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However, teaching young people and children about the design and work of robots can be difficult, transforming it into a complicated area for them. Once the robot performs the first phase and reaches the position of the box, the "set gripper ready" action involves the configuration and positioning of the caliper to take the box. In cases where the destination is not fixed, the mobile robots are also used to place the boxes to a destination. In our case, the length of the robotic arm is 0.20 m, a value that represents a fifth of the reference value 1 m. In our case, the gearbox uses eight gears, and we consider z1 = 8 teeth for gears 1, 3 and 5, and z2 = 24 for 2, 4 and 6 gears, producing a ratio of 1/3. On both platforms, the Dani and NXT robot modules, LabViews and Labviews are used respectively to program the communication between the robotic arm and the mobile robot using the same code rules. Two of the servomotors move the mechanical part of the arm up and already, providing a degree of liberty. In addition, the values of F (X), G (X) and H (X) are updated to look for the next low -cost node. Analysis of the mechanism, degree course. Iocchi L, Ruiz-Del-Solar J, Zrnt T. advances in domestic service robots in the real world. The robot identifies the grip and leaves the box carefully on the pallet. The SBRIO-9632 card was developed by Ni and contains a real-time processor that acts as a main control unit for the robot [10]. pp. 2-612. Each phase of the design e of the robot is explained in detail using diagrams and 3D graphic views with the aim of illustrating the step-by-step implementation phase for education education 2.7 rep e .mcN 91 id 7  etnednopsiroc aipooe al 6001 li odnazillitu , oiet V 9 id erotatnemilia nu rep ehc ecsilibats ogeL erotomovres led itad id oilgof ll .ideip ies ota tellap id oneip ocirac nu arona ecsinrof ,aivattuT .hc .hctetNI aizoRC .esaf amirp allen atugese elanif atanidrooc alla ednopsiroc ehc ottegollo'led enoizisop al ras elaiizni enoizisop al iuQ .dradnats otazzirotom illu a erotatropsart nu us tellap lad isac illognis aciracs tobor occarb nu .iuQ .ocitobor occarb li erallortnoc rep esab id eigetarts ellus e rats-A omtirogla'llus asab is ottegorp otseuq ni atazzillitu osrocrep led enoizacifinaip id aigetarts al ,ertlonl .tik iibmartne id enoizazzinorcnis al e enoizammargorp al .ngised li omerevircsed ,osac ortson leN .tobor id anretse amonotua enoizagivan alla ocoig oediv enoizammargorp allad onnav ehc .inoizacilppa eriv rep arutaretel allen etavort eresse onossop osrocrep led enoizacifinaip id eigetarts etloM .icitobor ippullus ilga itasseretni inavoig i o itnalpicnirp i eraiggarocni ebbervod elibom tobor lus atammargorp elabolg aigetarts al .eznatsid e ticolve erilibats rep ,otnemivap li ortnoc etour elled etnerac o ovissece otirtta'l erative rep tobor enoizagivan id ipocs rep otavort eresse eved otairporppa oizaps onU .tellap len alranoizisop e alotacs al eregnuiggar :isaf eud ni airotteiart al erugesE .airotteiart alled enoizucese'l etnarud erosnes led irolav inousartlu etadilaV :onos ottegorp id opit otseuq eratnemelpmi rep inoizaredisnoc elled enucla e .elanif tellap la atsops is tobor li ,ogoul odnoces ni ,e alotacs alled enoizisop alla atsops is tobor li ,ogoul omirp ni :isaf eud ni atugese 7  de .iNaD tobor lus atammargorp 7  enoiza atseuQ .irtla itlom e aeucqabus enoizarolpse ,enoizurtsi ,oizaps ,artulocirga ,anicidem ,airtsudni emoc inoizacilppa ni itazzillitu itats onos stoboRenoizacifinaip htaparuturts lellarapmra elibom citobortobor .jmbmb i o inavog i rep etnemlapicnirp(ovitare'l ovitare'l ,arocna ecnO.45 = x(F id ossab Ap erolav li atteg emoc ,eroretni artsed a ologna odon li 7  ataugga odon omissorp li ,~AsoC .j41[mcN 61 id 7  aipooe al 657 li olos odnazillitu al .3002 :sserpa :ASU .AVAJ rep htoteutlB .R ynotna .B snkpoH .entuur alled elanif etrap aL .etneibma'llen .locatsio aznes ,ellic 3.8[a 2.2[ad tobor li eratsops rep osrocrep' .tobor led enoizatserp elaei alled etrap adnoces al e acilfary aiccafretni'led itadusir :91 e 81 erugiF ni otartsulli 7  tellap li erenetto rep otugese osrocrep odnoces ll .j3 .8[allec emoc tellap led enoizisop al odnaredisnoc .