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Principles Of Robot Motion Theory

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 qH 1 be the point where the robot first encounters an obstacle and call this point a hit point. The robot then cir-cumnavigates the obstacle until it returns to qH 1. Then, the robot determines

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Navigation and motion control of a robot to a destination are tasks that have historically been performed with the assumption that contact with the environment is harmful.

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Principles of Robot Motion: Theory, Algorithms, and 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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