Knowledge of the environment

Obstacle characteristics

Robot characteristics

Problem class

$_{n}avigation_{2}005 published in 2005, Dr. Stilman, the founder of the NAMO domain, established a NAMO problem classificati$

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LP_{1}

LP_{2}

$_{p}lanning_{2}008 published in 2008. This notation allows us to quickly know what kind of situation an algorithm will be able to solve o$

Path Planning Algorithm(s) and heuristics

1

Evaluation and evolution of an obstacle's "movable" characteristic and its associated cost

Object manipulation maneuver planning

Planning taking uncertainty into account

Evaluation in a simulated/real setting

Computation time

Optimality and completeness

$lo$$cally$ $op$$ti$$mal$

Optimality target

Social acceptability

Number