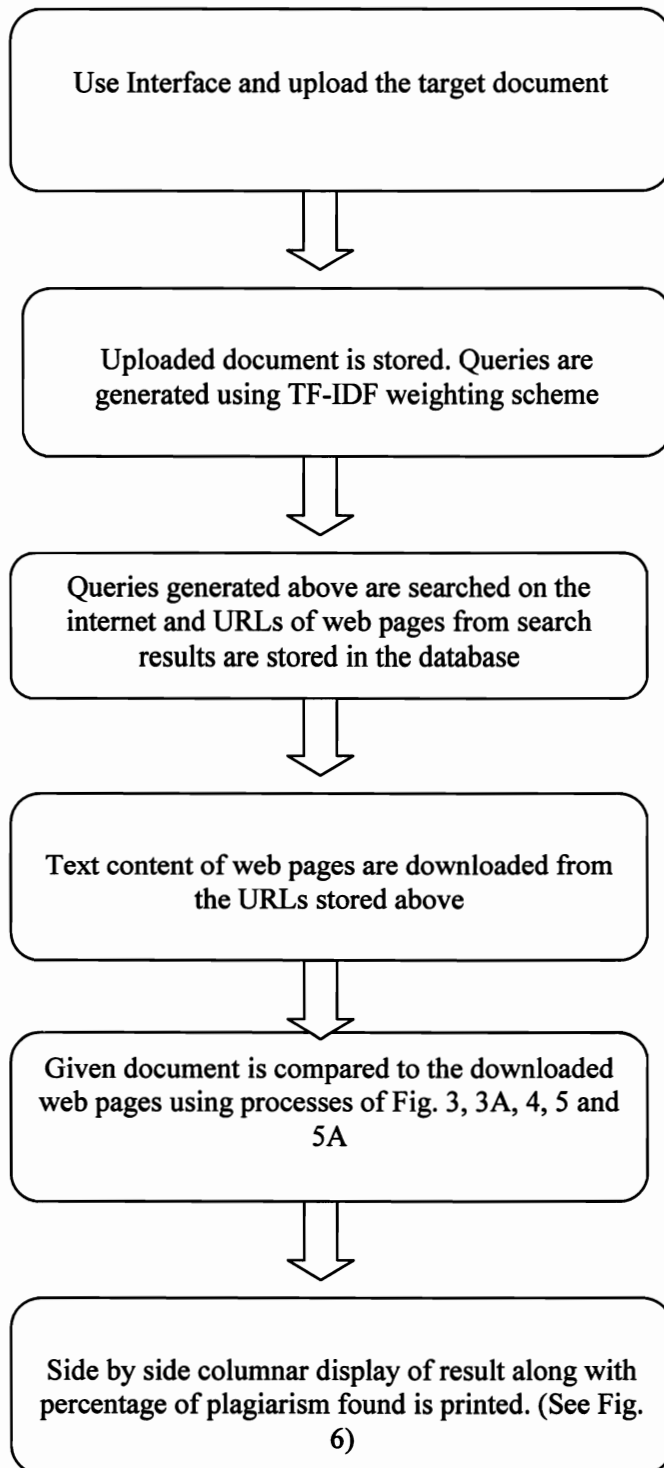
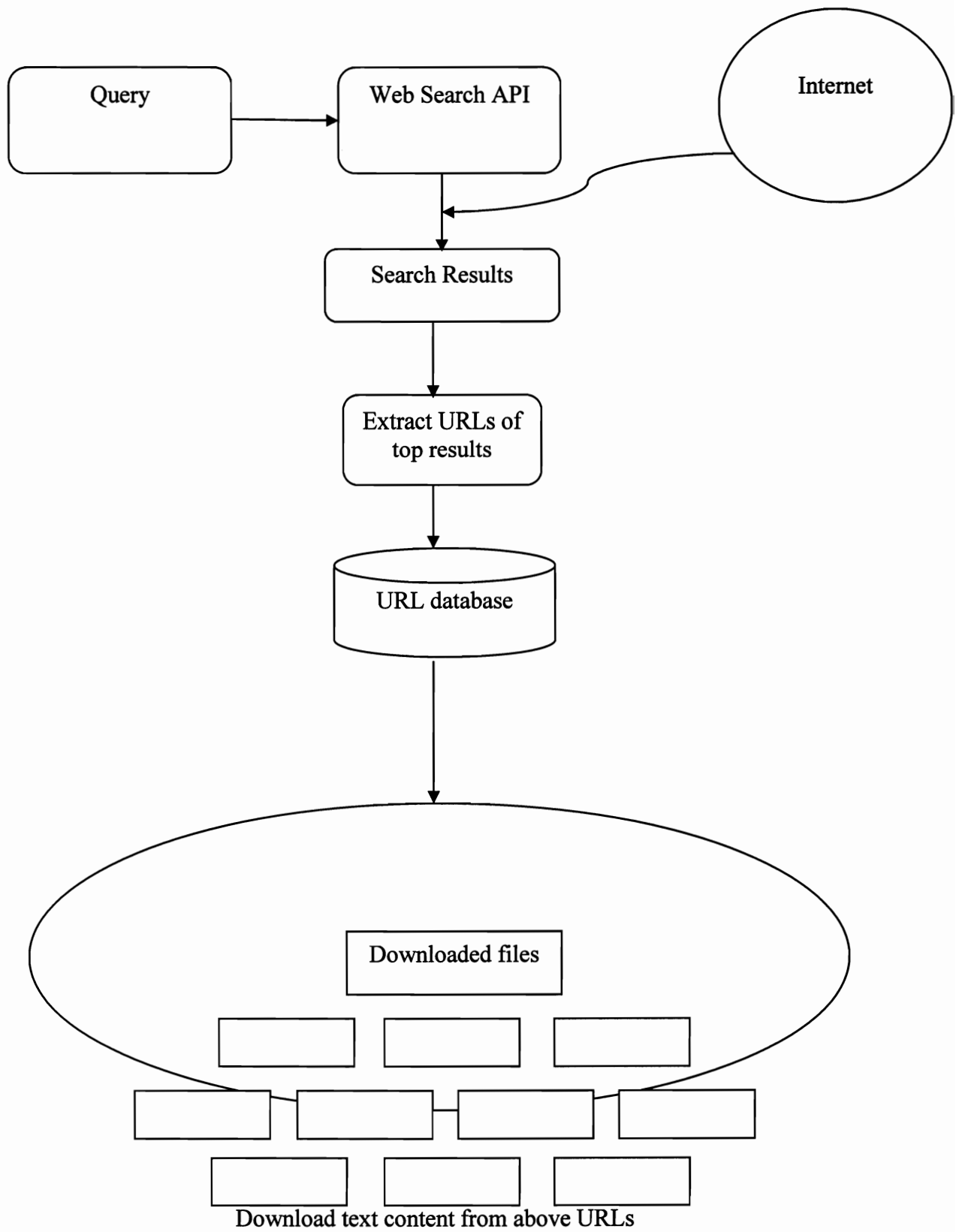
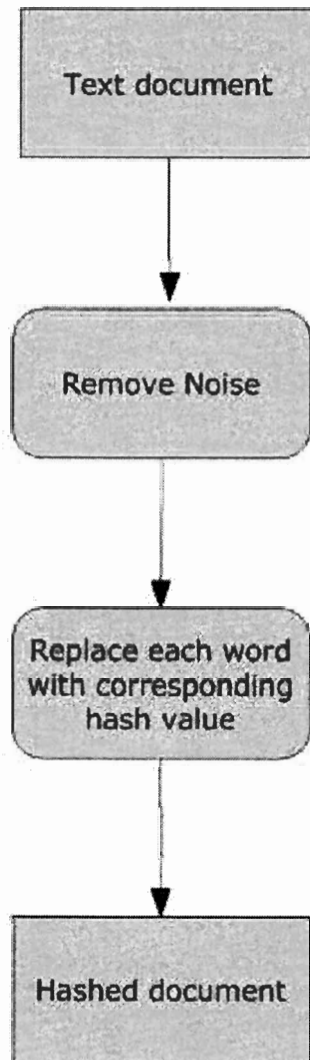


