Paper Title (Times New Roman, 23, Normal, Bold)

Name of Author[1], Name of Author[2], Name of Author[3], Name of Author[4] (12, Times,Bold)

[1] UG-PG student, Research Scholar, Asstt / Asso. Professor, Professor , Dr. (10,Times ,Italic)
Name of the Institute, City, Country, Pin, email ID of Correspondence author
[2] UG-PG student, Research Scholar, Asstt / Asso. Professor, Professor , Dr.
Name of the Institute, City, Country, Pin, email ID of Co-authors
(You can add max. 04 authors)

Abstract – *Paper size is A4, Margins 0.7'' from all four sides .Abstract should be in form of times new roman size 10 italic form. Abstract should be in form of times new roman size 10 italic form. Abstract should be in form of times new roman size 10 italic form. Abstract should be in form of times new roman size 10 italic form. Abstract should be in form of times new roman size 10 italic form. Abstract should be in form of times new roman size 10 italic form. Abstract should be in form of times new roman size 10 italic form. Abstract should be in form of times new roman size 10 italic form. Abstract should be in form of times new roman size 10 italic form. Abstract should be in form of times new roman size 10 italic form. Abstract should be in form of times new roman size 10 italic form. Abstract should be in form of times new roman size 10 italic form.****(150- 200 words)***

Keywords- *Keyword should be times new roman size 10 italic, bold. (****max. 06 keywords****)*

I. INTRODUCTION

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II. LITERATURE REVIEW

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III. METHODOLOGY

(***Includes System block diagram, circuit diagram & description, Hardware details, System flow diagram, Algorithm description, Pseudo code in brief if any.***)

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Table 1- Title of table (10, Normal)

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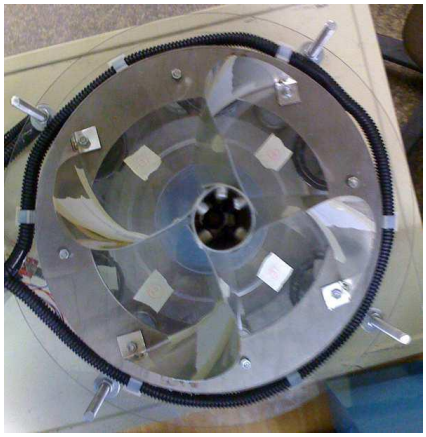

Fig. 1- fig shows the matter (10, Normal)

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IV. DESIGN (if any)

All the equations should be typed using equation editor, equations should not split.

$$\begin{bmatrix}\omega_1\\ \omega_2\\ \omega_3\\ \omega_4\end{bmatrix} = \frac{1}{R}\begin{bmatrix}1 & 1 & -(l_1+l_2)\\ 1 & -1 & l_1+l_2\\ 1 & -1 & -(l_1+l_2)\\ 1 & 1 & l_1+l_2\end{bmatrix} * \begin{bmatrix}u_x\\ v_y\\ w_z\end{bmatrix}$$

V. RESULT & DISCUSSION

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VI. CONCLUSION

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ACKNOWLEDGMENT (if any)

Acknowledgment to person or the organization supported to the author for the research work. This is not mandatory for all.

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[4] *Borenstein, J.; Everett, H.R. & Feng, L. (1996). Navigating Mobile Robots: Sensors and Omni directional Mobile Robot – Design and Implementation Ioan Doroftei, Victor Grosu and Veaceslav Spinu "Gh. Asachi" Technical University of Iasi Romania Techniques. A K Peters, Ltd, MA, USA.*

[5] *Ioan Doroftei; Victor Grosu and Veaceslav Spinu; "Omnidirectional mobile robot- Design and Implimentation" from "Gh.Asachi" Technical university of lasi, Romania.*

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[7] *Ilon, B. E. (1975). Wheels for a Course Stable Selfpropelling Vehicle Movable in any Desired Direction on the Ground or Some Other Base. U.S. Patent. U.S.A.*

[8] *Everett, H.R. (1995). Sensors for Mobile Robots: Theory and Application. A K Peters, Ltd, MA, USA.*

[9] *Diegel, O.; Badve, A.; Bright, G.; Potgieter, J. & Tlatle, S. (2002). Improved Mecanum Wheel Design for Omni-directional Robots, Proc. 2002 Australian Conference on Robotics and Automation, Auckland, 27-29 Nov. 2002, pp. 117-121.*

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