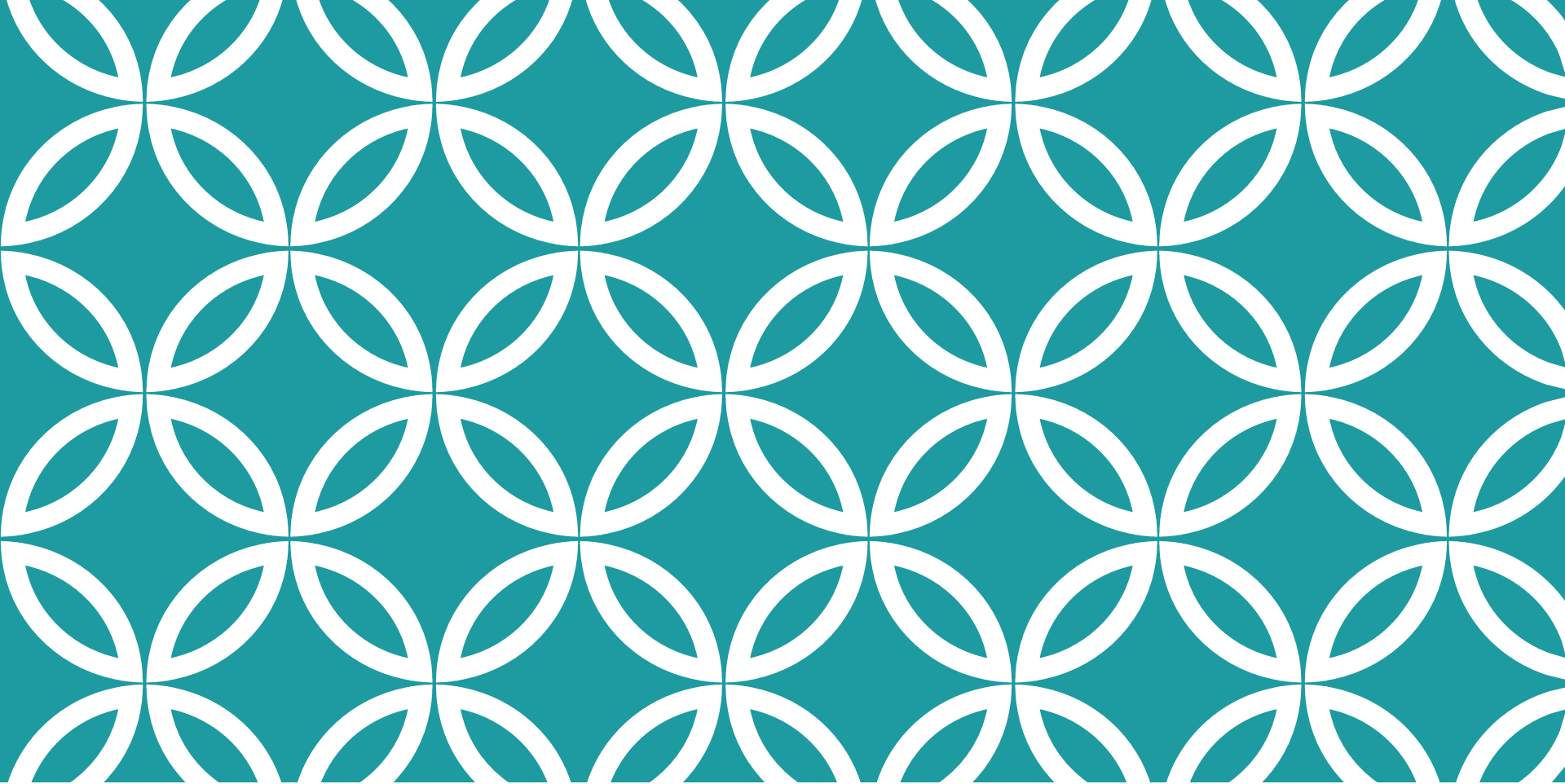
TEAM 2,3: COMPARATOR AND PID DESIGN





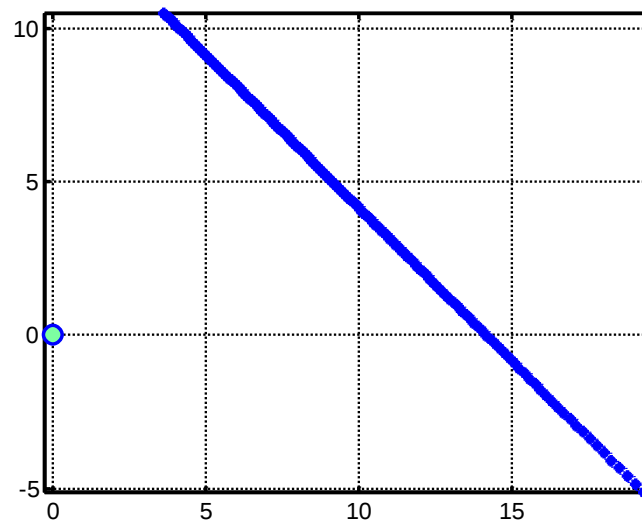
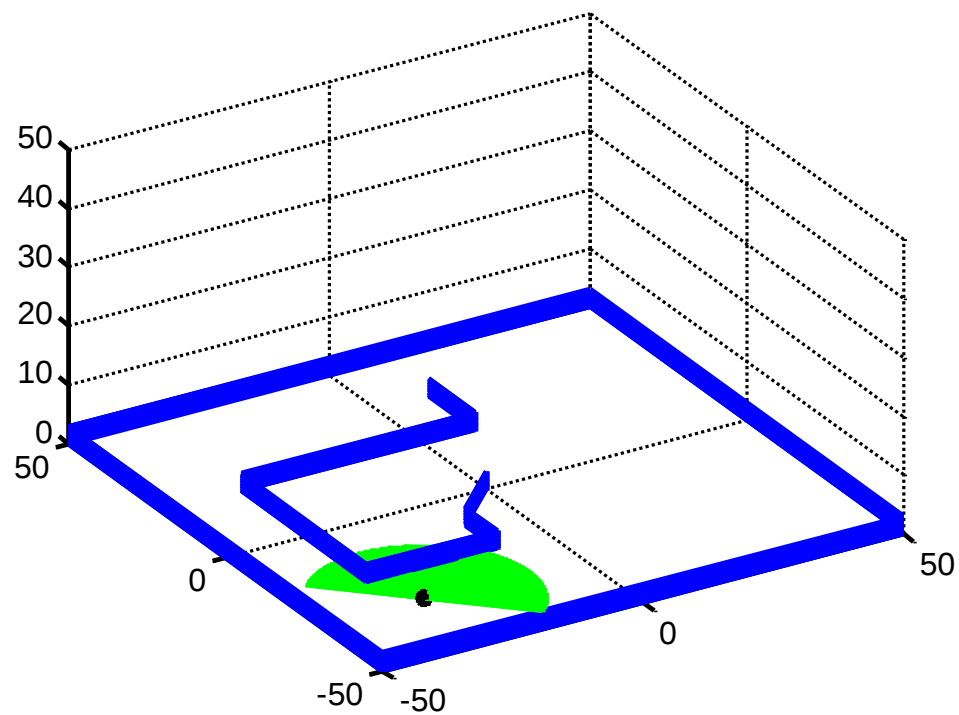


