

Implementation of biologically-inspired dynamical systems for movement generation: automatic real-time goal adaptation and obstacle avoidance

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Abstract—

I. INTRODUCTION

II. APPROACH

- A. Distance to objects*
- B. Collision monitoring*
- C. Potential field*
- D. Controller*

III. EXPERIMENTS

- A. Testing*
- B. ROS*
- C. Results*

IV. USE CASE

- A. Single arm*
- B. Dual arm*
- C. Self collision*

V. CONCLUSION

APPENDICES

ACKNOWLEDGMENTS

REFERENCES

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