

Lecture 8

Given that we have a rule for C-obs
in a form given q , we can extend it
to $q \in C_{obs}$ or it $\notin C_{obs}$

How do we search "C-Specs"
for a curve connecting q_{init} & q_{goal}
Clarify exist. alg. into a few
approaches:

- 1) Roadmap based approaches
 - 2) Cell Decomposition
 - 3) Potential based
 - 4) Sampling based
- } ① Criticality based
② Sampling based.

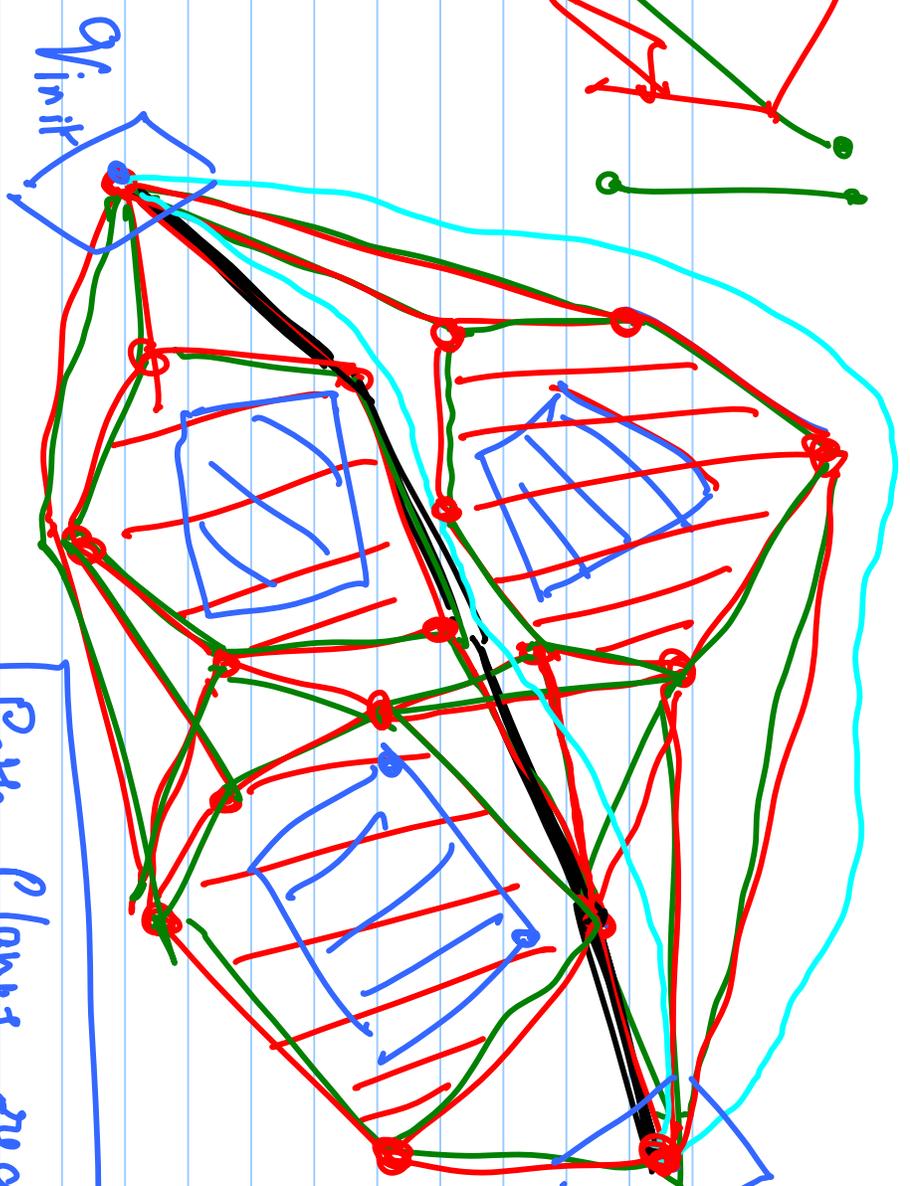
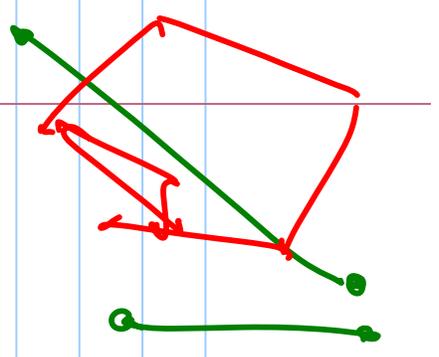
1) Roadmap based approach:
idea is to capture the connectivity of C_{free} in the form of a "network" of 1-dimensional curves lying in C_{free} . This "network" is called roadmap R . provides

a set of "street-oriented" paths. Path
Planning is reduced to "connecting" origin and
goals, unproblematically to R. and thereby the
roadmap.

