| $(k_1 \mid k_2)$ notation, 275 C^{∞} -related, 56 SE(n), 62 SO(3), 62 SO(n), 61 ϵ -neighborhood, 475 3R robot arm, 462 | boundary, 476 bounded, 18 boustrophedon decomposition, 169 bridge planner, 217 brushfire algorithm, 87 Bug1, 17 Bug2, 19 |
|--|---|
| accessible, 416 AERCam, 2 affine connection, 429 angular momentum, 364 applicability condition, 504 Ariadne's clew, 228 artificial potential function, 12 assembly, 259 asymptotic stability, 554 atan2, 74 atlas, 57 axis-angle parameterization, 492 | C-space, 40 car, 450 car pulling trailer, 459 Cauchy sequence, 480 cell decomposition, 13 center of mass, 362 centralized planning, 254 centrifugal term, 354 chain rule, 484 chained form, 444 chart, 55 Chow's theorem, 419 Christoffel symbol, 354 |
| bad bracket, 420 ball-and-socket joint, 49 Banach space, 481 base variable, 442 Bayes' rule, 548 Bayesian estimation, 13 bijective, 52 biology, 262 body inertia matrix, 366 body-frame transformation, 65 | closed set, 476 closed-chain robot, 49 closest neighbors, 209 closure, 476 codimension, 132 codistribution, 408 collision, 201 collision checking, 212 column space, 276 compact, 59 |

compact factor, 59 complement of a set, 475 complete, 407 complete planner, 6 complexity, 198 complexity theory, 515 computational complexity, 10 conditional probability, 548 configuration, 2, 39, 40, 202, 203, 227 configuration space, 10, 39, 40, 198 configuration space obstacle, 2, 43 configuration space, 2 connected, 58 connected component, 205, 225 connected components, 58 connection sampling, 223 connectivity, 202, 203, 205, 207 conservative, 47 constrained affine connection, 438 continuous function, 481 control affine nonlinear system, 415 control vector field, 415 control vector field, 406 control-based planning, 253 controllability, 401, 557 controllable, 416 convex hull, 477, 510 convex polygonal region, 500 convexity, 477 coordinate system, 56 Coriolis matrix, 354 Coriolis term, 354 cotangent bundle, 408 cotangent space, 408 covariance matrix, 278, 551 covariant derivative, 426 covector, 408 covector field, 408 cover, 168 coverage, 6 critical arc, 380

critical point, 78, 125, 379
critical values, 142
cumulutive distribution function
(CDF), 549
cycle algorithm, 181

data association, 292 dead reckoning, 285 decision problems, 516 decoupled planning, 256 decoupling vector field, 435 deformation retract, 118 deformation retraction, 121 degrees of freedom, 2, 10, 40 dense set, 477 deterministic sampling, 219 diffeomorphism, 53 differentiable manifold, 55, 57 differential, 69 differential drive, 452 differentially flat, 447 discrepancy, 219 dispersion, 220 distance function, 203 distance metric, 210, 428 distribution, 408 docking, 262 domain, 481 drift vector field, 406, 415 drift-free, 415 dynamical polysystem, 414

edge, 202, 203
eigenvalue placement, 558
eight-point connectivity, 87
EKF, 269, 289
elbow-down, 41
elbow-up, 41
embedding, 59, 210
end effector, 40
equilibrium controllable, 431
EST, 200, 201, 228, 230

Euclidean metric, 429
Euler angles, 66, 489
Euler's equation, 364
Euler-Lagrange equations, 350
events, 165
exact planning, 198
exhaustive search, 22
expected value, 550
extended Kalman filter (EKF), 289
extended system, 465

feedback transformation, 356 fiber controllability, 442 fiber variable, 442 fictitious input, 466 filtration, 411 first fundamental group, 122 fixed axis parameterizations, 491 flat output, 447 flexible object, 260 flow, 407 foliation, 412 forward kinematics, 69 four-bar mechanism, 72 four-point connectivity, 87 free configuration space, 43 free path, 43 free space, 43 freeways, 151 free configuration space, 14 free workspace, 14 Frobenius theorem, 412

