Al Yahmedi *et al.* is a paper describing the ways high-level mobile robot behaviors can be combined with fuzzy logic to produce natural navigation. They start by describing mobile robot navigation and summarizing some of the problems associated with final, output behavior determination. For instance, some pre-fuzzy navigation schemes propose selecting the most important behavior and using that as long as the initiating conditions apply. For example, even though a robot is trying to navigate to some end-goal, it is more important in the current moment that they move to avoid the obstacle between them and their goal. In this case, obstacle avoiding behavior takes priority over end-goal navigation behavior. Such navigation, where a single behavior is chosen and others ignored, can lead to sub-optimal path choice. The authors propose a fuzzy rule based system for behavior determination. The inputs from range sensors around the robot are combined in fuzzy rules to produce composite behaviors which act to achieve multiple goals simultaneously. While avoiding an obstacle, the robot no longer forgets about the end goal, but navigates towards it while avoiding the obstacle. The authors observed that both simulated and physical robots could navigate environments representative of office or residence floor plans. They recorded the paths for the robots through their environments with what behaviors were engaged at the different segments of the paths. Their results demonstrate that their fuzzy system combines different behaviors, resulting in short and smooth paths from the robot’s start-point to end-point. Unfortunately, they do not test non-fuzzy, single-behavior robots in their environments. As such, not much can be said about how naturally or quickly the fuzzy robots navigate. While the paper may fall short on application information for its lack of comparative results, it is a good source of references. It refers to over a dozen other mobile robot navigation schemes, fuzzy or otherwise. These are a good source of information to learn, first how navigation is treated generally in terms of behavior models, then of different fuzzy and non-fuzzy approaches to producing or selecting behaviors.