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During motion-to-goal, the robot moves along the m-line toward qgoal until it either encounters the goal or an obstacle. If the robot encounters an obstacle, let q_H be the point where the robot first encounters an obstacle and call this point a hit point. The robot then circumnavigates the obstacle until it returns to q_H . Then, the robot determines

Principles of Robot Motion: Theory, Algorithms, and ...
Principles of Robot Motion: Theory, Algorithms, and Implementations (Intelligent Robotics and Autonomous Agents series) Kindle Edition. by Howie Choset (Author), Kevin M. Lynch (Author), Seth Hutchinson (Author), George A. Kantor (Author), Wolfram Burgard (Author), Lydia E. Kavraki (Author), Sebastian Thrun (Author) & 4 more.

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Implementations H. Choset, K. M. Lynch, S. Hutchinson, G.

Kantor, W. Burgard, L. E. Kavraki and S. Thrun MIT Press,

Boston, 2005 Details and a sample chapter from the MIT Press site

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www.ros.org MoveIt Motion Planning Framework moveit.ros.org

The Open Motion Planning Library ompl.kavrakilab.org 4. 论文

Sampling-based. Probabilistic Roadmaps (PRM) Kavraki et al,

Probabilistic roadmaps for path planning in high-dimensional configuration spaces. 1996.

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