

RRT-GoalBias and Path Smoothing Based Motion Planning of Mobile Manipulators with Obstacle Avoidance

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- The motion planning based on the RRT-GoalBias algorithm and path smoothing is proposed.
- The kinematics model of mobile manipulator, constraints of configuration and obstacle avoidance are given.
- The RRT-GoalBias algorithm is applied and modified to generate an initial path.
- A novel post-processing algorithm is proposed to smooth and optimize the initial path.