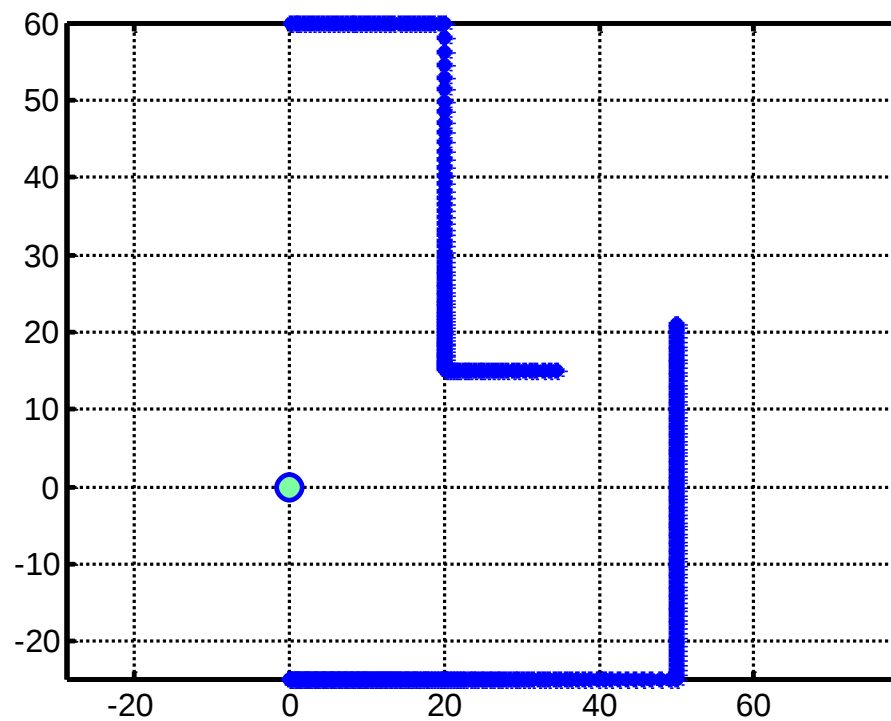
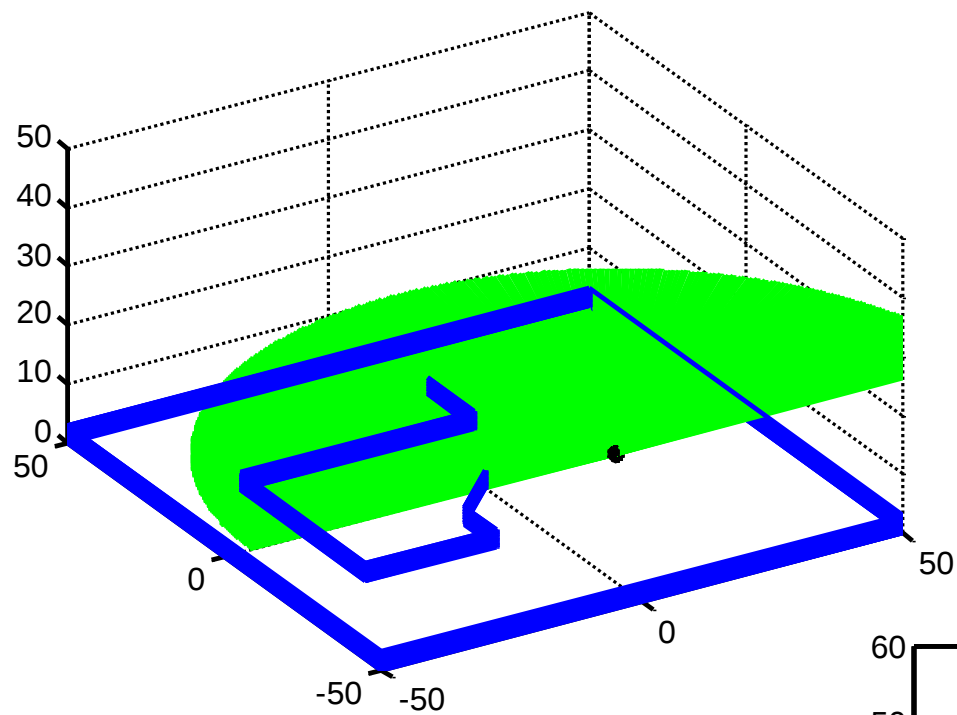


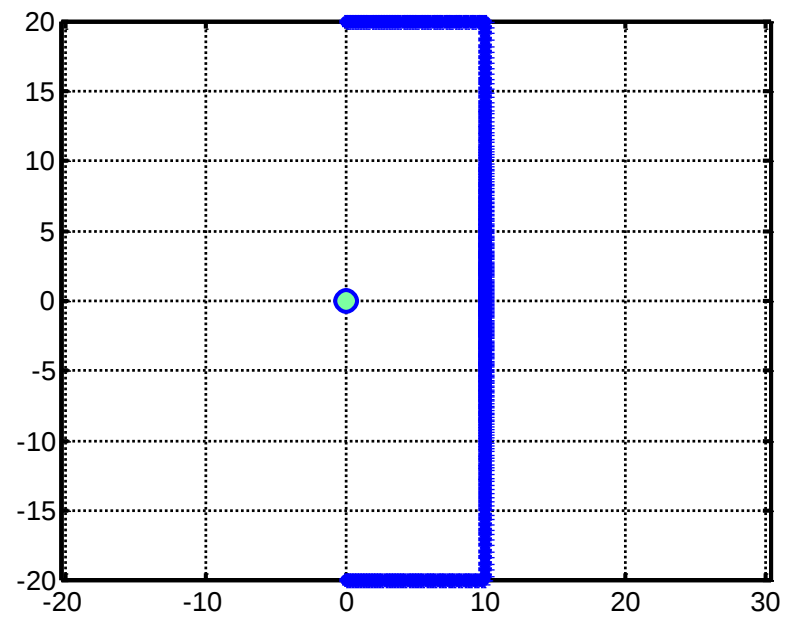
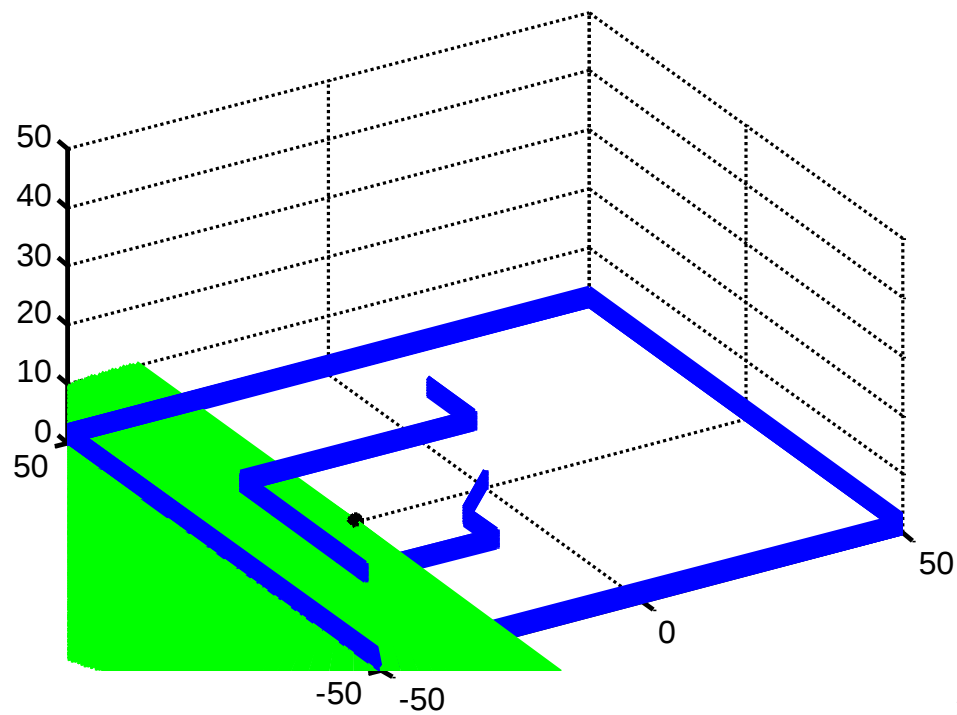


