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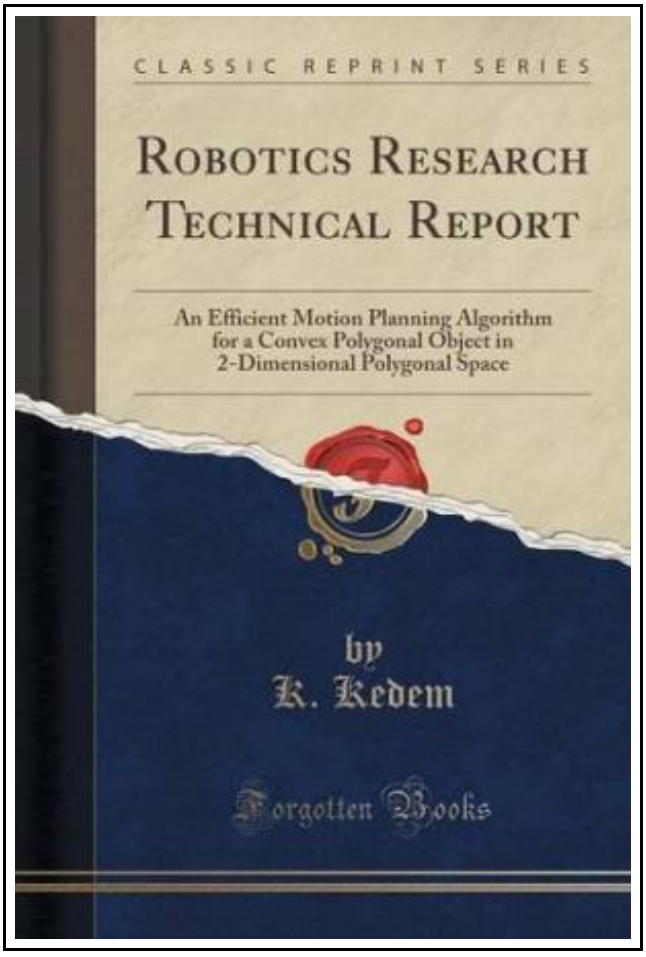

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Forgotten Books, United States, 2015. Paperback. Book Condition: New. 229 x 152 mm. Language: English . Brand New Book ***** Print on Demand *****.Excerpt from Robotics Research Technical Report: An Efficient Motion Planning Algorithm for a Convex Polygonal Object in 2-Dimensional Polygonal Space We present an efficient algorithm for planning the motion of a convex polygonal body B in two-dimensional space bounded by a collection of polygonal obstacles. Our algorithm extends and combines the techniques of Leven and Sharir and of Sifrony and Sharir used for the case in which B is a line segment (a ladder). It also makes use of the results of Kedem and Sharir on the planning of translational motion of B amidst polygonal obstacles, and of a recent result of Leven and Sharir on the number of free critical contacts of B with such polygonal obstacles. 1. Introduction. Let B be a convex polygonal object having k vertices and edges, free to move (translate and rotate) in an open two-dimensional space V bounded by a collection of polygonal obstacles(walls) having altogether n corners. The problem studied in this paper is to plan automatically a continuous obstacle avoiding motion of B between any two specified initial and final placements; cf. Fig. l.1. About the Publisher Forgotten Books publishes hundreds of thousands of rare and classic books. Find more at This book is a reproduction of an important historical work. Forgotten Books uses state-of-the-art technology to digitally reconstruct the work, preserving the original format whilst repairing imperfections present in the aged copy. In rare cases, an imperfection in the original, such as a blemish or missing page, may be replicated in our edition. We do, however, repair the vast majority of imperfections successfully; any imperfections that remain are intentionally left to preserve the state...

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