CONTENTS

APPROVAL ii

SELF DECLARATION AGAINST PLAGIARISM iii

ABSTRACT iv

ABSTRAK v

CONTENTS vi

LIST OF TABLES viii

LIST OF FIGURES ix

1 INTRODUCTION 1

1.1 Background . . . 1
1.2 Research Purpose . . . 2
1.3 Identification of Problems . . . 2
1.4 Scope of Problems . . . 2
1.5 Hypothesis . . . 3
1.6 Research Methodology . . . 3

2 REVIEW OF LITERATURE AND STUDIES 4

2.1 State of The Art . . . 4
2.2 Differential Wheeled Robot . . . 7
2.2.1 *Forward Kinematics* . . . 9
2.2.2 *Inverse Kinematics* . . . 9
2.2.3 Two Wheel Drive Mobile Robot . . . 10
2.3 Image Sensor . . . 10
2.3.1 *Camera* . . . 11
2.4 *Digital Image Processing* . . . 11
2.4.1 Binary Image . . . 12
2.4.2 Bounding Box . . . 12
2.5 Computer Vision . . . 13
2.6 Navigation System . . . 14
2.7 Fuzzy Sets Theory . . . 15
2.7.1 Fuzzification . . . 15

2.7.2 Triangular Membership Function 16
2.7.3 Trapezoidal Membership Function 16
2.7.4 Gaussian Membership Function 17
2.7.5 Generalized Bell Membership Function 17
2.7.6 Fuzzy Inference System 18
2.7.7 Mamdani Fuzzy Models 18
2.7.8 Sugeno Fuzzy Models 18
2.7.9 Deffuzification 19
2.7.10 Centroid of Area ^{z}COA 19
2.7.11 Bisector of Area ^{z}BOA : ^{z}BOA satisfies 19
2.7.12 Mean of Maximum ^{z}MOM 19

3 DESIGN AND MODEL SYSTEM 21
3.1 Design System 21
3.2 Object Detection 23
3.3 Hardware Design 24
3.3.1 Mobile Robot Design 24
3.3.2 Camera Design 24
3.3.3 Receiver Design 25
3.4 Design of Algorithm 25
3.4.1 Design of Fuzzy Logic Algorithm 25
3.4.2 Fuzzification of Distance 26
3.4.3 Fuzzification of Angle 26
3.4.4 Fuzzification of Velocity 27
3.4.5 Fuzzy Rule Base 27
3.4.6 Defuzzification 28

4 PRESENTATION, ANALYSIS AND INTERPRETATION OF DATA 29
4.1 Camera Sensor Testing 29
4.2 Object Detection 30
4.2.1 Mobile Robot Detection 31
4.2.2 Obstacle Detection 31
4.2.3 Goal Detection 33
4.3 Overall Test 34
4.3.1 Data Representation 35

5 CONCLUSION AND RECOMMENDATIONS 37
5.1 Conclusions 37
5.2 Recommendations 37

BIBLIOGRAPHY 38