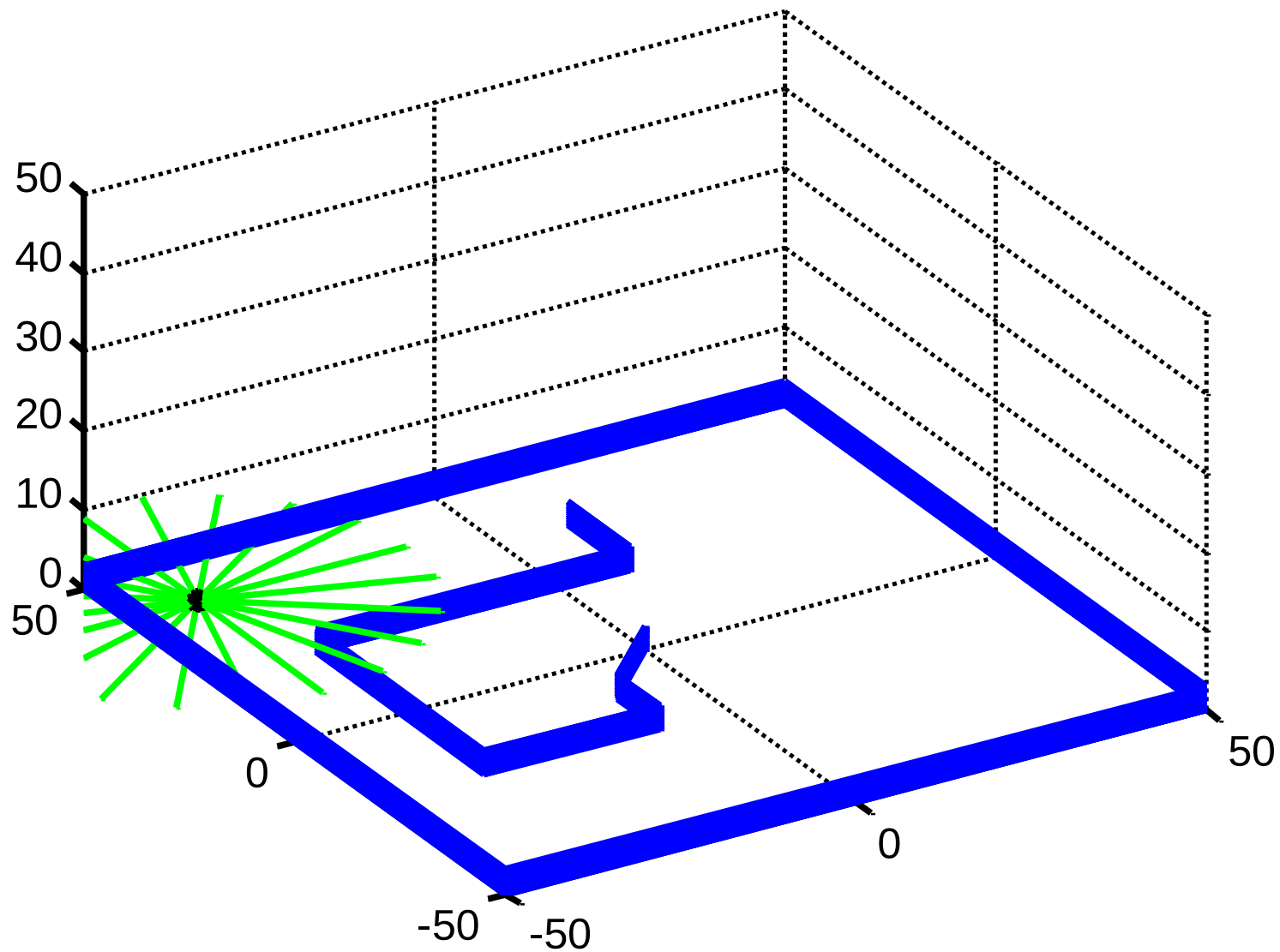
TEAM 6: SENSOR AND FILTER DESIGN

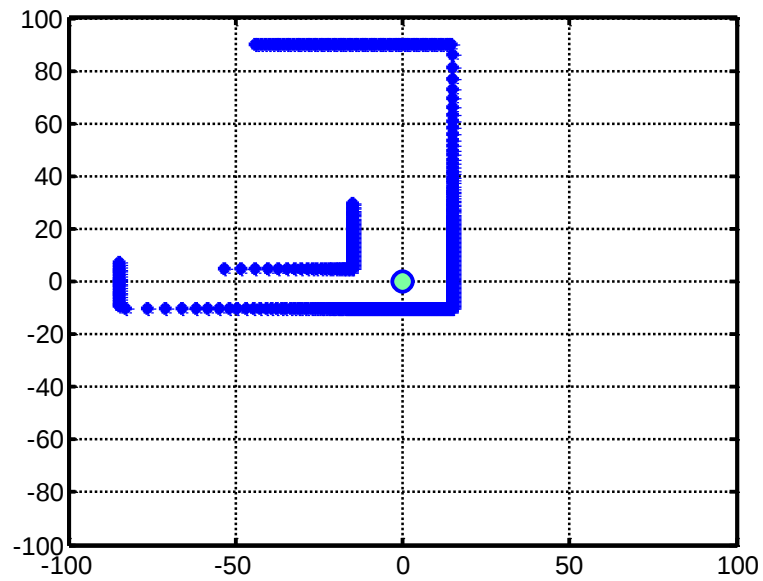
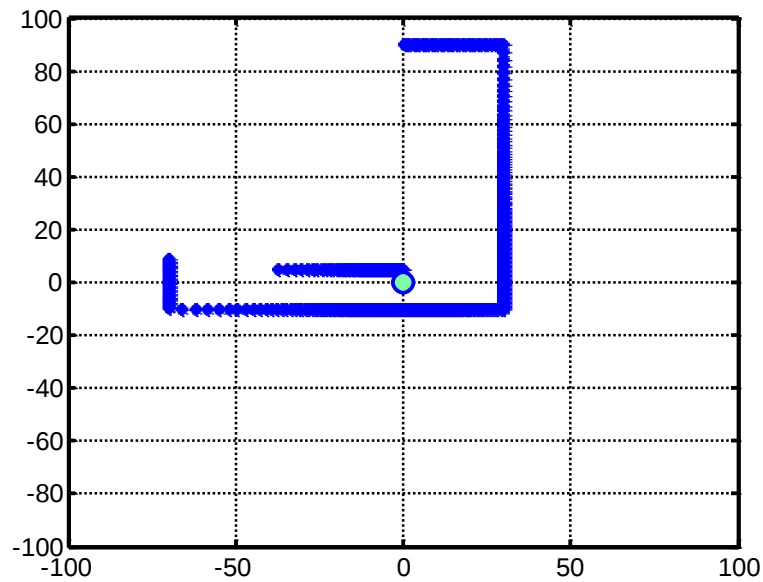
