

Fig. 14. The slave linear velocity when there are obstacles.

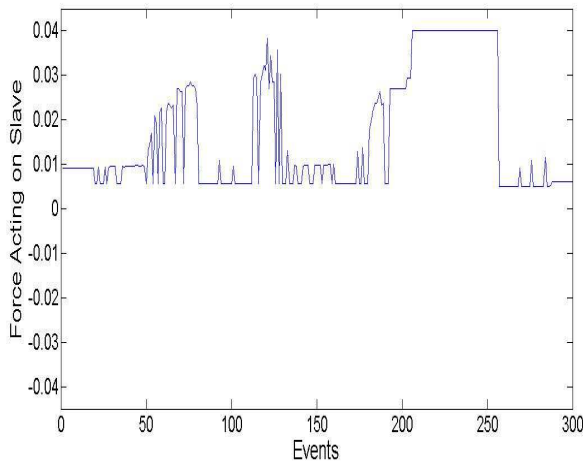


Fig. 15. The force acting on slave reflected to master device.

VII. CONCLUSION AND FUTURE WORK

The above mentioned results have been plotted to analyze the performance of controller and the coordination between master and slave. The results are quite impressive and exhibit the excellent coordination between master and slave. In future work the map building will be added to the GUI so that the human operator can understand the environment around slave robot more precisely and the vision system will be used to detect and localize humans in the environment and then send to them the rescue robot after detection.

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