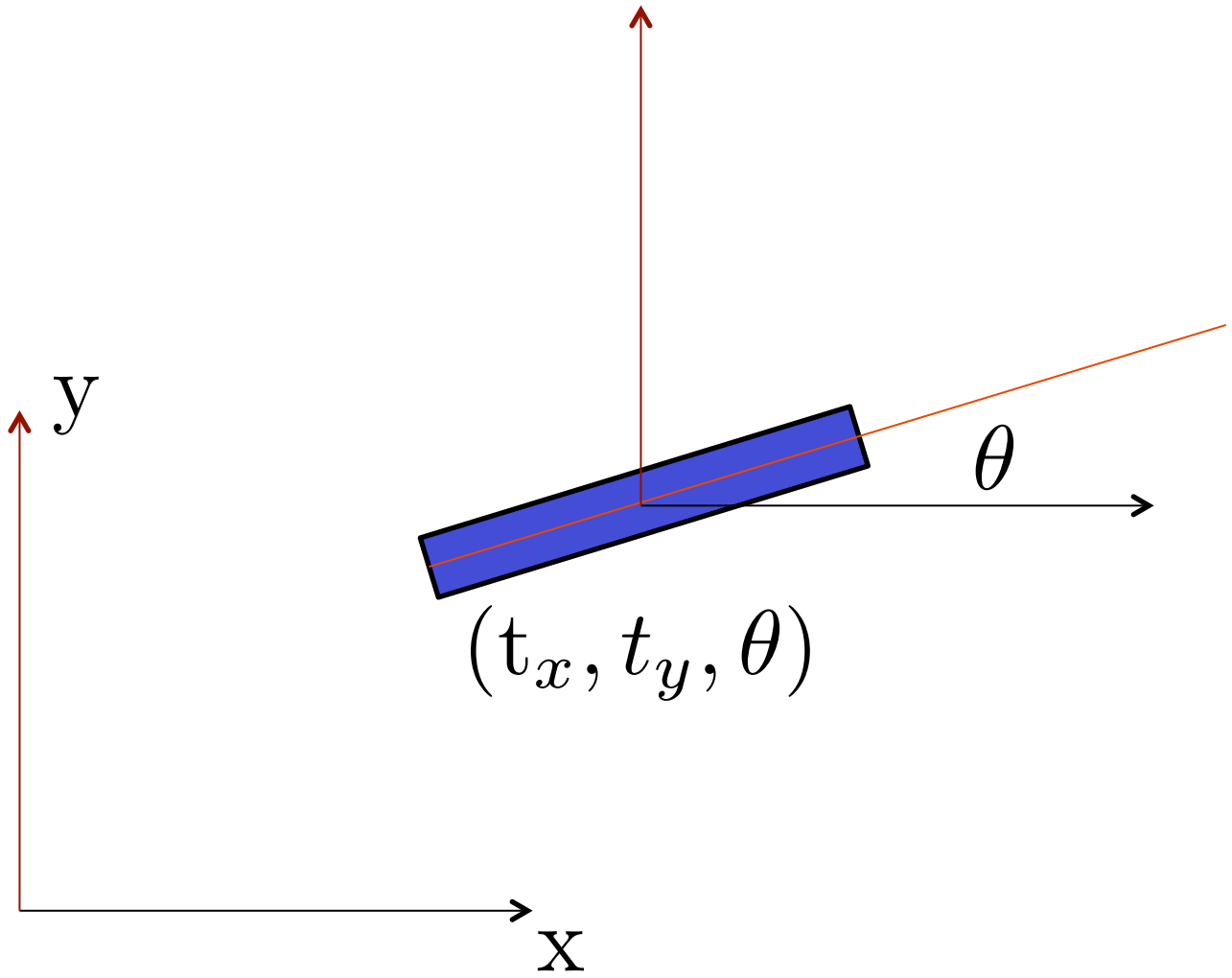
Piano Mover's problem

SECTION 2.3

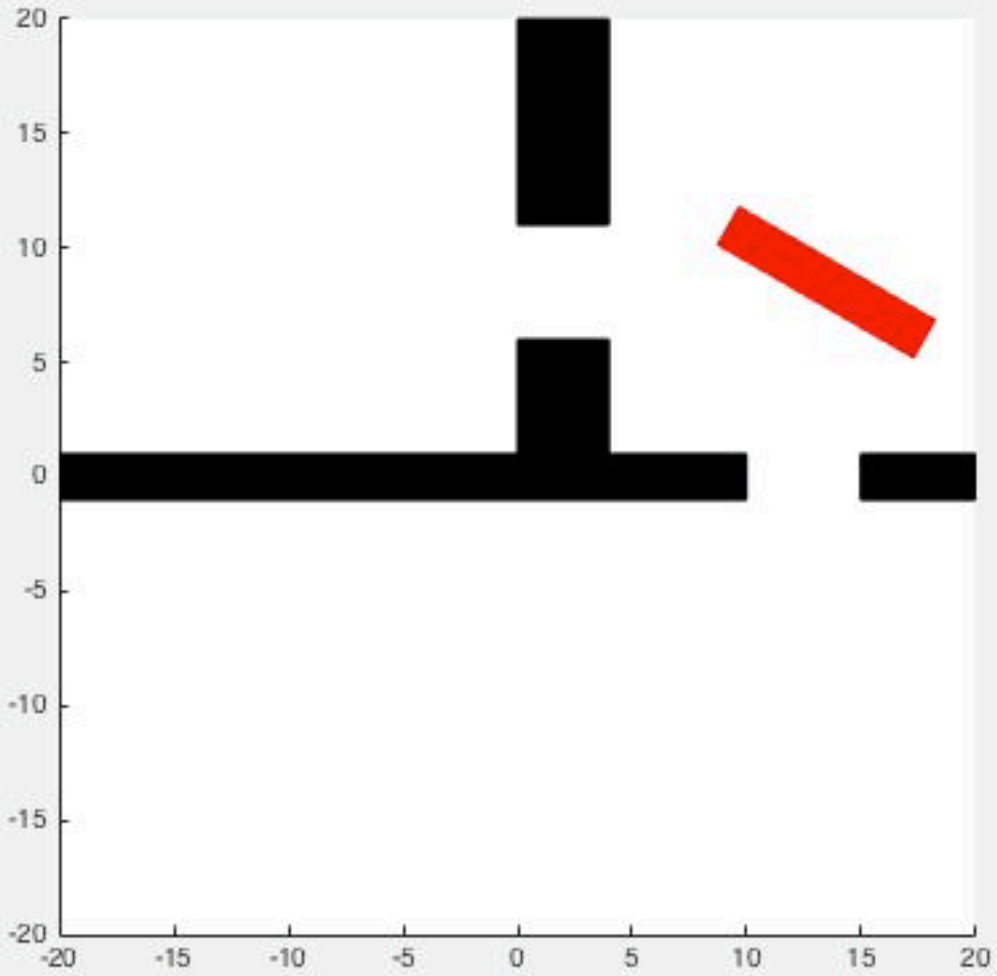
Penn

Translating and Rotating Robot

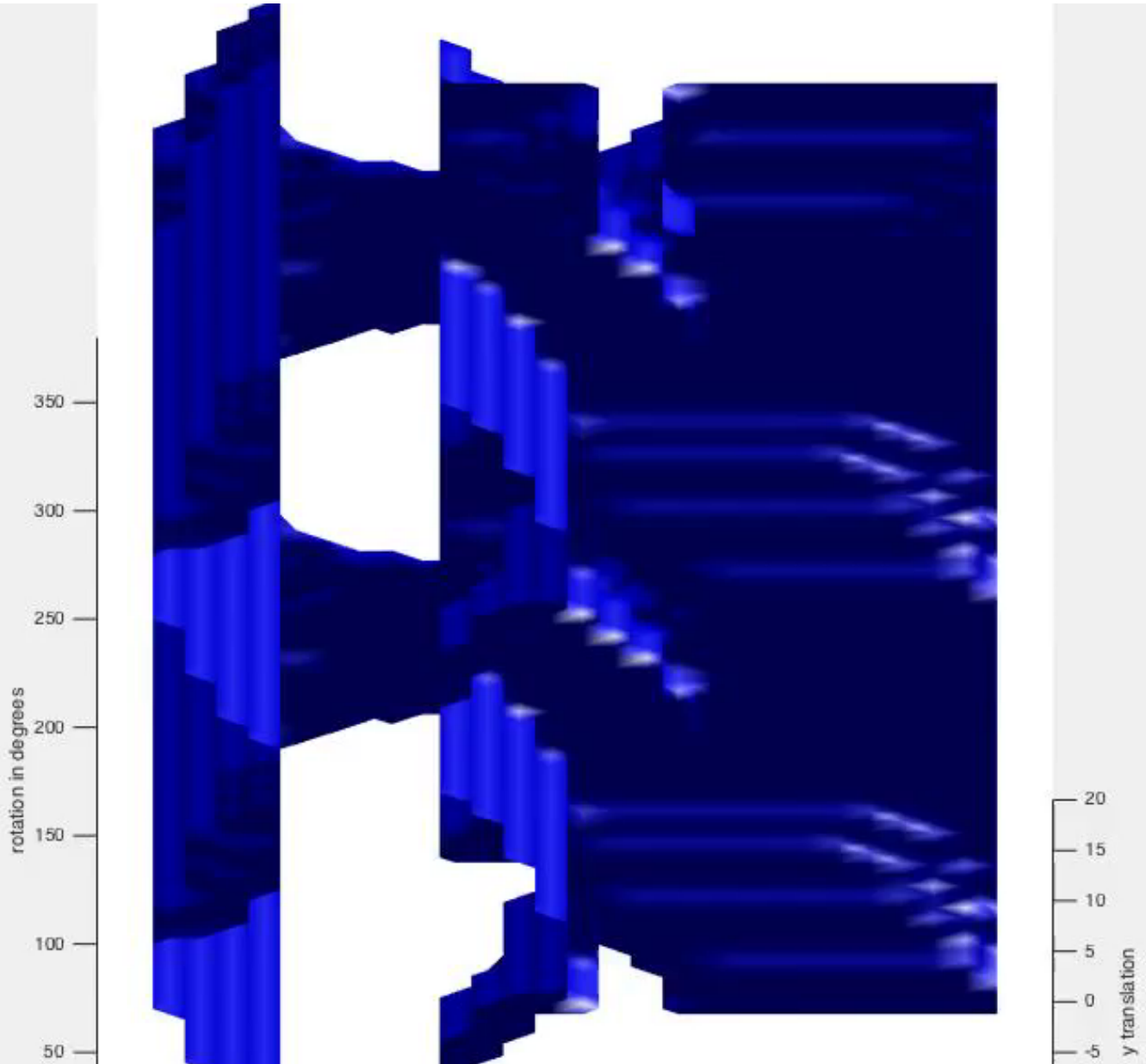


- **Once again when we introduce obstacles into the workspace we can think about the set of configurations that are eliminated. In this case the configuration space has 3 dimensions and the configuration space obstacles can be thought of as 3 dimensional regions in this space.**
- Except in this case the configuration space is 3D so visualization is a little more challenging.