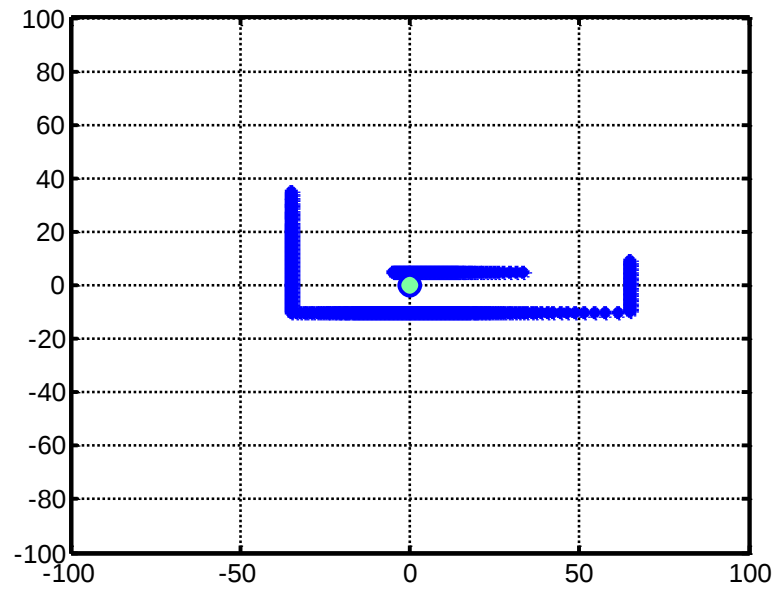
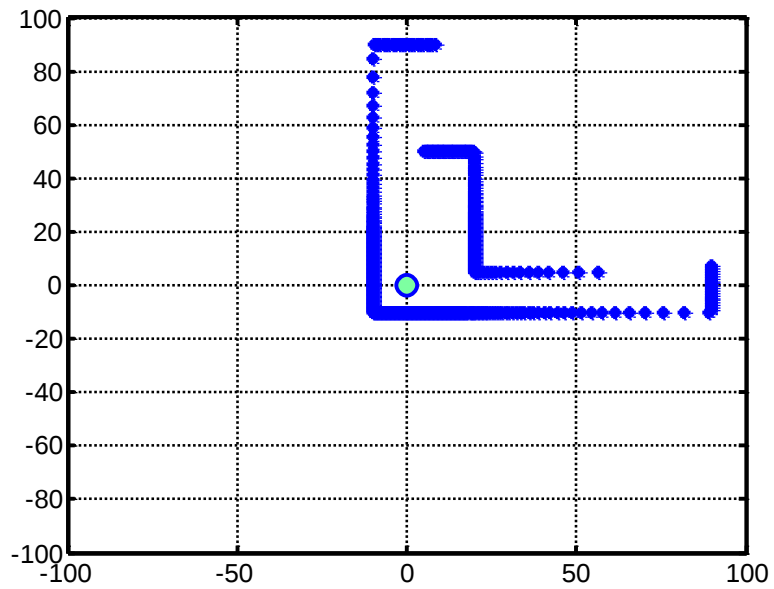


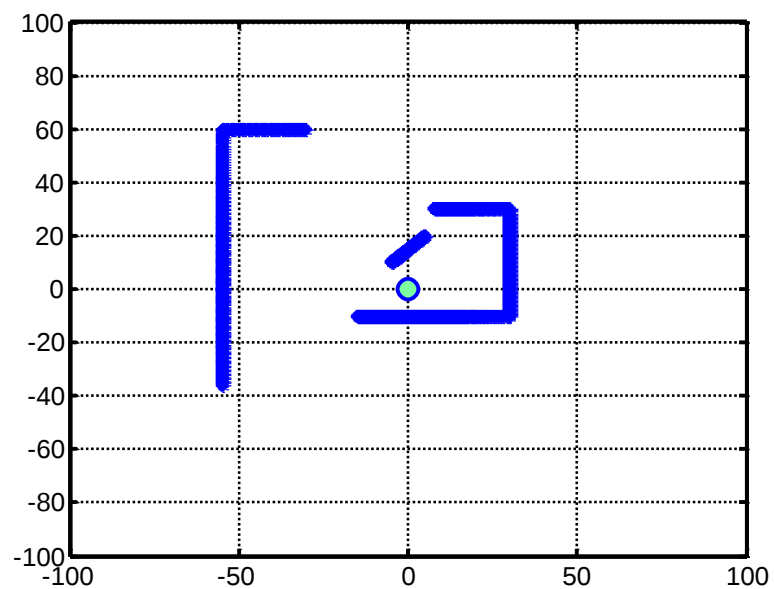
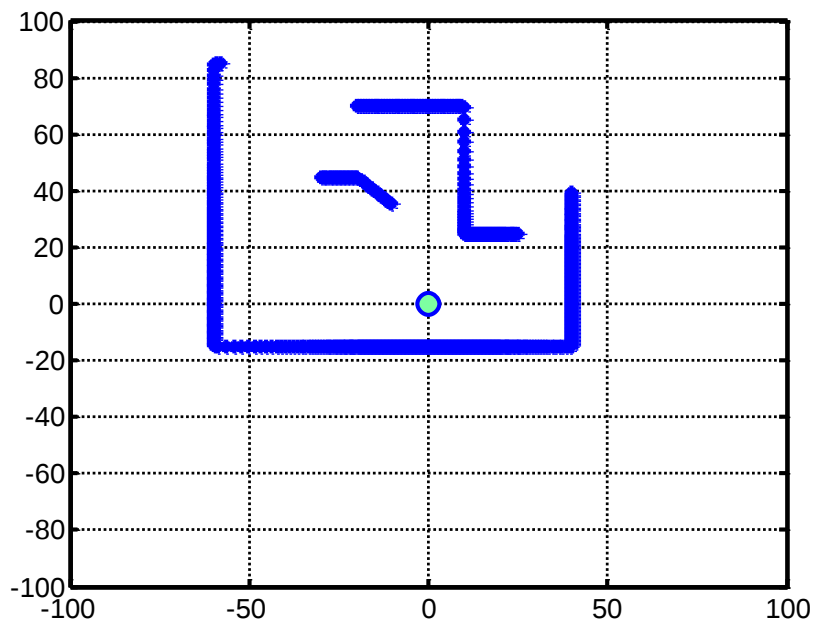
