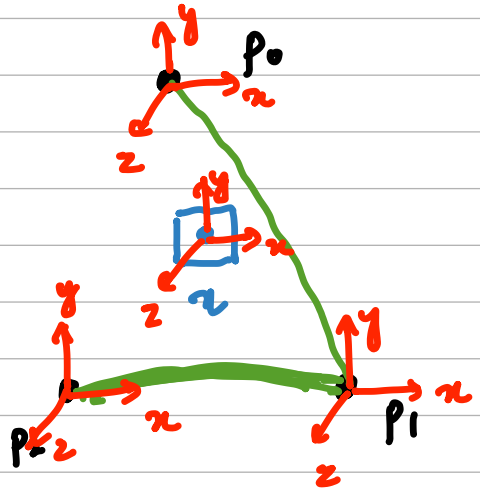


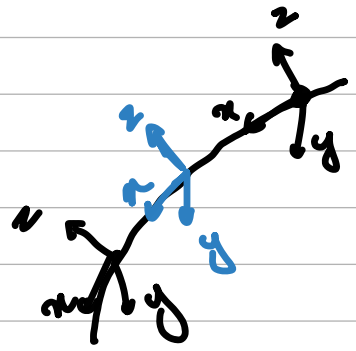
For initial planning the coordinates of obstacle

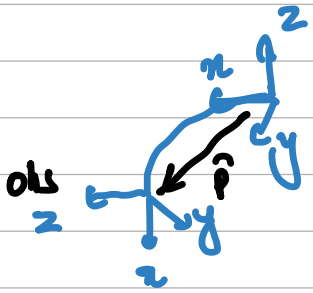
$q_1 = x - p_0$

For second planning the coordinates of obstacle

$q_2 = x - p_1$

If the global docking points frames are left in the same orientation then obstacle mapping is easy





for this orientation with respect to global axis know

T_G^0 known

To plan we need just T_p^0

T_G^p known

$T_G^p \times T_p^0 = T_G^0$

$T_p^0 = (T_G^p)^{-1} T_G^0$

1. ICCAR 2025 Kyoto April 18-20 [Submissions now open]

Deadline Dec 20th, 2024

2. ICARA 2025 Zagreb Croatia Feb 12-14 [Submissions now open]

↓

more towards intelligent robotics side

Deadline : Sept 25th 2024 (No less than 4 pages)

→ within 5 pages

3. ICIAE 2024 Singapore Nov 15-17

→5 pages minimum

Deadline for Abstracts and Full paper : July 25 2024