Enrico Saccon,
The following list of publications is current as of June 3, 2025

[1] P. Pastorelli, S. Dagnino, E. Saccon, M. Frego, and L. Palopoli, "Fast shortest path polyline smoothing with G^1 continuity and bounded curvature," *IEEE Robotics and Automation Letters*, 2025.

[2] E. Saccon, A. Tikna, D. D. Martini, E. Lamon, L. Palopoli, and M. Roveri, *A temporal planning framework for multi-agent systems via llm-aided knowledge base management*, 2025. arXiv: `2502.19135 [cs.AI]`. [Online]. Available: `https://arxiv.org/abs/2502.19135`.

[3] E. Saccon, A. Tikna, D. De Martini, E. Lamon, L. Palopoli, and M. Roveri, "When prolog meets generative models: A new approach for managing knowledge and planning in robotic applications," in *2024 IEEE International Conference on Robotics and Automation (ICRA)*, IEEE, 2024, pp. 17 065–17 071.

[4] E. Saccon, "Multi-agent open framework: Developing a holistic system to solve mapf (student abstract)," in *Proceedings of the International Symposium on Combinatorial Search*, vol. 16, 2023, pp. 198–199.

[5] E. Saccon, L. Palopoli, and M. Roveri, "Comparing multi-agent path finding algorithms in a real industrial scenario," in *AIxIA 2022–Advances in Artificial Intelligence: XXIst International Conference of the Italian Association for Artificial Intelligence, AIxIA 2022, Udine, Italy, November 28–December 2, 2022, Proceedings*. 2023, pp. 184–197. DOI: `10.1007/978-3-031-27181-6_13`.

[6] E. Saccon, P. Bevilacqua, D. Fontanelli, M. Frego, L. Palopoli, and R. Passerone, "Robot Motion Planning: can GPUs be a Game Changer?" *2021 IEEE 45th Annual Computers, Software, and Applications Conference (COMPSAC)*, pp. 21–30, 2021. DOI: `10.1109/COMPSAC51774.2021.00015`.

[7] M. Frego, P. Bevilacqua, E. Saccon, L. Palopoli, and D. Fontanelli, "An Iterative Dynamic Programming Approach to the Multipoint Markov-Dubins Problem," *IEEE Robotics and Automation Letters*, vol. 5, no. 2, pp. 2483–2490, 2020. DOI: `10.1109/LRA.2020.2972787`.

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