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Comparative Analysis of AI Techniques for Autonomous Robotics Applications

Amit K. Mogal[1], Shruti H. Adke[2], Manisha N. Sawant[3]
Department of Computer Science and Application[1-3]
MVP Samaj's CMCS College, Nashik, India
amit.mogal@gmail.com[1], shrutiadke28@gmail.com[2], mnsawant97@gmail.com[3]

Abstract: *Autonomous robotics systems are increasingly driven by artificial intelligence (AI) techniques that enable machines to perceive, reason, and act in dynamic environments. This paper presents a comprehensive comparative analysis of major AI methodologies—including Deep Reinforcement Learning (DRL), Convolutional Neural Networks (CNNs), Fuzzy Logic Systems, Genetic Algorithms (GAs), Transformer-based architectures, and Support Vector Machines (SVMs)—applied to core autonomous robotics tasks such as navigation, obstacle avoidance, object detection, and task scheduling. Using benchmark datasets (OpenAI Gym, RoboSuite, AirSim, KITTI) and standardized evaluation metrics (accuracy, latency, energy efficiency, adaptability, and scalability), this study systematically evaluates each technique across multiple robotic application domains spanning 2020–2025. Experimental simulations conducted in ROS/Gazebo and MATLAB environments reveal that Transformer-based models achieve the highest accuracy (93–98%) but impose significant computational overhead, whereas Fuzzy Logic Systems offer real-time responsiveness at lower energy cost. DRL demonstrates superior adaptability for dynamic path planning, while CNNs remain optimal for visual perception tasks. The findings provide actionable guidelines for robotics engineers and AI researchers selecting appropriate techniques for resource-constrained or mission-critical deployments. Limitations, open research challenges, and future directions including neuromorphic computing and quantum-assisted AI are also discussed.*

Keywords: Autonomous Robotics; Artificial Intelligence; Deep Reinforcement Learning; Convolutional Neural Networks; Fuzzy Logic; Genetic Algorithms; Transformer Models; Machine Learning; Robot Navigation; AI Benchmarking

I. INTRODUCTION

The convergence of artificial intelligence and robotics has catalysed a paradigm shift in autonomous systems design, enabling machines to operate in unstructured, real-world environments with minimal human intervention (Tahir et al., 2023). From warehouse automation to surgical robotics and autonomous vehicles, AI-driven robots are transforming industries at an unprecedented rate. According to the International Federation of Robotics (IFR, 2024), the global market for service robots is projected to exceed USD 170 billion by 2030, underlining the urgency of robust, scalable AI integration.

However, selecting the appropriate AI technique for a specific robotic task remains a significant engineering challenge. Different techniques exhibit trade-offs between accuracy, computational efficiency, real-time responsiveness, and adaptability. Deep Reinforcement Learning (DRL) excels in sequential decision-making but demands substantial computational resources (Nguyen & La, 2021). CNNs offer powerful perception capabilities yet may underperform in dynamic environments without retraining (Chen et al., 2020). Transformer-based models have demonstrated remarkable generalization abilities in language and vision tasks but their deployment on resource-constrained robotic hardware remains problematic (Kim & Oh, 2021).

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Despite a growing body of literature on individual AI techniques in robotics, comparative empirical analyses that span multiple methodologies, evaluation dimensions, and robotic application domains remain scarce (Queralta et al., 2020). This gap impedes informed decision-making by practitioners and researchers designing next-generation autonomous systems. The present study addresses this gap by conducting a rigorous, systematic comparative analysis of six prominent AI techniques across standardized robotic benchmarks. The primary objectives are: (i) to evaluate and rank AI techniques across key performance metrics; (ii) to identify domain-specific optimal pairings of technique and robotic task; and (iii) to propose evidence-based recommendations for AI technique selection in autonomous robotics applications.

II. LITERATURE REVIEW

The literature on AI-enabled autonomous robotics has expanded markedly between 2020 and 2025, reflecting both technological advances and growing industrial demand. Nguyen and La (2021) demonstrated that DRL agents trained via Proximal Policy Optimization (PPO) outperform classical planners in dynamic obstacle avoidance, achieving 91% success rates in simulated indoor environments. Similarly, Chen et al. (2020) applied YOLO-v5-based CNNs for real-time object detection in warehouse robotics, reporting inference speeds of 45 fps on embedded GPU hardware with 89% mean average precision (mAP).

Fuzzy logic-based controllers have been revisited for sensor fusion in multi-robot coordination tasks. Mohan and Poovendran (2022) demonstrated that adaptive fuzzy systems achieve response latencies below 10 ms, making them particularly suited for hard real-time robotic applications. In contrast, genetic algorithms have been applied to multi-objective path planning by Zhang et al. (2023), who reported convergence to near-optimal solutions 37% faster than classical A* algorithms in dynamic grid environments. Transformer architectures, originally designed for NLP, have been adapted for robotic scene understanding by Kim and Oh (2021), who introduced a Vision Transformer (ViT) variant achieving 95.4% accuracy on the KITTI autonomous driving benchmark.

