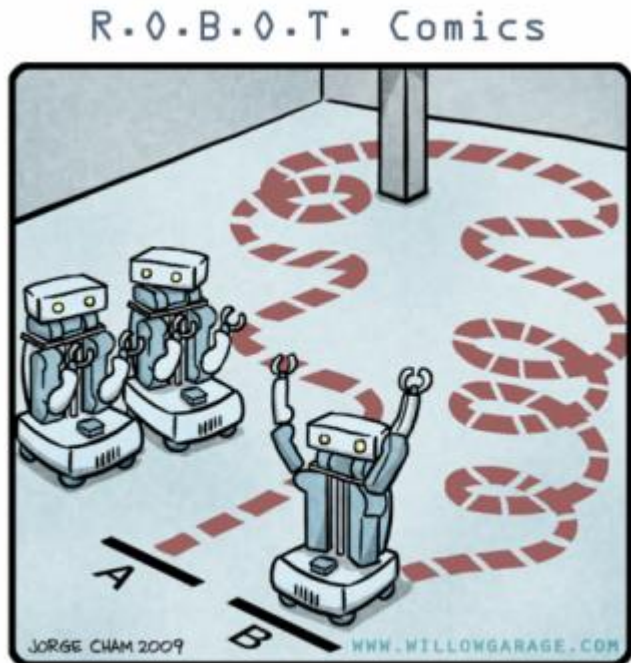
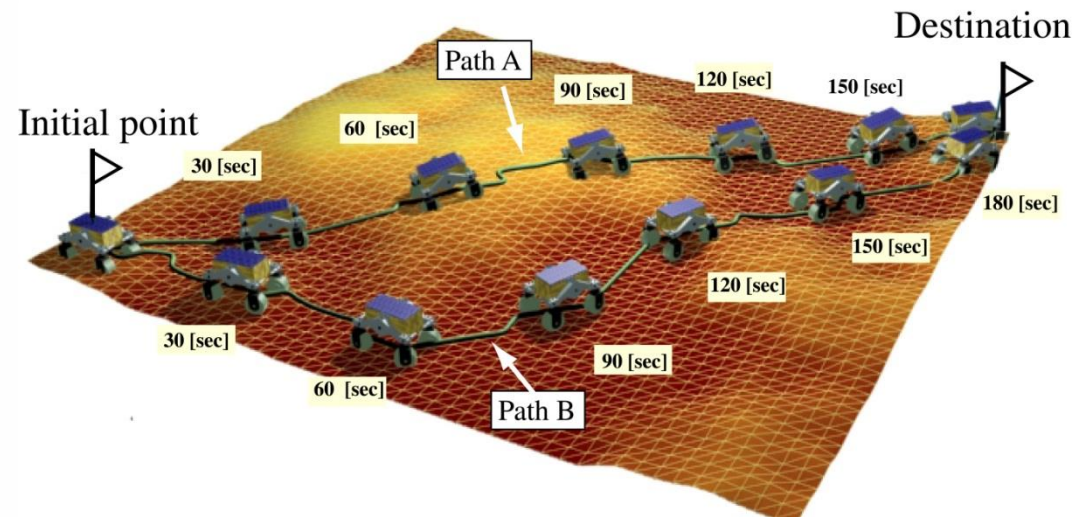