**Figure 1**

**Figure 2**



Conversion of text document into hashed document

Figure 3

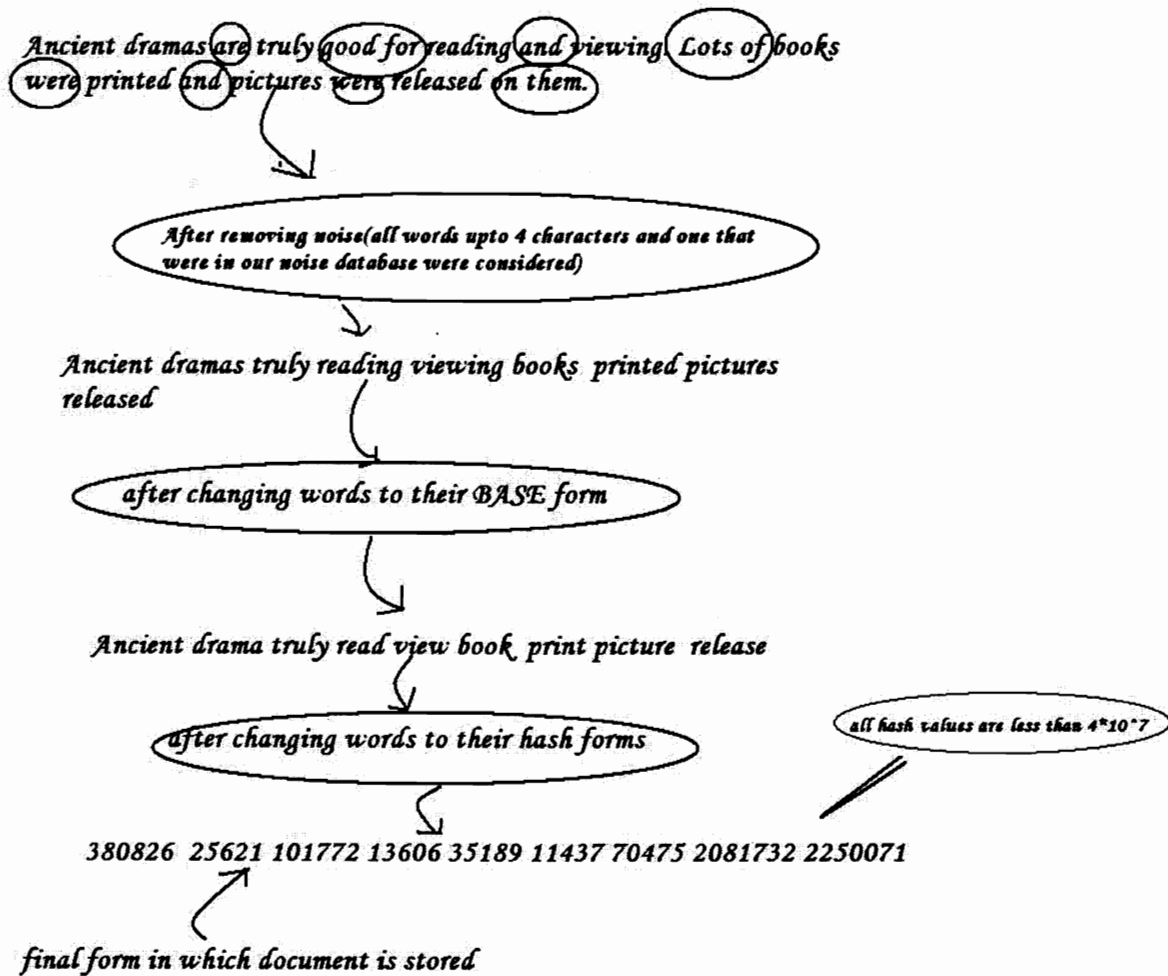
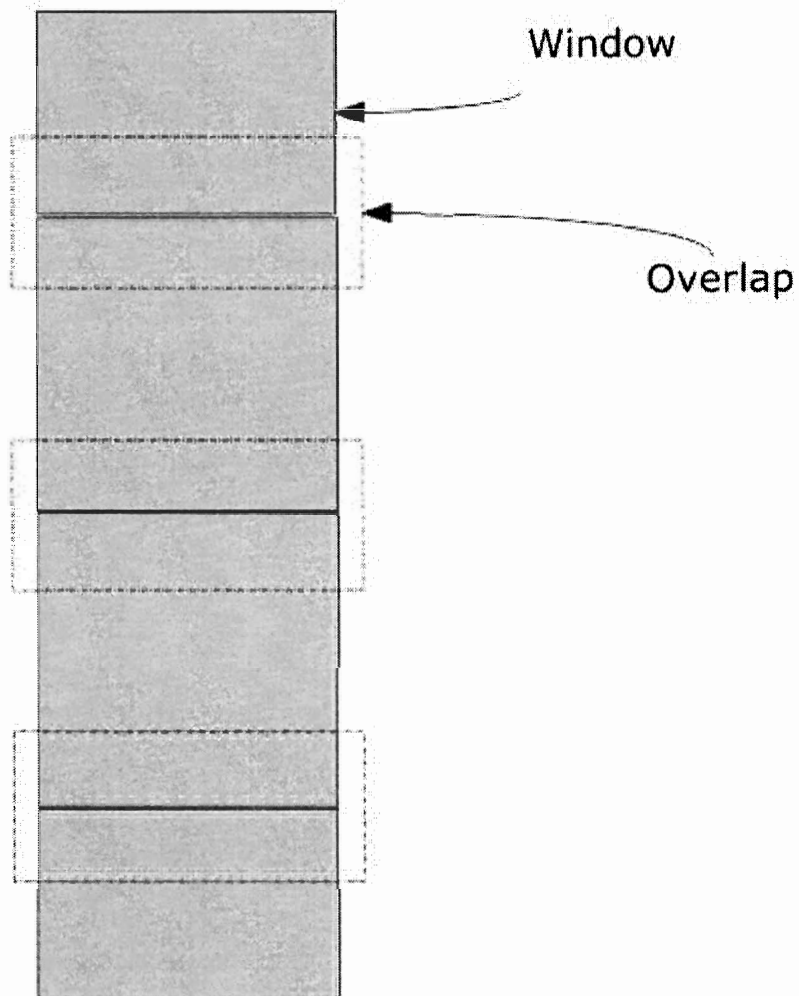