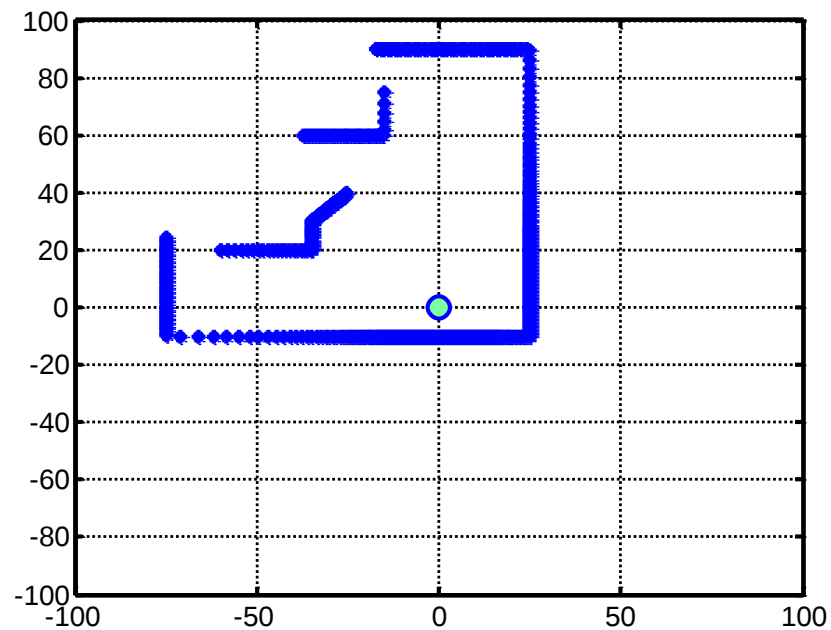
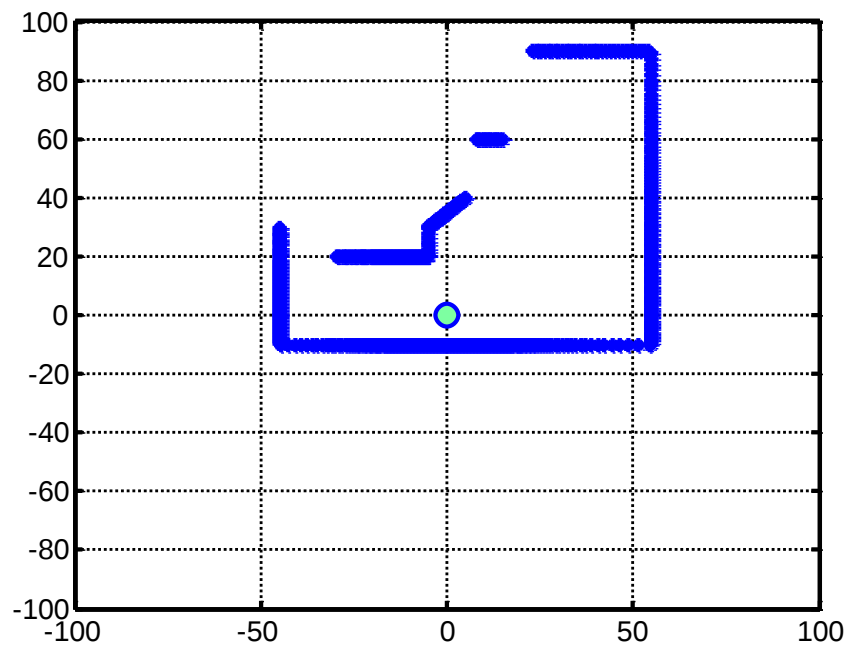


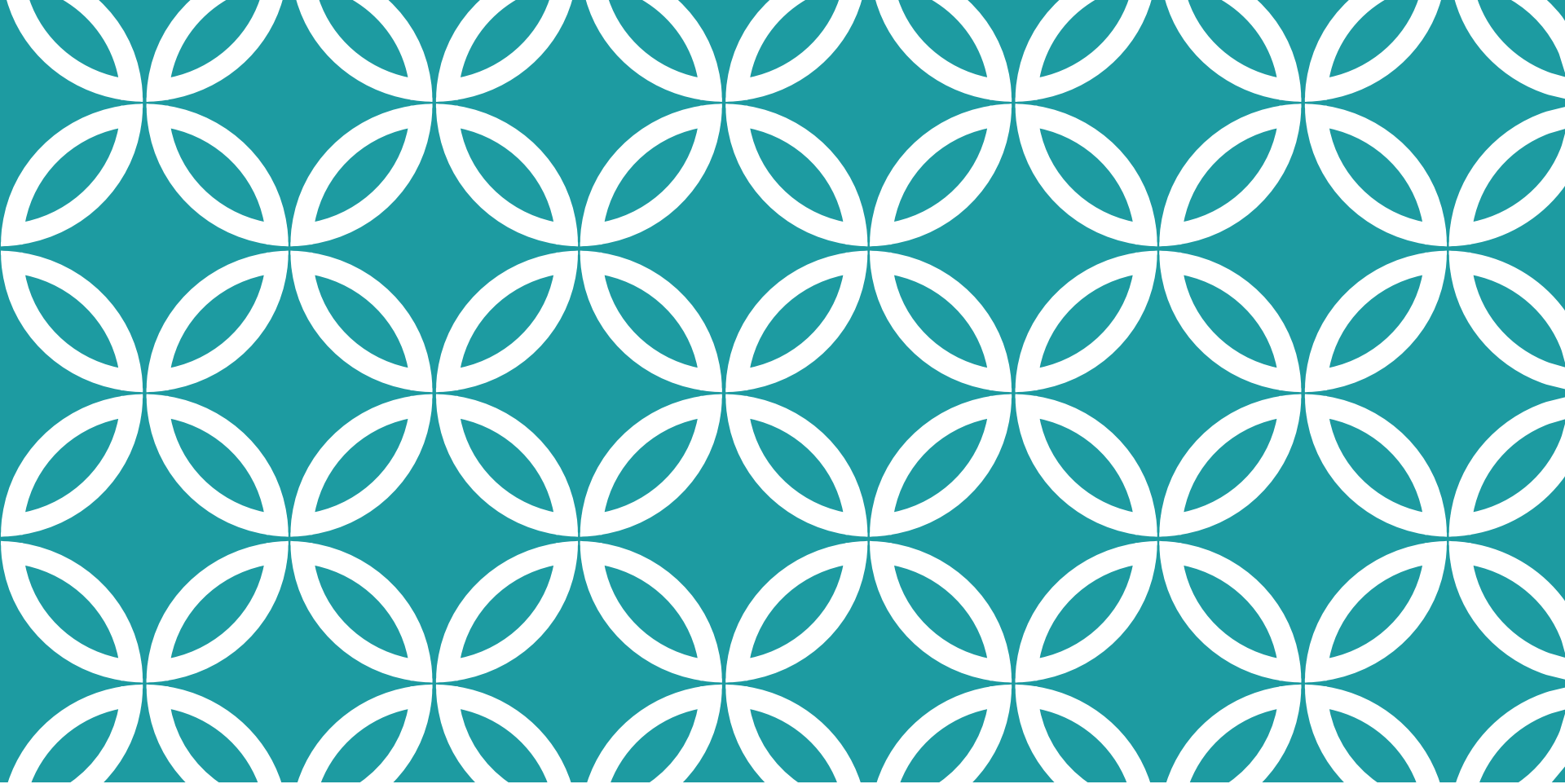






