Uncertainty Aware Mobile Manipulator Platform Pose Planning Based on Capability Map

Yuhao Meng, Yujing Chen and Yunjiang Lou School of Mechanical Engineering and Automation, Harbin Institute of Technology Shenzhen, China

- Mobile manipulator platform has great pose uncertainty in cluster and dynamic environment.
- Find a platform pose with higher manipulability expectation under the uncertainty.
- Use a uncertainty distribution based filter to the feasible platform poses.
- Achieve higher manipulability expectation with less computing time increasement.