Example: 2D polygonal (translation):

→ visibility graph in c-space
roadmap

efficiency issues for V-graph computation
I won't cover it. Read up



(V_{Graph} Alg)

"visibility"

"Graph"

Shortest path

$$R = G(V, E)$$

nodes of G

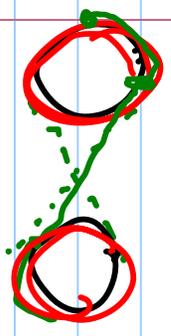
Cons edges

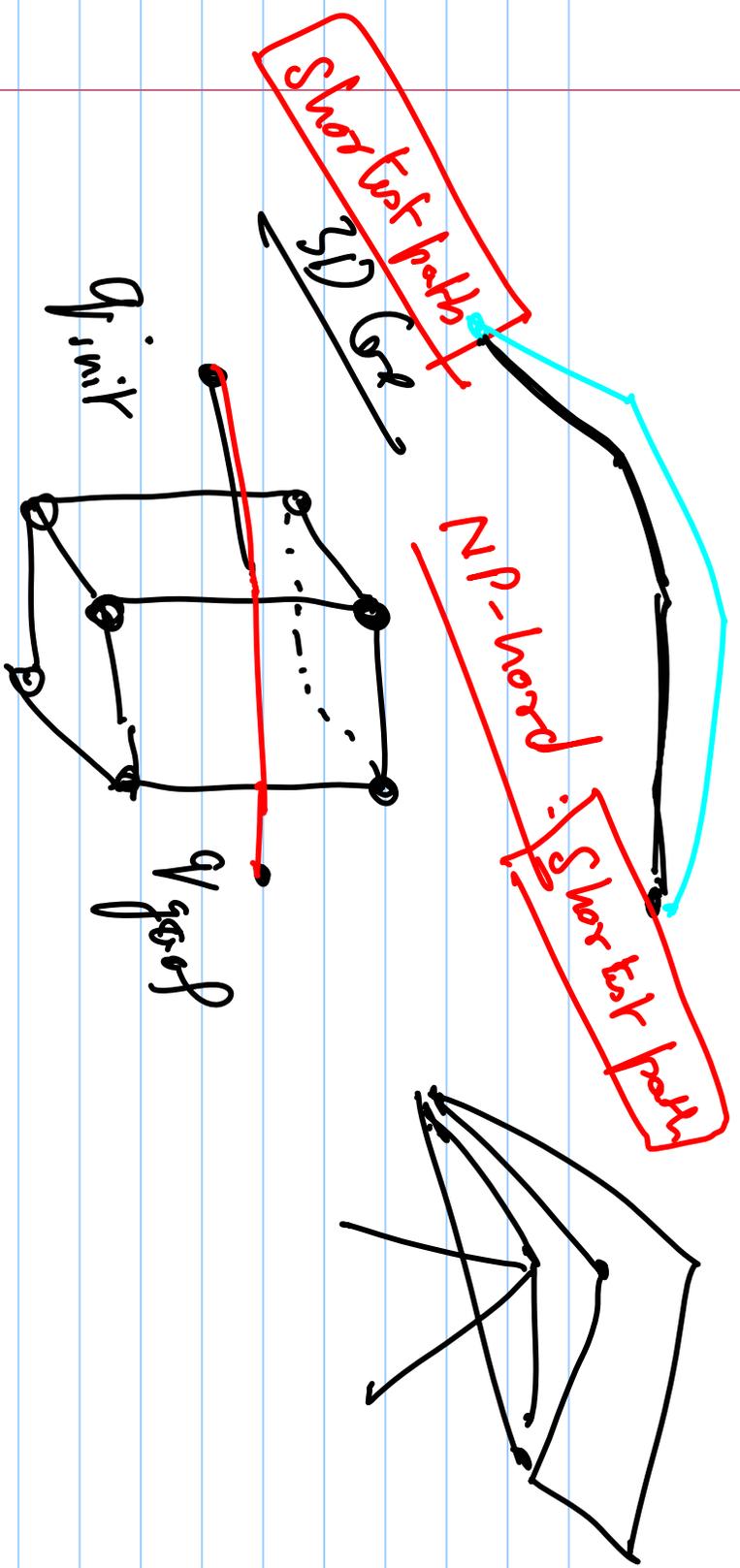
not con-

to "visibl"

nodes

Path Planning reduces
to Shortest paths
in a graph.





Hard part: how do you construct R ?

Tr 20: Voronoi diagram (used \times heavily for Voronoi Diag. illustration)

One can show $P: C_{free} \rightarrow \text{Vor}(C_{free})$ is a retraction.

clearance(q) what is $P: \text{supp } q \notin \text{Vor}(C_{free})$
= $\#$ dist. to
closest obs.

Closest to q : $\|q - p\| = \text{clearance}(q)$

the line segment L that connects p to q extended "away from" P , will intersect

$\text{Var}(\mathbb{K}_{\text{free}})$ in some pt, $\rho(q)$.
if $q \in \text{Vor}(\text{free})$, $\rho(q) = q$

}

We will skip some of the formal results
in this line, mainly theoretical interest,
we take from semi-alg. Geometry

Camy: 1987/88: "Sibulatte" method

→ Semi-algebraic sets: Polynomials
with rational
co-efn.