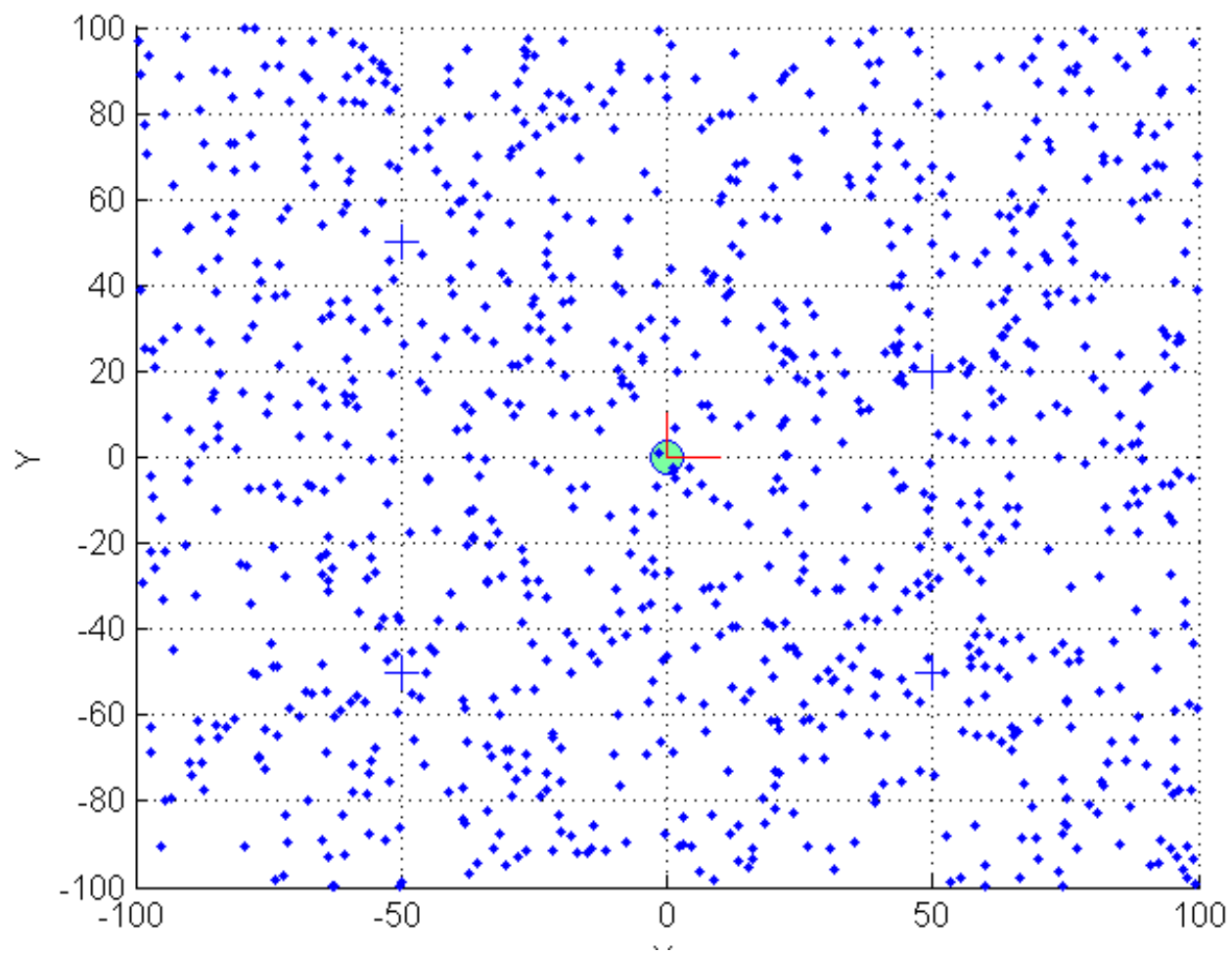


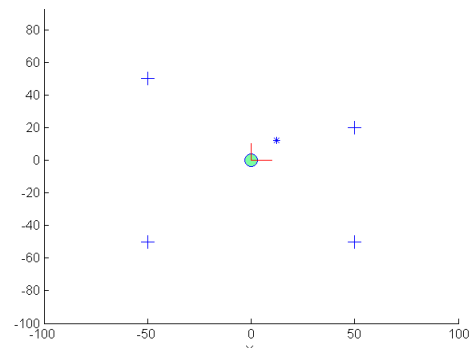
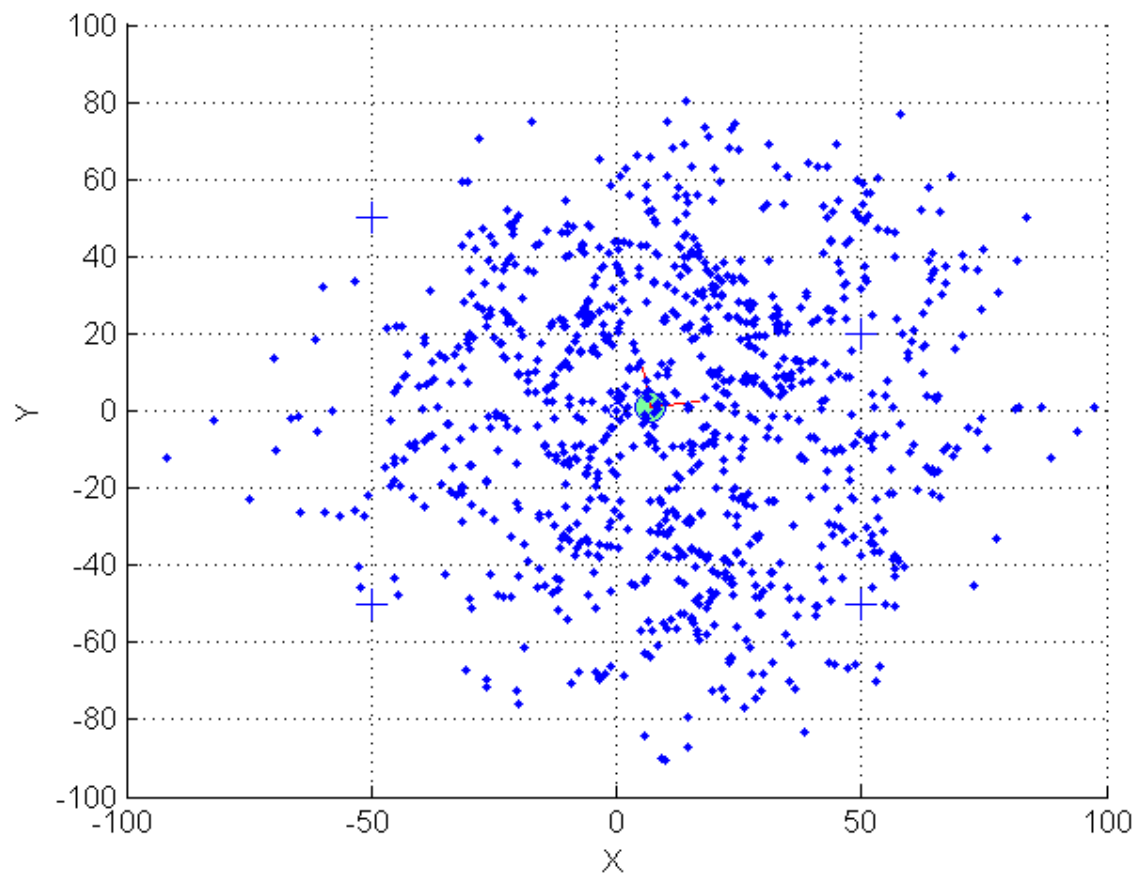


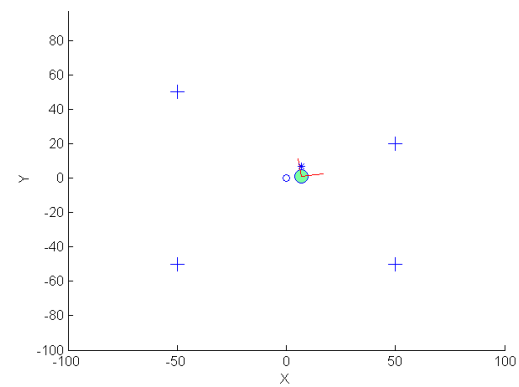
