Project

In our previous works [1] we provide a comprehensive strategy for multi-robot navigation in environments shared with human beings. Some improvements can be implemented to the algorithm:

- the coordination between robot has to be improved. The robot intended motion should be incorporeted at the coordination level. In particular, new shapes for the density function $\varphi(q)$ can be explored e.g., learning techniques to synthesize the shape of $\varphi(q)$.
- other state-of-the-art local path planner can be implemented to improve performance.

[1] M. Boldrer, A. Antonucci, P. Bevilacqua, L. Palopoli, D. Fontanelli, Multi-agent navigation in human-shared environments: A safe and socially-aware approach, Robotics and Autonomous Systems