

# *Contents*

*Foreword*    **xv**

*Preface*    **xvii**

*Acknowledgments*    **xxi**

## **1 Introduction    1**

- 1.1 Overview of Concepts in Motion Planning    9
- 1.2 Overview of the Book    12
- 1.3 Mathematical Style    13

## **2 Bug Algorithms    17**

- 2.1 Bug1 and Bug2    17
- 2.2 Tangent Bug    23
- 2.3 Implementation    30
  - 2.3.1 What Information: The Tangent Line    31
  - 2.3.2 How to Infer Information with Sensors: Distance and Gradient    32
  - 2.3.3 How to Process Sensor Information: Continuation Methods    35

## **3 Configuration Space    39**

- 3.1 Specifying a Robot's Configuration    40
- 3.2 Obstacles and the Configuration Space    43
  - 3.2.1 Circular Mobile Robot    43
  - 3.2.2 Two-Joint Planar Arm    45
- 3.3 The Dimension of the Configuration Space    47

3.4	The Topology of the Configuration Space	50
3.4.1	Homeomorphisms and Diffeomorphisms	51
3.4.2	Differentiable Manifolds	55
3.4.3	Connectedness and Compactness	58
3.4.4	Not All Configuration Spaces Are Manifolds	59
3.5	Embeddings of Manifolds in $\mathbb{R}^n$	59
3.5.1	Matrix Representations of Rigid-Body Configuration	60
3.6	Parameterizations of $SO(3)$	66
3.7	Example Configuration Spaces	68
3.8	Transforming Configuration and Velocity Representations	69
<b>4</b>	<b>Potential Functions</b>	<b>77</b>
4.1	Additive Attractive/Repulsive Potential	80
4.2	Gradient Descent	84
4.3	Computing Distance for Implementation in the Plane	85
4.3.1	Mobile Robot Implementation	86
4.3.2	Brushfire Algorithm: A Method to Compute Distance on a Grid	86
4.4	Local Minima Problem	89
4.5	Wave-Front Planner	90
4.6	Navigation Potential Functions	93
4.6.1	Sphere-Space	93
4.6.2	Star-Space	96
4.7	Potential Functions in Non-Euclidean Spaces	99
4.7.1	Relationship between Forces in the Workspace and Configuration Space	100
4.7.2	Potential Functions for Rigid-Body Robots	101
4.7.3	Path Planning for Articulated Bodies	104
<b>5</b>	<b>Roadmaps</b>	<b>107</b>
5.1	Visibility Maps: The Visibility Graph	110
5.1.1	Visibility Graph Definition	110
5.1.2	Visibility Graph Construction	113
5.2	Deformation Retracts: Generalized Voronoi Diagram	117
5.2.1	GVD Definition	118

5.2.2	GVD Roadmap Properties	119
5.2.3	Deformation Retract Definition	121
5.2.4	GVD Dimension: The Preimage Theorem and Critical Points	123
5.2.5	Construction of the GVD	126
5.3	Retract-like Structures: The Generalized Voronoi Graph	129
5.3.1	GVG Dimension: Transversality	130
5.3.2	Retract-like Structure Connectivity	133
5.3.3	Lyapunov Control: Sensor-Based Construction of the HGVG	136
5.4	Piecewise Retracts: The Rod-Hierarchical Generalized Voronoi Graph	138
5.5	Silhouette Methods	141
5.5.1	Canny's Roadmap Algorithm	142
5.5.2	Opportunistic Path Planner	151
<b>6</b>	<b>Cell Decompositions</b>	<b>161</b>
6.1	Trapezoidal Decomposition	162
6.2	Morse Cell Decompositions	168
6.2.1	Boustrophedon Decomposition	169
6.2.2	Morse Decomposition Definition	170
6.2.3	Examples of Morse Decomposition: Variable Slice	172
6.2.4	Sensor-Based Coverage	178
6.2.5	Complexity of Coverage	182
6.3	Visibility-Based Decompositions for Pursuit/Evasion	187
<b>7</b>	<b>Sampling-Based Algorithms</b>	<b>197</b>
7.1	Probabilistic Roadmaps	202
7.1.1	Basic PRM	203
7.1.2	A Practical Implementation of Basic PRM	208
7.1.3	PRM Sampling Strategies	216
7.1.4	PRM Connection Strategies	225
7.2	Single-Query Sampling-Based Planners	227
7.2.1	Expansive-Spaces Trees	230

7.2.2	Rapidly-Exploring Random Trees	233	
7.2.3	Connection Strategies and the SBL Planner	238	
7.3	Integration of Planners: Sampling-Based Roadmap of Trees	238	
7.4	Analysis of PRM	242	
7.4.1	PRM Operating in $\mathbb{R}^d$	243	
7.4.2	$(\epsilon, \alpha, \beta)$ -Expansiveness	246	
7.4.3	Abstract Path Tiling	250	
7.5	Beyond Basic Path Planning	253	
7.5.1	Control-Based Planning	253	
7.5.2	Multiple Robots	254	
7.5.3	Manipulation Planning	257	
7.5.4	Assembly Planning	259	
7.5.5	Flexible Objects	260	
7.5.6	Biological Applications	262	
<b>8</b>	<b><i>Kalman Filtering</i></b>	<b>269</b>	
8.1	Probabilistic Estimation	270	
8.2	Linear Kalman Filtering	272	
8.2.1	Overview	273	
8.2.2	A Simple Observer	274	
8.2.3	Observing with Probability Distributions	277	
8.2.4	The Kalman Filter	282	
8.2.5	Kalman Filter Summary	284	
8.2.6	Example: Kalman Filter for Dead Reckoning	285	
8.2.7	Observability in Linear Systems	287	
8.3	Extended Kalman Filter	289	
8.3.1	EKF for Range and Bearing Localization	290	
8.3.2	Data Association	292	
8.3.3	EKF for Range-Only Localization	294	
8.4	Kalman Filter for SLAM	294	
8.4.1	Simple SLAM	294	
8.4.2	Range and Bearing SLAM	296	
<b>9</b>	<b><i>Bayesian Methods</i></b>	<b>301</b>	
9.1	Localization	301	
9.1.1	The Basic Idea of Probabilistic Localization	302	

