

# Optimized Underwater Manipulator Path Planning to Minimize The Disturbance on Robot

Xiaodi Liu , Xin Wang\* and Xiaotian Cai

Mechanical Engineering and Automation,  
Harbin Institute of Technology Shenzhen, China.

- The goal of the path planning in this paper is to cause the smallest possible variation in disturbance moments to the robot body.
- Generates a disturbance map by data collection, on the basis of which the path search is then carried out.
- Develop an algorithm based on the path search of the underwater manipulator and the optimized trajectory generation to minimize the disturbance to the robot body.