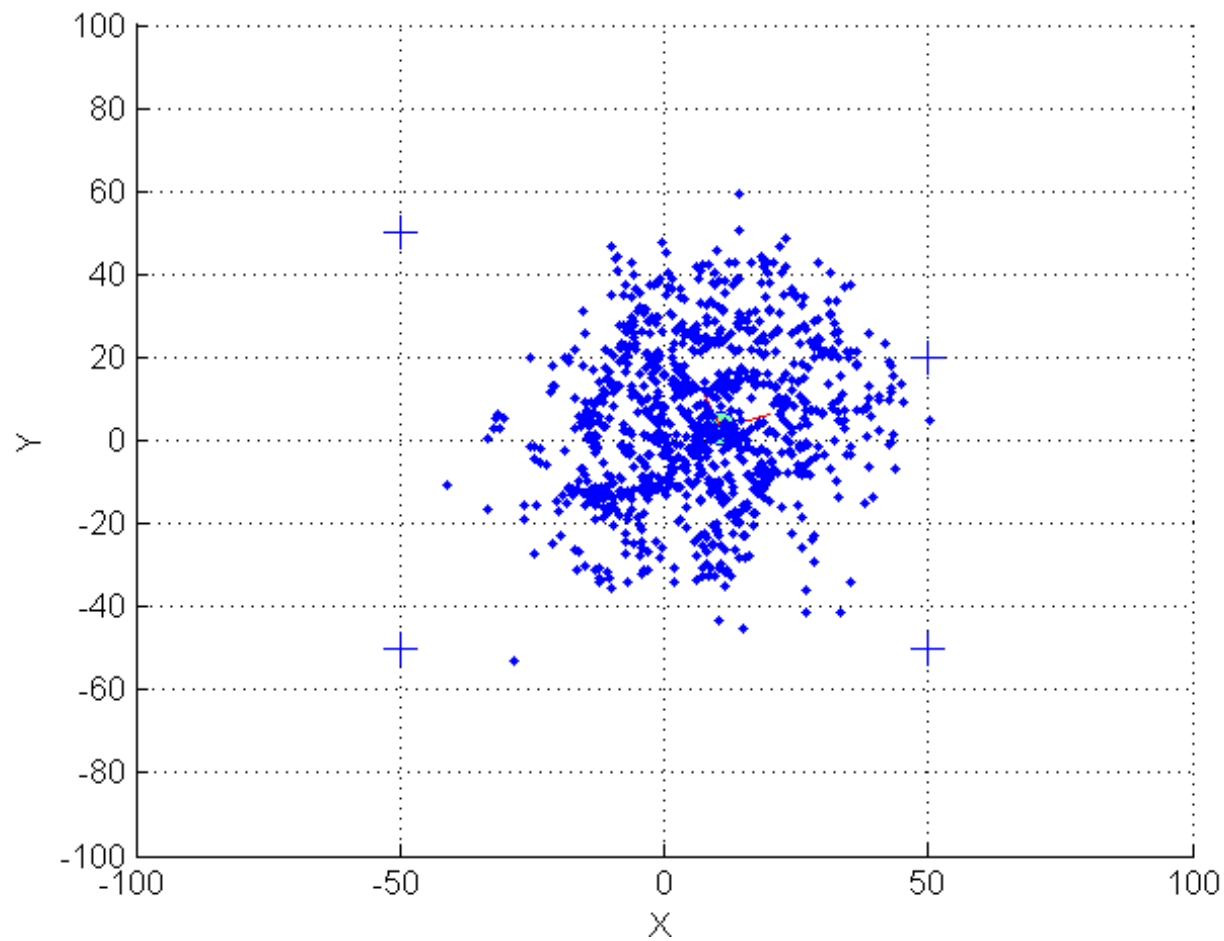


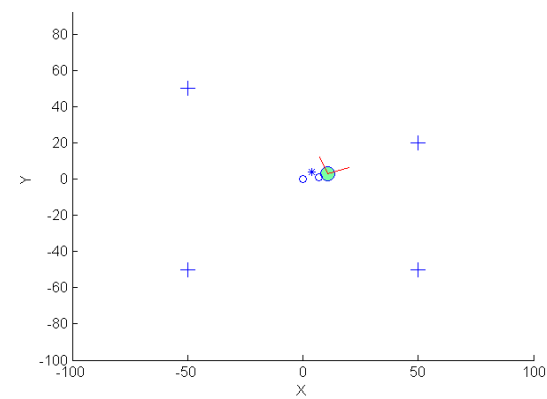
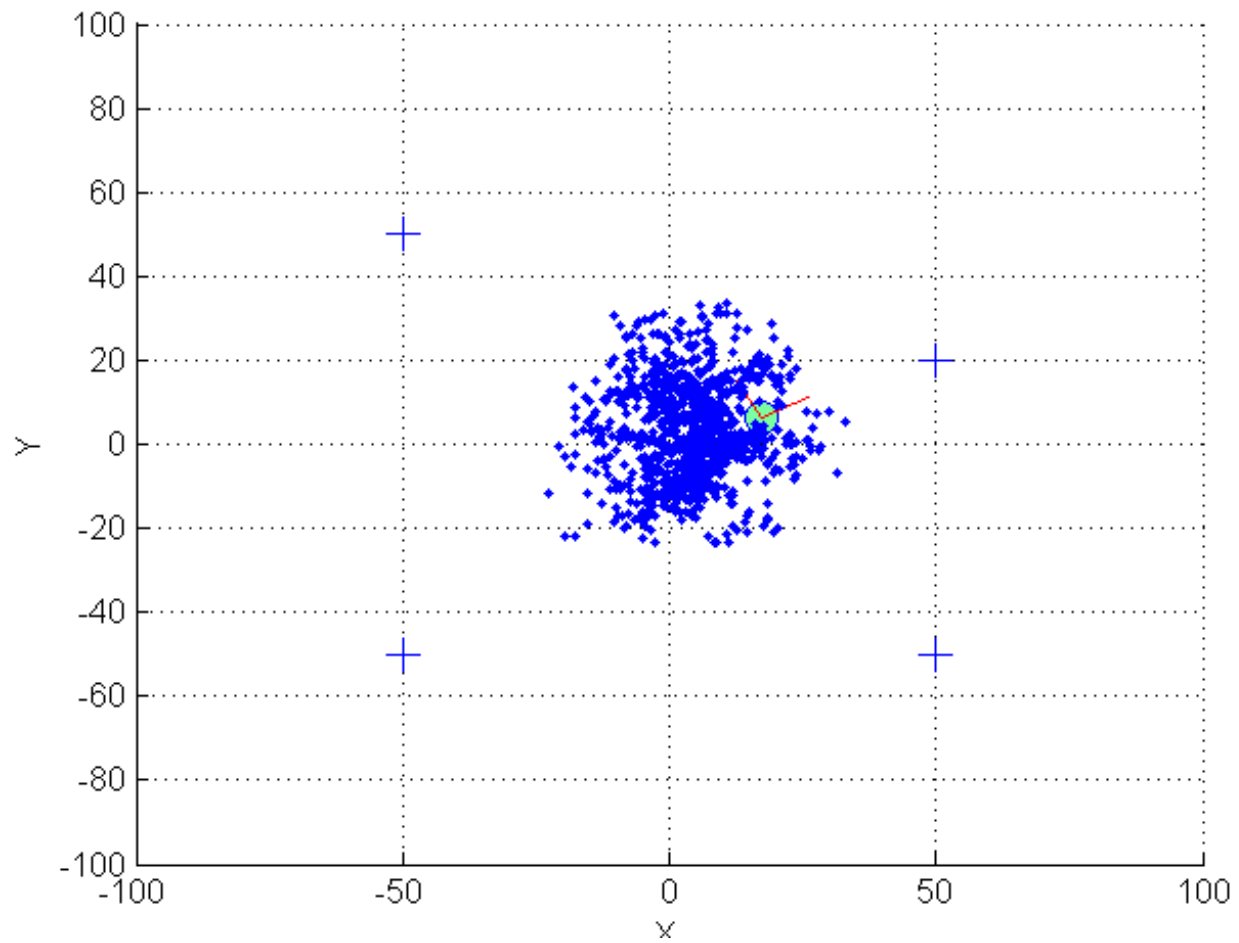
TEAM 6: FILTER DESIGN