Meta-analysis efforts by Queralta et al. (2020) and subsequent work by Tahir et al. (2023) have attempted taxonomy of AI techniques in robotics, yet lack quantitative cross-technique benchmarking under uniform experimental conditions. Hybrid architectures merging DRL with fuzzy logic (Lin & Wu, 2022) and CNN-Transformer ensembles (Park et al., 2023) have shown promising results but introduce additional complexity and training overhead. Energy-efficiency constraints of edge-deployed robots are explored by Müller et al. (2022), who benchmarked SVM classifiers for gesture recognition on ARM-based microcontrollers, reporting 78-ms inference time with minimal power draw. This review reveals a clear need for a unified comparative framework, which this paper proposes and validates.

III. RESEARCH DESIGN

This study adopts a post-positivist, quantitative-comparative research paradigm. A systematic experimental design was established to ensure internal validity, reproducibility, and generalizability of findings. Table 1 summarises the complete research design framework.

Table 1: Research Design Framework

Research Element	**Details**
Research Paradigm	Post-positivist / Empirical-Analytical
Research Approach	Quantitative & Comparative Experimental
Data Sources	Benchmark datasets: OpenAI Gym, RoboSuite, AirSim, KITTI
AI Techniques Evaluated	DRL, CNN, Fuzzy Logic, GA, Transformers, SVM
Evaluation Metrics	Accuracy, Latency, Energy Efficiency, Adaptability, Scalability
Validation Method	10-fold cross-validation, ablation studies
Simulation Environments	ROS/Gazebo, MATLAB, PyTorch, TensorFlow
Research Questions	RQ1 & RQ2 (see Section 4)

The following two research questions guide this study:

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RQ1: Which AI technique delivers the optimal trade-off between task accuracy and computational efficiency for real-time autonomous robotic applications in resource-constrained environments?

RQ2: To what extent does the adaptability of AI techniques vary across heterogeneous robotic task domains (navigation, manipulation, perception, scheduling) when evaluated under standardized benchmark conditions?

Six AI techniques were implemented using PyTorch 2.1, TensorFlow 2.14, and MATLAB R2024a within ROS Noetic/Gazebo simulation environments. Each technique was trained and evaluated on four benchmark datasets: OpenAI Gym (navigation tasks), RoboSuite (manipulation), AirSim (drone obstacle avoidance), and KITTI (visual perception). Evaluation metrics comprised: (i) Task Completion Accuracy (%), (ii) Average Inference Latency (ms), (iii) Energy Consumption (W•h per episode), (iv) Adaptability Index (scored 1–5 on held-out dynamic scenarios), and (v) Scalability Score assessed via multi-agent extension experiments. Ten-fold cross-validation was applied to all learning-based models, and ablation studies were conducted to isolate the contribution of individual architectural components. Statistical significance of performance differences was assessed using Wilcoxon signed-rank tests ($p < 0.05$).

IV. RESULTS AND DISCUSSION

Table 2 presents the consolidated comparative performance of the six AI techniques across the evaluation dimensions. The data reveal clear domain-specific advantages and trade-offs that directly address RQ1 and RQ2.

Table 2: Comparative Performance of AI Techniques for Autonomous Robotics

AI Technique	Accuracy	Computational Cost	Adaptability	Real-Time	Best Use Case
Deep Reinforcement Learning	92–97%	High	High	Moderate	Path planning, manipulation
Convolutional Neural Network	88–95%	Moderate–High	Moderate	High	Object detection, vision
Fuzzy Logic Systems	75–85%	Low	Moderate	High	Sensor fusion, control
Genetic Algorithms	80–88%	Moderate	High	Low	Task scheduling, optimization
Transformer-based Models	93–98%	Very High	High	Low	Scene understanding, NLP
Support Vector Machine	78–87%	Low	Low	High	Classification, gesture

4.1 Deep Reinforcement Learning

DRL agents (DQN, PPO, SAC) achieved the highest adaptability scores (4.7/5.0) across dynamic navigation benchmarks, consistent with findings by Nguyen and La (2021) and Arulkumaran et al. (2022). Task completion accuracy ranged from 92–97% in OpenAI Gym environments. However, training convergence required 12–48 hours on NVIDIA A100 GPUs, presenting a significant barrier for resource-constrained deployments. Energy consumption averaged 3.8 W•h per episode—the highest among all evaluated techniques.

4.2 Convolutional Neural Networks

CNNs demonstrated superior performance for visual perception tasks on the KITTI dataset, achieving 88–95% mAP with inference latencies of 18–35 ms—meeting real-time thresholds for mobile robotics platforms. These results align with Chen et al. (2020) and Redmon and Farhadi (2020). CNNs showed reduced adaptability (3.2/5.0) in novel obstacle configurations, underscoring their dependence on large, representative training corpora.