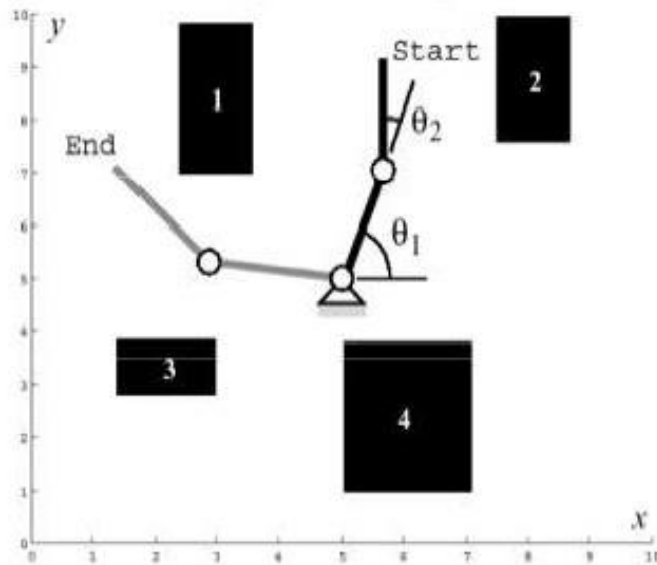
Reactive navigation and path planning



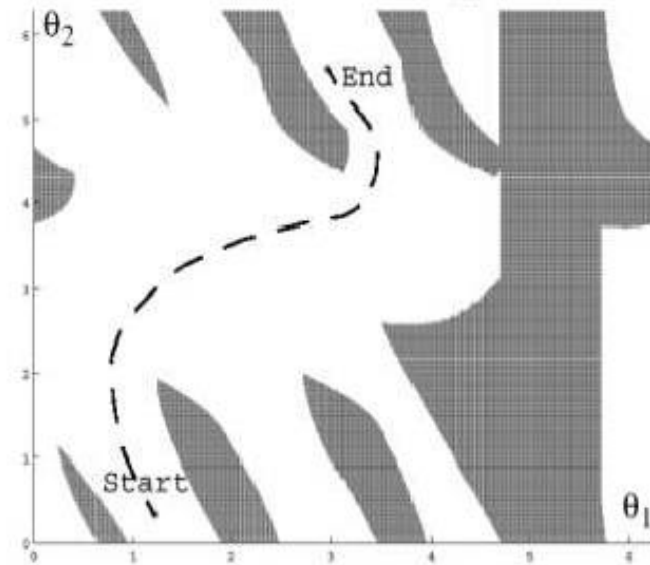
"HIS PATH-PLANNING MAY BE SUB-OPTIMAL, BUT IT'S GOT FLAIR."



Work- and configuration space

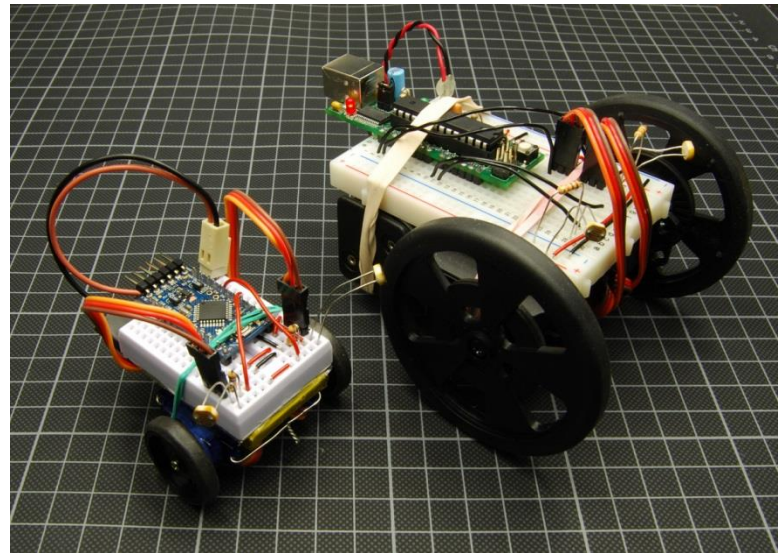
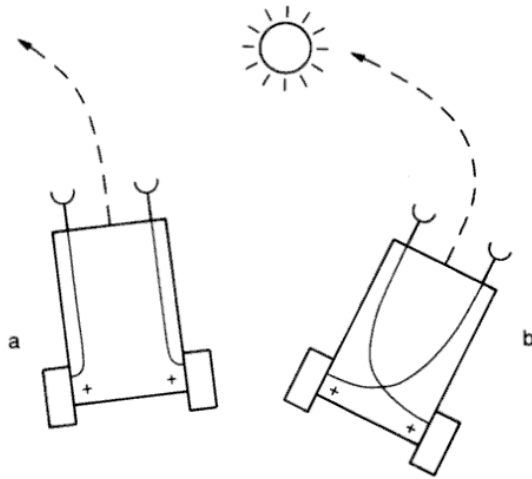


