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

**Name of Author1, Name of Author2, Name of Author3, Name of Author4** (12, Times,Bold)

*1UG-PG student, Research Scholar, Asstt / Asso. Professor, Professor, Dr. (10,Times ,Italic)*

*Name of the Institute, City, Country, Pin, email ID of Correspondence author*

 *2UG-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****)*

1. **INTRODUCTION**

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**II. LITERATURE REVIEW**

Add Literature review of the earlier papers in your work area here. Citations should be mentioned clearly.

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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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**IV. DESIGN (if any)**

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

$$\left[\begin{matrix}ω\_{1}\\ω\_{2}\\ω\_{3}\\ω\_{4}\end{matrix}\right]=\frac{1}{R}\left[\begin{matrix}1&1&-(l\_{1}+l\_{2})\\1&-1&l\_{1}+l\_{2}\\1&-1&-(l\_{1}+l\_{2})\\1&1&l\_{1}+l\_{2}\end{matrix}\right]\*\left[\begin{matrix}u\_{x}\\v\_{y}\\w\_{z}\end{matrix}\right]$$

**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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6. *Olaf Diegel, AparnaBadave, Glen Bright, Johan Potgieter, Sylvester Tlale, (2002) “Improved Mecanum Wheel Design for Omni-directional Robot”, Australasian Conference on Robotics And Automation, Auckland.*
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.*
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11. *IoanDoroftei; Victor Grosu and VeaceslavSpinu; “Omnidirectional mobile robot- Design and Implimentation” from “Gh.Asachi” Technical university of lasi, Romania.*

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