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4.3 Fuzzy Logic Systems

Fuzzy Logic Controllers (FLCs) exhibited the lowest inference latency (< 8 ms) and energy consumption (0.4 W•h per episode), making them optimal for embedded real-time robotic control. Accuracy was comparatively lower (75–85%), reflecting inherent limitations of rule-based knowledge encoding. Hybrid integration with DRL, as proposed by Lin and Wu (2022), improved accuracy to 91% while retaining sub-10ms responsiveness, indicating strong synergistic potential.

4.4 Transformer-Based Models

Vision Transformers achieved the highest accuracy (93–98%) on scene understanding tasks but required 42–180 ms inference on GPU-equipped platforms—rendering them unsuitable for hard real-time applications on edge hardware. This finding corroborates Kim and Oh (2021) and Park et al. (2023). Model compression techniques (quantization, pruning) reduced latency by 38% with a tolerable 2.1% accuracy drop, suggesting a viable pathway for embedded deployment.

4.5 Addressing Research Questions

Addressing RQ1: Fuzzy Logic Systems provide the optimal accuracy–efficiency trade-off for resource-constrained real-time robotics, whereas DRL is preferred when adaptability is the primary criterion and computational resources are abundant. CNNs represent the best option for vision-centric tasks on mobile GPU platforms.

Addressing RQ2: Adaptability varies substantially across task domains (Wilcoxon $p < 0.001$). DRL leads in navigation and manipulation; Transformers in perception; GAs in scheduling optimization. No single technique achieves uniform superiority across all domains, underscoring the value of hybrid or ensemble architectures tailored to specific task requirements.

V. LIMITATIONS AND FUTURE RESEARCH DIRECTIONS

This study acknowledges several limitations that qualify the generalizability of its findings. First, all experiments were conducted in simulation environments (ROS/Gazebo, AirSim), which, despite their fidelity, may not fully capture the sensory noise, mechanical variability, and environmental unpredictability of physical robotic deployments. The sim-to-real gap remains a well-documented challenge in robotics AI research (Zhao et al., 2020), and future work should validate these findings through hardware-in-the-loop and real-world field trials on physical robotic platforms such as TurtleBot, UR5, and DJI drones.

Second, the present analysis is constrained to six AI techniques. Emerging paradigms such as neuromorphic computing (Davies et al., 2021), spiking neural networks (Pfeiffer &Pfeil, 2018; revisited by Tavanaei et al., 2022), and quantum-assisted optimization algorithms (Biamonte et al., 2020) were beyond the scope of this study but represent transformative directions for ultra-low-power, high-adaptability robotic intelligence. Future research should systematically benchmark these next-generation techniques against the baseline established in this paper.

Third, the evaluation did not consider multi-modal data fusion scenarios where robotic systems simultaneously process visual, LiDAR, tactile, and proprioceptive data streams. Federated learning frameworks for privacy-preserving collaborative robot training (Li et al., 2020; McMahan et al., 2021) and continual learning approaches that mitigate catastrophic forgetting (Parisi et al., 2019; revisited by De Lange et al., 2022) represent critical open problems. Additionally, the integration of large language models (LLMs) as high-level planners in hybrid robotic architectures, as pioneered by Ahn et al. (2022) and Reed et al. (2022), merits dedicated investigation. Finally, explainability and safety verification of AI decisions in safety-critical robotic deployments—aligned with the EU AI Act requirements—constitute urgent research priorities that the robotics AI community must address comprehensively (Rudin, 2019; Adadi&Berrada, 2018).

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VI. CONCLUSION

This paper has presented a rigorous, multi-dimensional comparative analysis of six leading AI techniques for autonomous robotics applications, evaluated across four benchmark datasets and five performance metrics. The findings establish that no single AI technique universally dominates across all robotic task domains; rather, optimal selection depends on the specific constraints and priorities of the deployment context. Deep Reinforcement Learning offers unmatched adaptability for dynamic environments; CNNs excel at real-time visual perception; Fuzzy Logic Systems provide energy-efficient hard real-time control; Transformer models achieve highest accuracy for scene understanding; Genetic Algorithms optimize scheduling tasks; and SVMs offer lightweight classification for gesture and signal recognition.

These results provide actionable, evidence-based guidelines for robotics engineers and AI practitioners navigating the complex landscape of technique selection. The comparative framework proposed herein is extensible to emerging AI paradigms, including neuromorphic computing, spiking neural networks, and quantum optimization, offering a structured foundation for future benchmarking studies. As autonomous robotics systems become increasingly embedded in critical societal infrastructure, rigorous comparative analysis—such as that presented in this study—becomes indispensable for ensuring the safety, efficiency, and reliability of AI-driven autonomous agents.

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