

# IEEE RCAR 2020 Digest Template

## Paper Title in One or Two Lines

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- We construct a vector field histogram based on the observed static obstacles and pedestrians.
- An objective function is proposed to get an optimal direction of the mobile robot.
- We introduce a fuzzy inference system to generate smooth and efficient motion.
- The proposed planner is tested on a robot in various densely crowded scenarios



Robot navigation in dense crowds by the proposed planner