Gaussian distribution, 277, 551 generalized coordinate, 350 generalized force, 350 generalized gradient, 155 generalized Voronoi graph, 129 generalized Voronoi region, 118 generalized mover's problem, 2 generic loop, 447 geodesic, 428

GJK distance computation algorithm, 509 global localization, 302 good bracket, 420 gradient, 77, 483 graph, 203 greedy, 22 grid, 86 group, 60 Grübler's formula, 50

Hamiltonian, 386 Hessian, 78 Hilbert space, 481 holonomic constraint, 48, 361 homeomorphism, 53 homogeneous coordinates, 64 homotopic, 121 homotopy, 121 hopping robot, 433 hyper-redundant, 50 hyper-redundant robot, 7

image, 52 implicit function, 120 implicit function theorem, 36, 487 inadmissible region, 376 inertia matrix, 353 inertial frame inertia matrix, 364 injective, 52 inner product, 427, 481 innovation, 276 integral curve, 407 integral manifold, 407, 412 interior, 476 intersection, 475 inverse kinematics, 69 involutive, 412 involutive closure, 412

Jacobian, 35, 39, 69, 356, 483 junction region, 141

Kalman filter, 269, 284
Kalman filtering, 13
kidnapped robot problem, 302
kinematic, 2
kinematic reduction, 435
kinematic reduction, rank 1, 435
kinematic reduction, rank *m*, 435
kinematically controllable, 437
kinetic energy metric, 429
kinodynamic, 228
knife-edge, 359

Lagrange multipliers, 357, 386 Lagrange's equations, 350 Lagrangian, 350, 386 LARC, 419 lazy evaluation, 226 leaf, 412 left arm, 69 left-arm, 41, 42 Legendre-Clebsch condition, 387 Lie algebra, 402, 411 Lie algebra rank condition, 419 Lie bracket, 409, 410 Lie product, 410 line of nodes, 369 line of sight, 477 linear state feedback, 557 local planner, 203, 207, 211 localization, 4, 9 locally diffeomorphic, 54 locally homeomorphic, 54

Mahalanobis distance, 279, 293
Manhattan distance
metric, 480
manifold, 55
manifold with boundary, 59
manipulation, 257
mapping, 5, 9
mass matrix, 353
matrix commutator, 467

maximally reducible to a kinematic system, 435 mean, 550 measurement noise, 273 meet points, 119 metric, 479 metric space, 479 metric spaces, 479 metric topology, 480 Minkowski difference, 477, 508 Minkowski sum, 477 mobility, 49 Morse, 93 Morse decomposition, 169, 171 motion model, 305 motion library, 466 motion planning, 14

natural pairing, 408 navigation, 9 navigation function, 80, 93 navigation functions, 93 negative half plane, 500 neighborhood, 54, 475, 479 neutralize, 421 Newton-Raphson convergence theorem, 488 nilpotent, 412 nilpotentizable, 466 node, 202, 203 non-degenerate, 78 non-Euclidean space, 2 nonholonomic, 4, 10, 13, 409 nonholonomic constraint, 48, 361, 401 nonlinear optimization, 390 nonwandering point, 423 nonwandering set, 423 normed space, 480 null space, 35, 276