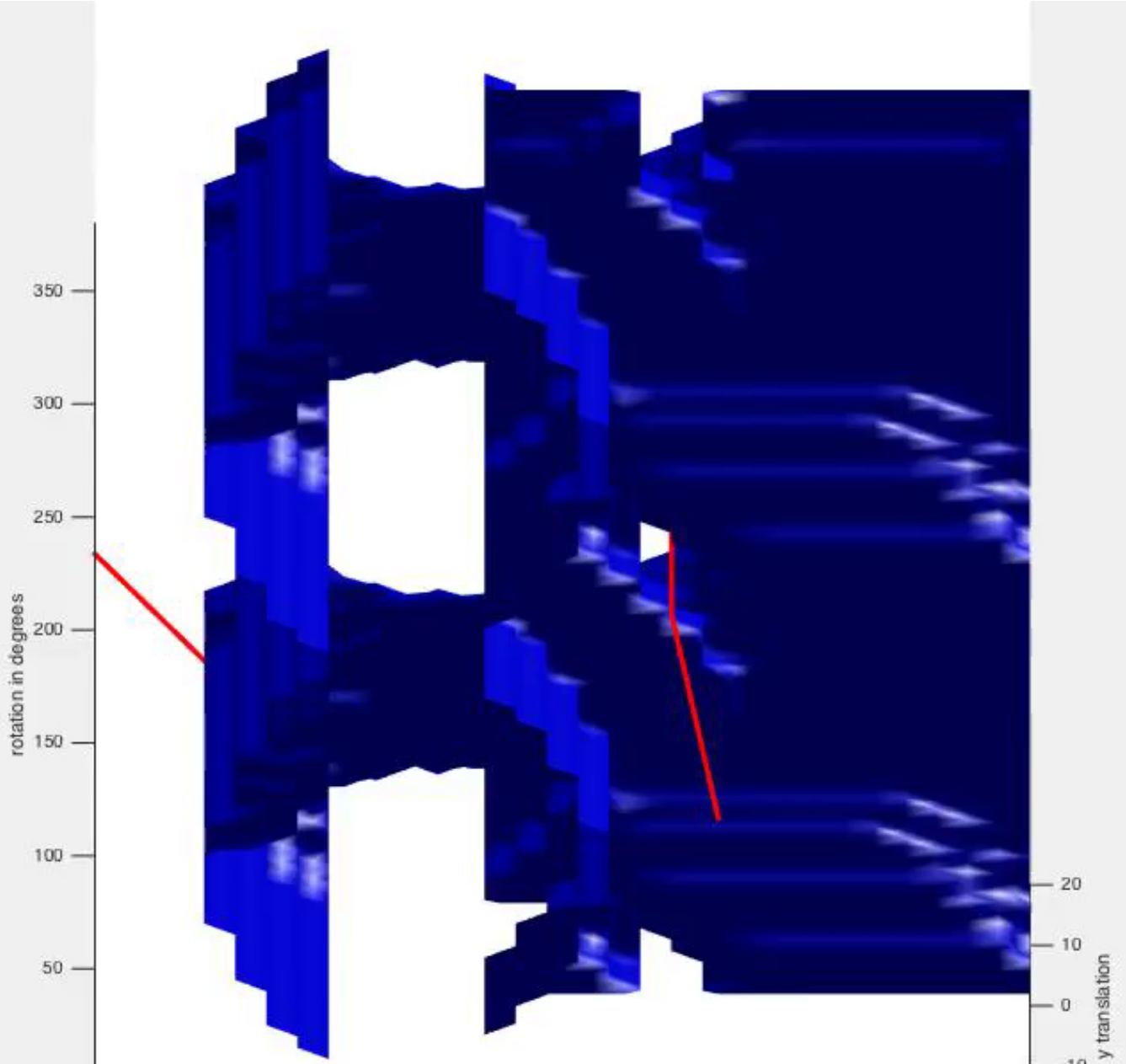
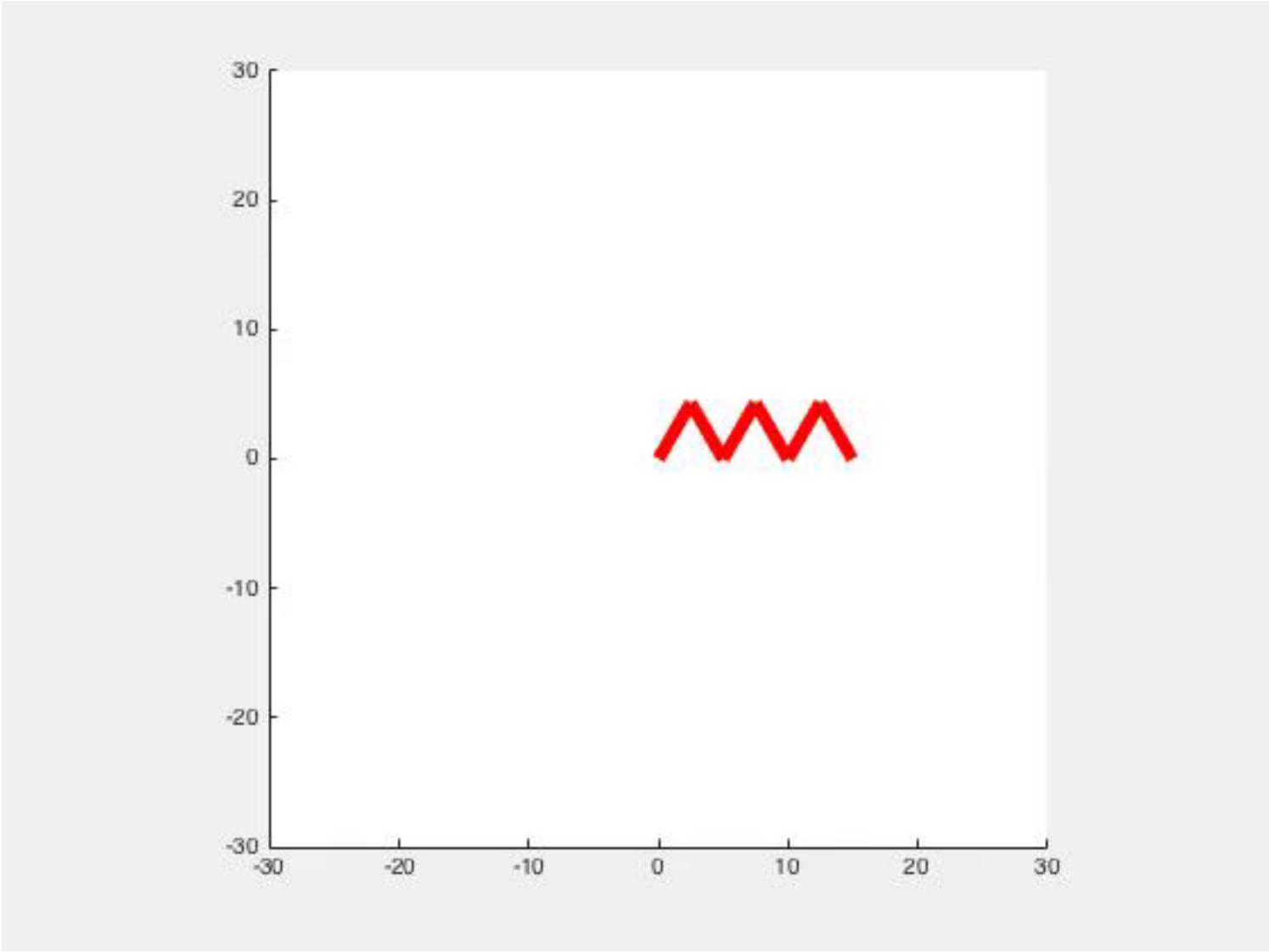
Rotation and Translation with Obstacles



Configuration Space Obstacle



Configuration Space Trajectory



Six Link Planar Robot