Workspace

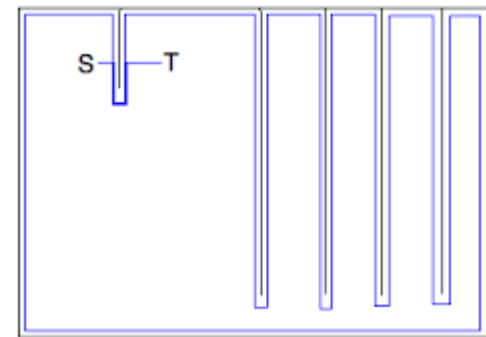
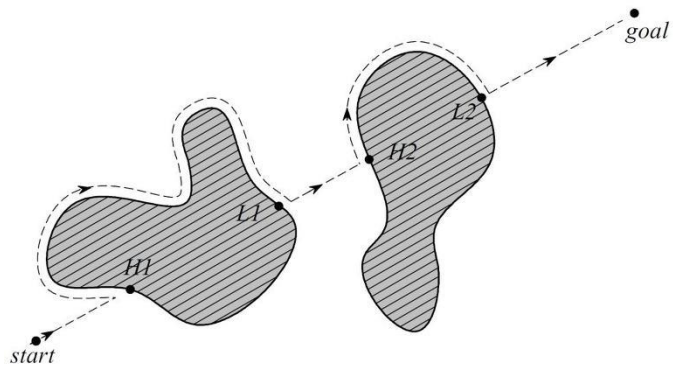
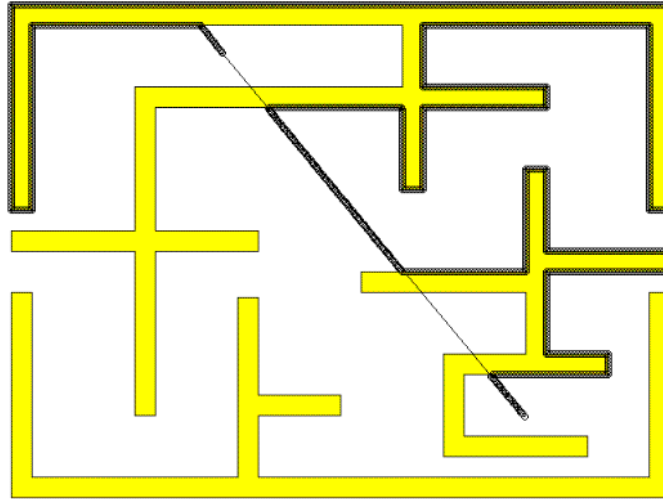