observability, 287, 559 observation model, 305

potential function, 77 observer, 559 obstacle based sampling, 216 preimage, 52 offline, 11 principal axis of inertia, 366 offline planning, 2 prior, 305 offset curve, 33, 35 prior probability, 305 priority queue, 526 one-form, 408 one-to-one, 52 prismatic joint, 49 online, 11 PRM, 198, 200, 201 onto, 52 probabilistic completeness, 201, 243 open ball, 54, 480 probabilistic localization, 270 open set, 476, 478 probabilistic roadmap, 202 opportunistic, 22 probability density function (PDF), 549 opportunistic path planner, 151 optimal control, 440 probability mass function (PMF), 549 optimization problems, 516 process noise, 273 orthogonal, 276, 427 product of Gaussians, 283 protein folding, 262 parallel mechanism, 49 pursuit/evasion problem, 187 parallel-axis theorem, 363, 369 parameterization, 56 quasirandom sampling, 219 path, 2, 14, 202, 203, 205 quaternions, 494 query, 202–204 path planning, 14 path-connected, 58 Peano-Baker, 554 random variable, 548 random vector, 550 Pfaffian constraint, 357, 409 Philip Hall basis, 412 range, 481 piano mover's problem, 1 raw distance function, 23 pixel, 86 reduced visibility graph, 111 redundant, 50 planar body with thrusters, 404 plane sweep algorithms, 114 redundant robot, 7 planner, 197, 198, 201, 202 Reeb graph, 178 polygon, 501 Reeds-Shepp curve, 453 polygon soup, 499 regular, 411 polygonal region, 501 regular distribution, 408 Pontryagin minimum principle, 386 regular value, 125 position tracking, 301 retract, 121 positive half plane, 500 retraction, 121 positively Poisson stable, 423 revolute joint, 49 post processing, 212 Riemannian metric, 429 posterior, 304 right arm, 69 posterior probability, 304 right-arm, 41, 42 potential, 227 roadmap, 12, 198, 202, 203, 205

robot, 197, 198, 203, 227 sofa mover's problem, 2 robot dynamics, 2, 13 special Euclidean group, 62 rod, 138 special orthogonal group, 62 roll, pitch and yaw, 491 spherical joint, 49 rotation matrix, 66, 67 SRT, 200, 201, 238, 257 RP manipulator, 351 stability, 554 RPP, 227, 228 standard topology, 478 RRT, 200, 201, 228, 233 star algorithm, 507 star-shaped, 97, 477 star-spaces, 97 sampling-based, 197, 198, 227 saturate raw distance function, 23 state space, 552 SBL, 229 STLA, 416 STLC, 417 semifree path, 43 sensor-based, 11 STLCA, 431 sensor-based planning, 5 STLCC, 431 serial mechanism, 49 **STLEC**, 431 STLKC, 437 set, 475 shape variable, 442 submanifold, 60 shortest path, 427 subset, 475 silhouette curve, 142 surjective, 52 simple mechanical control system, 425 sweep line, 114, 165 symmetric closure, 431 singular, 70 singular arc, 380 symmetric control system, 414 singular optimal control, 388 symmetric product, 430 singular point, 380 SLAM, 5, 270, 294 tangent, 31 slice, 141 Tangent Bug, 23 small-time local equilibrium tangent bundle, 405 controllability, 431 tangent map, 483 small-time locally accessible, 416 tangent space, 125, 405 small-time locally configuration tangent vector, 405 accessible, 431 time scaling, 374 small-time locally configuration time-optimal, 6 controllable, 431 topological space, 478 small-time locally controllable, 417 topology, 50, 478 small-time locally kinematically torus, 41 controllable, 437 trajectory, 2 smooth, 53 trajectory planning, 13 smooth curve, 484 transform matrix, 62 smooth function, 482 transversal, 132 smoothing, 205 transversality, 131 snakeboard, 470 tree, 228

two-form, 408, 429 type A contact, 503 type B contact, 503

ultrasonic sensor, 33 underactuated, 401 underactuation, 13 unicycle, 403 uniform distribution, 203, 550 uniform sampling, 208, 216 union, 475

variance, 551 vector field, 77, 405 velocity limit curve, 377 visibility graph, 110 visibility-based sampling, 218 Voronoi region, 118

weakly positively Poisson stable, 423 white noise, 273 workspace, 14, 40, 203, 227 world-frame transformation, 65

zero inertia point, 375, 379