

ICGST/CNIR - Template Paper Title (14-Point Size, Times New Roman, Bold and Cantered over Two Columns)

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Abstract (12 Bold)

The abstract goes here (10 Normal). Your abstract should be a maximum of 200 words here clearly outlining the contribution of your paper. The paper discusses the possibilities of rehabilitation robots for elderly and disabled people under the important aspect of (semi) autonomous robot control, which plays a key role in acceptance and economic profitability. Due to the financial restrictions in this area, the user interface, the wheelchair, the robot manipulator, the necessary sensors and the control units are quite different compared with industrial robots. The whole control structure has to be redesigned under the needs of the target group and the financial restrictions. In the paper typical scenarios for the application of these robots and new scientific results are presented.¹

Keywords (10 Bold and Italic): *Autonomous robot, Stochastic control, Kalman filter, Fuzzy logic, Neural Network, Adaptive navigation (10 italic).*

1. Introduction

We consider that it is necessary to decide a state of the network load in order to adjust an image information quantity responding a state of the network. In this paper, A state of the network load is decided by using a ratio of send and receive of image data communicated between slave site and master site, a receive interval of image receive report and a send completion time of image data. The master site reports a received image data quantity to the slave site every a certain time. The slave site decides a state of the network load by making a comparison between received report and image data quantity transmitted until it receive reports. Simultaneously, the slave site decides that the network load is large, in case that it can't receive the report inside a certain time. Also

the slave site measures a transmission completion time of image data.

The remainder of the paper is organized as follows: Section (2) focuses on Section (3) emphasizes on

2. Theory

There are two different approaches to the characterization of dynamic systems: In linear systems theory, one can assume either some structure in the signals or some structure in the system. Attempts have been made to combine these two approaches e.g. harmonic identification techniques in the Fourier domain.

First approach: Structure the signal can be found using linear transforms. This approach does not take into account that the system has some structure. In the time domain, filtering is a linear transformation. The Fourier, Wavelet, and Karhunen-Loeve transforms have compression Capability and can be used to identify some structure in the signals. When we are using these transforms, we do not take into account any structure in the system.

Second approach: Structure the system can be found by fitting a model to the system.

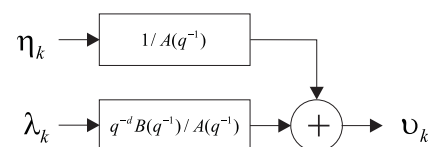


Figure 1. This postscript format 600 DPI figure, font size 8

3. Conclusion

This is the conclusion. The major contributions of this article arise from the formulation of a new approach, spectral analysis, to the modelling and identification of XYZ and ABC features that provide improved computational efficiency in the positioning techniques. By manipulating the manner in which feature information

¹ This study has been implemented on XYZ platform at IA lab. University of

of both A and BVN signatures is incorporated into the model, it can be shown that significant improvements in the performance of the algorithm can be realised. Moreover, the simplicity and the efficiency of dynamic pose tracking techniques succeeded to improve the robot pose estimation process.

4. Acknowledgements

we would like to acknowledge the financial support by ... of our project at the University of

5. References

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[8] A. Hauthor and H. A. Maauthor. Chapter Title, chapter In: Bauthor, Geauthor, Maauthor, Ulauthor (Eds.) ABC Year. ABCD publisher, Year.

Biographies



and

Author One received his B.Sc. from at and his M.Sc. from at Currently he is working for and he is a PhD student at University of in the Laboratory under the supervision of His research interests include,



for His main research interests are,, and

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