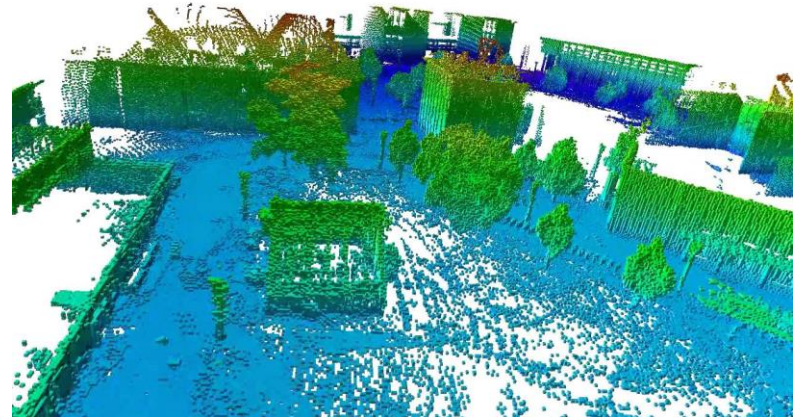
Configuration Space

Braitenberg vehicles

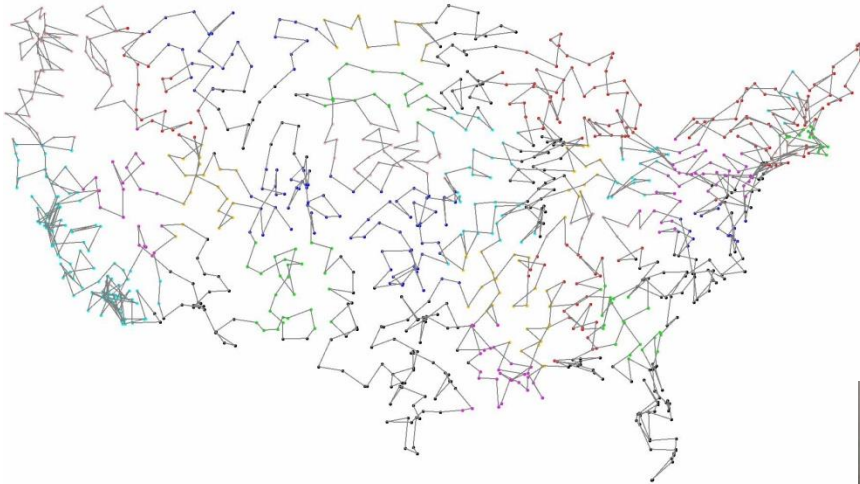


Bug2 algorithm



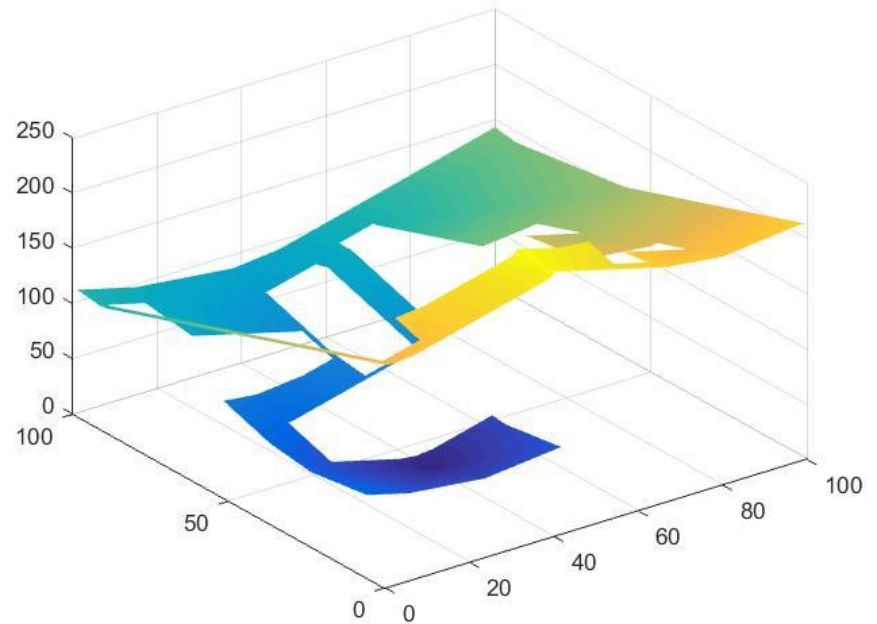
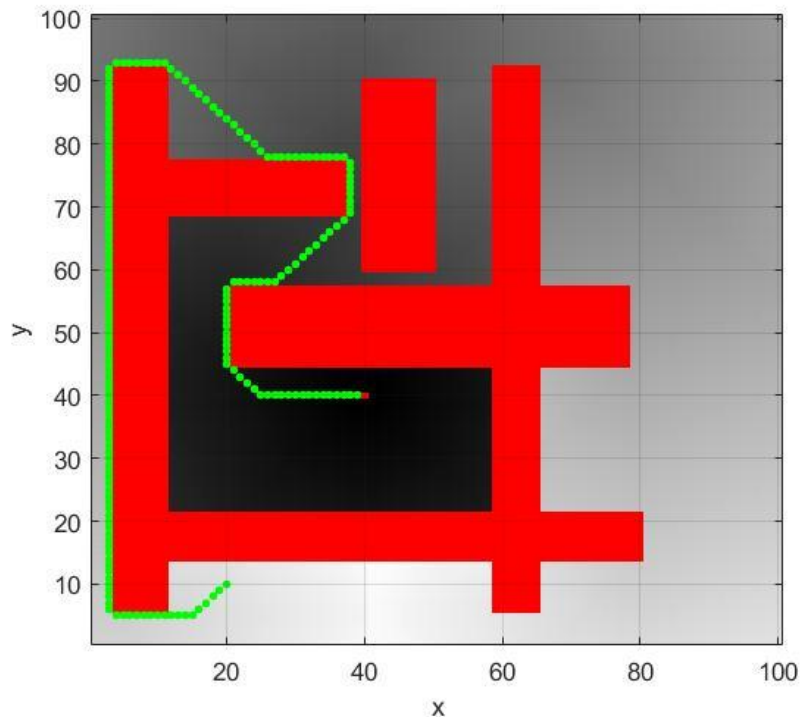
[illegible]

