

Design of a terrain robot model

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Abstract: In the context of the widespread application of automation technology in industry and services, this topic focuses on designing a terrain robot model to address challenges related to mobility and efficient operation across various types of terrain. The objective of the research is to build an intelligent control system for terrain robots that can self-learn and adapt to diverse environments. The method employs a combined theoretical and experimental approach to determine optimal movement algorithms. The significance of this topic lies not only in contributing to the field of automation science research but also in aiming to promote the development of intelligent technology for the terrain industry.

Keywords: Terrain robot, Intelligent control, Automation technology, Self-learning, Diverse mobility