

# State of the art

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## Article 1

### Cooperative leader following in a distributed multi-robot system

In this paper they adress the problem of managing a group robots with heterogeneous capabilities. The first robot navigates by using a predefined pattern or by being teleoperated, whie the other robots follow it. To achieve that, a series of rules are needed, at team and individual level (both levels can be executed in parallel). Those behaviours are:

- **Team - Follow:** every robot follows the local leader
- **Team - Wait:** If an unexpected event happens the group stops
- **Team - Recover:** It is executed to recover from a wait conditiond
- **Robot - Follow:**
- **Robot - Local wait:**
- **Robot - Remote wait:**
- **Robot - Local recover:**
- **Robot - Remote recover:**