Figure 3A



Document divided into windows.
Overlap between successive windows is shown

Figure 4

Ancient dramas are truly good for reading and viewing. Lots of books were printed and pictures were released on them.

Antique plays like those of Shakespeare are really good to watch and read. Many books have also been published on those and many movies have been made.

after processing them by the procedure described in figure 3A

380826 25621 101772 13606 35189
11437 70475 2081732

435285 30744 344545 80401 13606 11437
2272251 57658 7607

11437 1
13606 1
25621 1
30744 1
35189 1
45321 1
57685 1
70475 1
101772 1
380826 1
435285 1
2081732 1
2453790 1
3892136 1

In an array all the hashes and its synonym (after consulting from dictionary) are set to their number of occurrences with all other value being zero.

Snippet of Dictionary

59437->49687 85980 2745820 18882 4187935
380826->435285 2453790
25621->30744 45321
2081732->57685 3892136

(For detail view how dictionary is generated see figure 6)

Fig-5- Comparison of two windows of two document

Figure 5

When reading second window same procedure as above is followed and if initially value is marked in array minimum of two value is taken and if total number of words hit cross a threshold paragraph is counted as plagiarised.

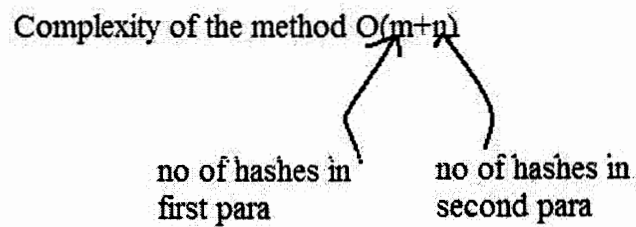


Figure 5A

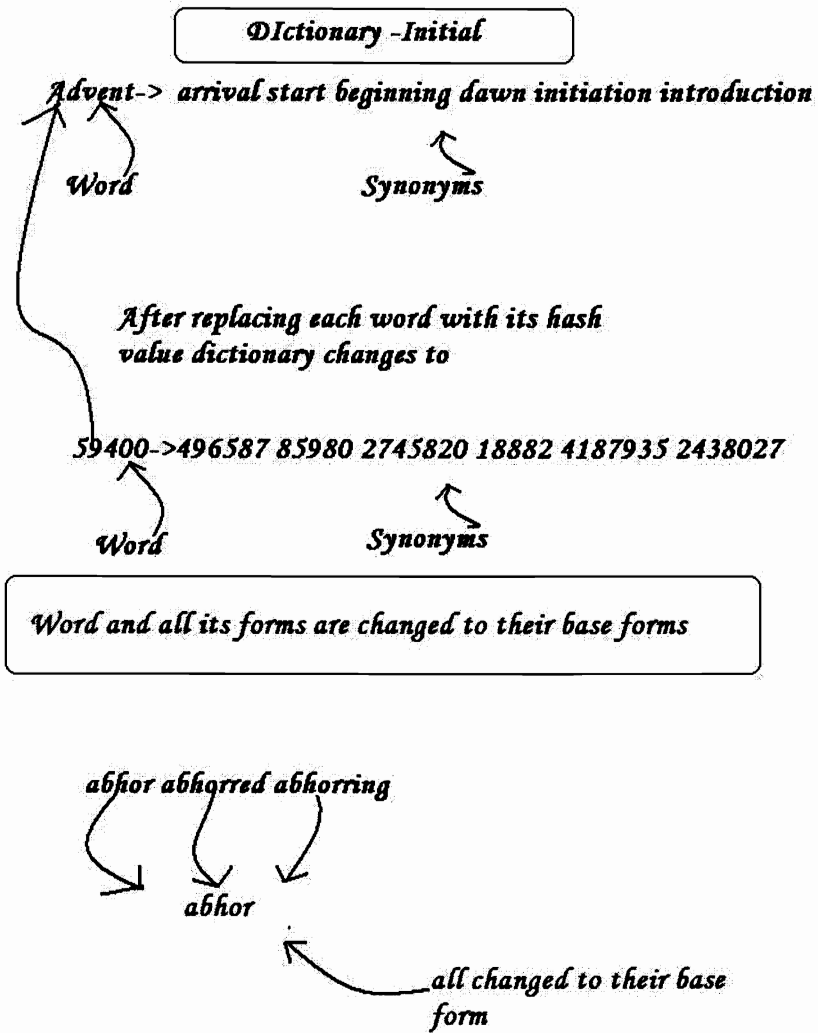


Figure 6

Original document

Source of copy

Line number Text	URL Line number Text
Line number Text	URL Line number Text
Line number Text	URL Line number Text

Percentage Plagiarism found:

Columnar display of result

Plagiarism Result	
Given Document	Plagiarized with
Line No 2 It has been observed that stable gait of an bipeds is a function of tasks handle is performing. Tasks like carrying buckets of water or heavy bottles need different gait to be generated. The problem discussed in the paper is the stability analysis of a human being while it is carrying some load. Trajectories of different joints are evaluated and stability of a person in a particular posture is predicted by selecting the trajectory which gives the maximum distance of Zero Moment Point (ZMP) from the edges of the stability region. The results were compared to kinematics of various bipeds.	