9.1.2	Probabilistic Localization as Recursive Bayesian Filtering	304
9.1.3	Derivation of Probabilistic Localization	308
9.1.4	Representations of the Posterior	310
9.1.5	Sensor Models	322
9.2	Mapping	328
9.2.1	Mapping with Known Locations of the Robot	328
9.2.2	Bayesian Simultaneous Localization and Mapping	337
<b>10</b>	<b><i>Robot Dynamics</i></b>	<b>349</b>
10.1	Lagrangian Dynamics	349
10.2	Standard Forms for Dynamics	353
10.3	Velocity Constraints	357
10.4	Dynamics of a Rigid Body	361
10.4.1	Planar Rotation	362
10.4.2	Spatial Rotation	363
<b>11</b>	<b><i>Trajectory Planning</i></b>	<b>373</b>
11.1	Preliminaries	374
11.2	Decoupled Trajectory Planning	374
11.2.1	Zero Inertia Points	378
11.2.2	Global Time-Optimal Trajectory Planning	384
11.3	Direct Trajectory Planning	384
11.3.1	Optimal Control	385
11.3.2	Nonlinear Optimization	389
11.3.3	Grid-Based Search	392
<b>12</b>	<b><i>Nonholonomic and Underactuated Systems</i></b>	<b>401</b>
12.1	Preliminaries	402
12.1.1	Tangent Spaces and Vector Fields	405
12.1.2	Distributions and Constraints	407
12.1.3	Lie Brackets	409
12.2	Control Systems	414

12.3	Controllability	416	
12.3.1	Local Accessibility and Controllability	419	
12.3.2	Global Controllability	422	
12.4	Simple Mechanical Control Systems	424	
12.4.1	Simplified Controllability Tests	425	
12.4.2	Kinematic Reductions for Motion Planning	434	
12.4.3	Simple Mechanical Systems with Nonholonomic Constraints	438	
12.5	Motion Planning	440	
12.5.1	Optimal Control	440	
12.5.2	Steering Chained-Form Systems Using Sinusoids	444	
12.5.3	Nonlinear Optimization	445	
12.5.4	Gradient Methods for Driftless Systems	446	
12.5.5	Differentially Flat Systems	447	
12.5.6	Cars and Cars Pulling Trailers	450	
12.5.7	Kinematic Reductions of Mechanical Systems	462	
12.5.8	Other Approaches	465	
<b>A Mathematical Notation</b>		<b>473</b>	
<b>B Basic Set Definitions</b>		<b>475</b>	
<b>C Topology and Metric Spaces</b>		<b>478</b>	
C.1	Topology	478	
C.2	Metric Spaces	479	
C.3	Normed and Inner Product Spaces	480	
C.4	Continuous Functions	481	
C.5	Jacobians and Gradients	483	
<b>D Curve Tracing</b>		<b>487</b>	
D.1	Implicit Function Theorem	487	
D.2	Newton-Raphson Convergence Theorem	488	
<b>E Representations of Orientation</b>		<b>489</b>	
E.1	Euler Angles	489	
E.2	Roll, Pitch, and Yaw Angles	491	

E.3	Axis-Angle Parameterization	492
E.4	Quaternions	494
<b>F</b>	<b><i>Polyhedral Robots in Polyhedral Worlds</i></b>	<b>499</b>
F.1	Representing Polygons in Two Dimensions	499
F.2	Intersection Tests for Polygons	502
F.3	Configuration Space Obstacles in $Q = \mathbb{R}^2$ : The Star Algorithm	507
F.4	Configuration Space Obstacles in $Q = SE(2)$	508
F.5	Computing Distances between Polytopes in $\mathbb{R}^2$ and $\mathbb{R}^3$	509
<b>G</b>	<b><i>Analysis of Algorithms and Complexity Classes</i></b>	<b>513</b>
G.1	Running Time	513
G.2	Complexity Theory	515
G.3	Completeness	520
<b>H</b>	<b><i>Graph Representation and Basic Search</i></b>	<b>521</b>
H.1	Graphs	521
H.2	$A^*$ Algorithm	527
H.2.1	Basic Notation and Assumptions	530
H.2.2	Discussion: Completeness, Efficiency, and Optimality	531
H.2.3	Greedy-Search and Dijkstra's Algorithm	532
H.2.4	Example of $A^*$ on a Grid	533
H.2.5	Nonoptimistic Example	535
H.3	$D^*$ Algorithm	536
H.4	Optimal Plans	546
<b>I</b>	<b><i>Statistics Primer</i></b>	<b>547</b>
I.1	Distributions and Densities	548
I.2	Expected Values and Covariances	550
I.3	Multivariate Gaussian Distributions	551
<b>J</b>	<b><i>Linear Systems and Control</i></b>	<b>552</b>
J.1	State Space Representation	552
J.2	Stability	554

J.3	LTI Control Systems	557
J.4	Observing LTI Systems	559
J.5	Discrete Time Systems	562
J.5.1	Stability	562
J.5.2	Controllability and Observability	563
<b>Bibliography</b>		<b>565</b>
<b>Index</b>		<b>597</b>