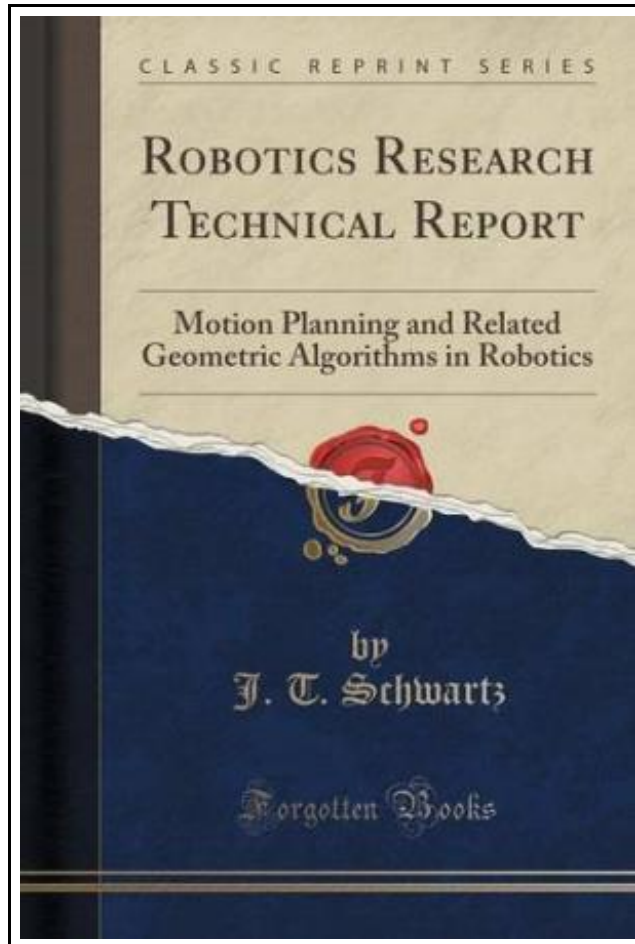


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Forgotten Books, United States, 2015. Paperback. Book Condition: New. 229 x 152 mm. Language: English . Brand New Book \*\*\*\*\* Print on Demand \*\*\*\*\*.Excerpt from **Robotics Research Technical Report: Motion Planning and Related Geometric Algorithms in Robotics** Research on theoretical problems in robotics looks ahead to a future generation of robots substantially more autonomous than present robotic systems, whose current algorithmic and software capabilities are rather primitive. The improved capabilities which this research aims to create can be grouped into three broad categories: sensing, planning, and control. Of these three, planning involves the use of an environment model to carry out significant parts of a robot's activities automatically. The aim is to allow the robot's user to specify a desired activity in very high level, general terms, and then have the system fill in the missing low-level details. For example, the user might specify the end product of some assembly process, and ask the system to construct a sequence of assembly substeps; or, at a less demanding level, to plan collision-free motions which pick up individual subparts of an object to be assembled, transport them to their assembly position, and insert them into their proper places. Studies in this area have shown it to have significant mathematical content; tools drawn from classical geometry, topology, algebraic geometry, algebra, and combinatorics have all proved relevant. This work relates closely to work in computational geometry, an area which has also progressed very rapidly during the last few years. About the Publisher Forgotten Books publishes hundreds of thousands of rare and classic books. Find more at This book is a reproduction of an important historical work. Forgotten Books uses state-of-the-art technology to digitally reconstruct the work, preserving the original format whilst repairing imperfections present in the aged copy. In rare cases, an...



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