Line No 21 It has been observed that stable gait of a human being is the stability analysis of a human body of structure while it is carrying some load e.g. bucket, book, bag or any of the various multisectional. Trajectories of different joints are evaluated and stable gait of a person in a particular posture is predicted by selecting the trajectory which gives the maximum distance of Zero Moment Point (ZMP) from the edges of the stability region. The results were compared to kinematics of various subjects measured by constructing the kinematics of a 7 Link, closed robot was simulated using the identified open kinematics engine which helped in modeling, learning & moving the robot bodies considering the external action. The results of ZMP control algorithm was evaluated which
Line No 7 inspired by video screening. A ZMP control algorithm has been evolved here which is used for maintaining the stability of bipeds during the walking on uneven terrain. Goal is to simulate the motion of a human body while carrying weight as by taking care of various joint parameters such as velocity, torque etc. Since humans do not have their own sensors provide measurements while walking, a control design was also proposed based on ZMP architecture for generation of angular patterned gait cycle. In that model reference values were	Line No 27 was used for maintaining the stability of bipeds during the walking on uneven terrain. Goal is to simulate the motion of a human body while carrying weight, as by taking care of various joint parameters such as velocity, torque etc. Since humans do not have their own sensors to provide measurements while walking, a control design was also proposed based on ZMP architecture for generation of angular patterned gait cycle. In that model reference values were generated using control algorithm values coming from sensors were verified with that. Finally the patterns were then

Figure 7