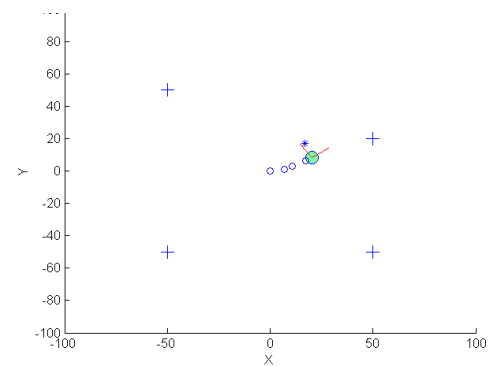
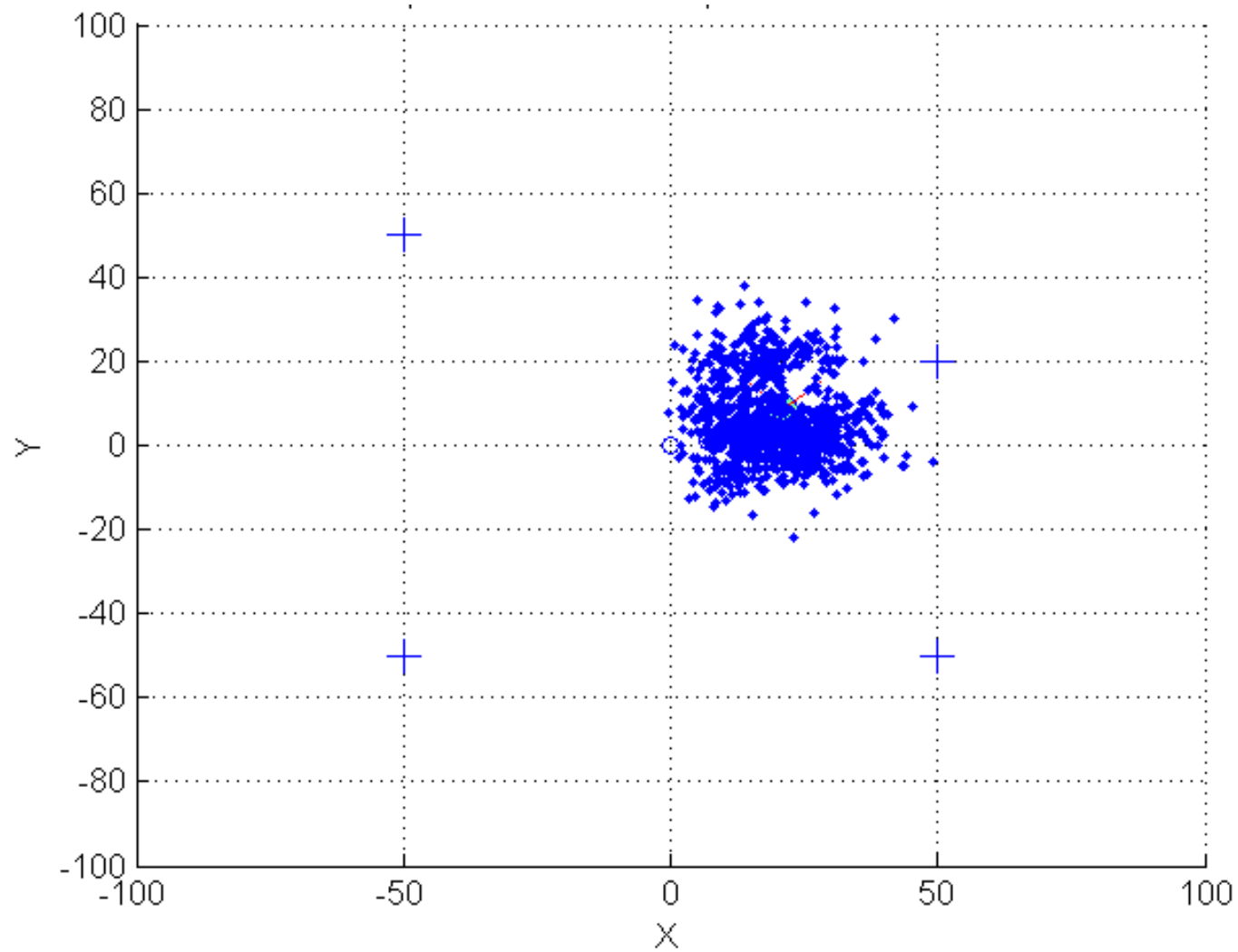


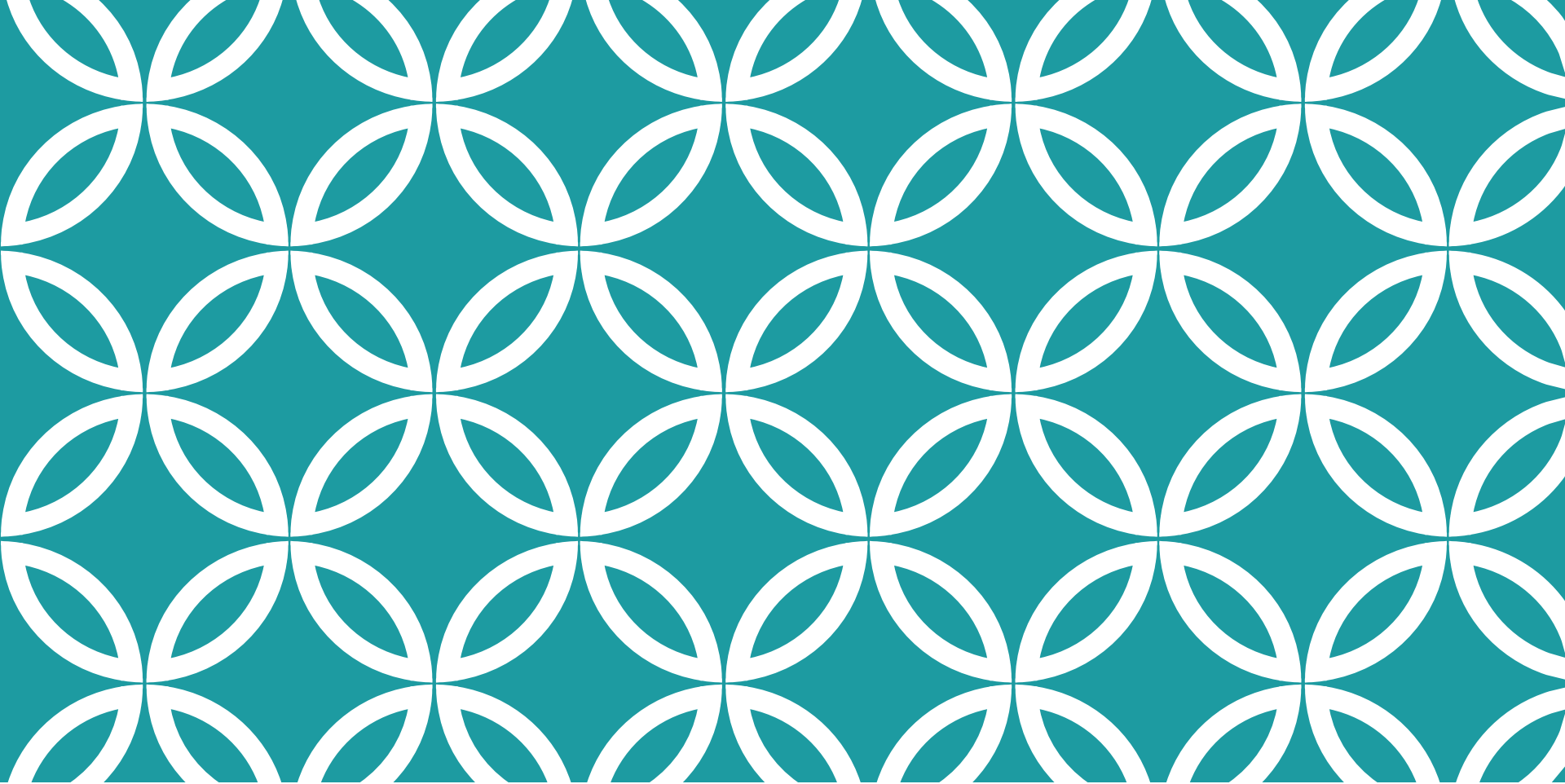












**TEAM 5: DISPLAY THE FINAL
RESULT**