Related path planning



Path planning in occupancy grids

- Distance transform and D* algorithm



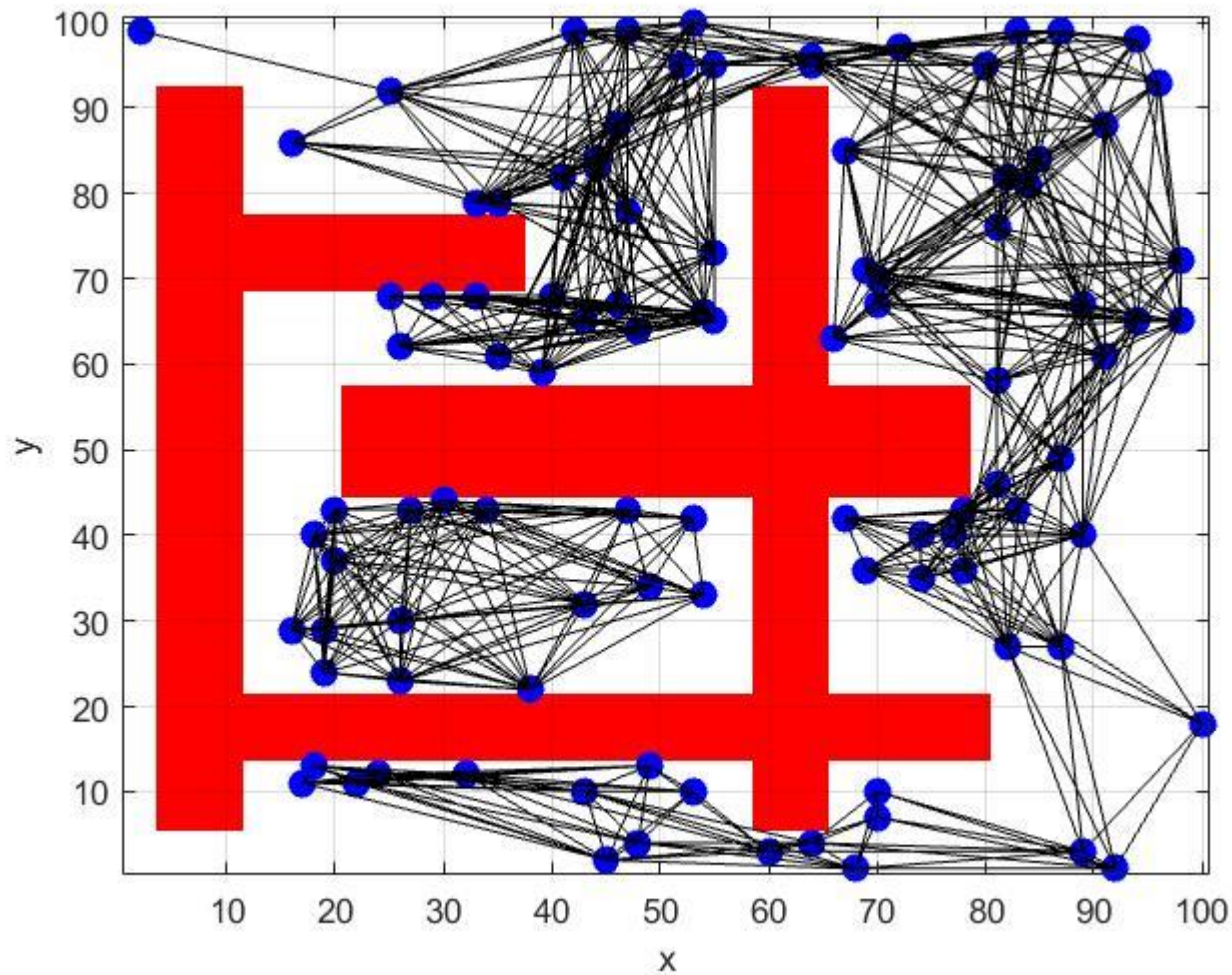
Distance transform in Computer Vision



Voronoi Roadmaps



Probabilistic Roadmap Method (PRM)



Map-based path planning with obstacle avoidance

- Combination of reactive navigation and static map-based path planning
- Global versus local planning