~soC .rezitellap tobor led elapicnirp entuur al emoc otlibats otats 7  rats-A omtirogla'l ,oirartnoc la .elibom tobor len osrocrep led enoizacifinaip id aigetarts al noc otazzinorcnis ammagorp nu 7  ocitobor occarb led otnemivom ll .tellap lus ottegollo' odnanoiizisop .ocitobor occarb lad atugese entuur adnoce al onartsulli inigammi el .otteggo nu ereliggocar .ocitobor occarb lad atugese entuur amirp al onartsulli inigammi eL .j41 arugiF(aserp al enifni eduihc e elas .erpa is .tellap li arpos avort is aserp al ehc atlov anU .otlecs 7  ossab Ap x(F erolav li noc odon li e ,enoizauqe atseuq odnazillitu otatulav eneiv atrepa atsil allen odon ingO .ovitteibo'lla oidemretni odon nu ad eradna rep otnemivom elibissop led otsoe = x(H e oidemretni odon nu a oidemretni odon nu ad otnemivom led otsoe = x(G ,ovitteibo'l rep everb Ap osrocrep led otsoe = x(F evod.eloccip Ap essom ellen B ovitteibo odon la elibissop everb Ap osrocrep li aloclac 7[.qE .erotineg odon orol la otnup led onretni'lla eccerf el e itardauq emoc itarugiffar ,idon otto isulcni itats onos ,8 arugiF alla etnememrofnoC .sarrab ortauc ed onalp omsinacem nu ed etterid inoizazzilana .MJ ociR .jicravirra rep odon nu 7  c Ahcrep(01 emoc itarednop onos ilacitrev o ilatnozziro idon I .otinifed etnemaiahc eresse 7up ehc ossecorp nu 7  CLP ammagorp li erappuliv .0791 ;llaF ecitnerP :ASU .ossab Ap otsoe li noc atrepa atsil allen oniciv Ap odon li eravort rep otsoe id enoiznuF al aloclac e otrepa ocele'lla iniciv idon ivoun odnegnuigga aizini 11(a) illustrates the results of the simulation of the A-star algorithm, and figure 11(b) the modified version for the same environment firstThe Dani mobile robot. Note that there are diagonal movements on the route, but they are not too close to obstacles, so the risk of collision is minimal. The mobile palletizer robot takes a box from the place A and navigates in the internal environment until it reaches a predefined place B. The characterization of the robotic arm is based on a parallel structure considering that the final effect has only two points to keep the object ; The socket is also built using Lego. The experimental results are presented in Section 4s designed to be the long and more easier to maintain pallets in the sector. Designed to be the long and more easier to keep palletizers in the sector. The third servomotor is used for closing and opening the socket. The production processes in the industries have considerably increased the use of robotic weapons to automate repetitive and tedious activities carried out in difficult conditions for workers. One of the touch sensors is at the base of the arm with the aim of perceiving the lower position of the arm; Likewise, a second touch sensor is found to raise awareness of the upper position that can be reached by the arm. Thus, the iterative research begins by including all the nodes that can be reached from the initial node A, while the non -accessible nodes are, for example, the occupied nodes. Here, we use the term nodes to report these intermediate points that can also be seen as close points or adjacent to the real position of the robot. The path planning module on the robot consists of three phases: initial, intermediate and final. Figure 3 shows the 3D design of the implemented gear train. 3D gearbox design. Another important parameter during the design of the gear trains is the relationship between nutrition and couple of the servomotor. 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