

Contents

Preface	page xi
I Introductory Material	
1 Introduction	1
1.1 Planning to plan	3
1.2 Motivational examples and applications	4
1.3 Basic ingredients of planning	14
1.4 Algorithms, planners, and plans	16
1.5 Organization of the book	20
2 Discrete Planning	23
2.1 Introduction to discrete feasible planning	24
2.2 Searching for feasible plans	27
2.3 Discrete optimal planning	36
2.4 Using logic to formulate discrete planning	48
2.5 Logic-based planning methods	53
II Motion Planning	63
3 Geometric Representations and Transformations	66
3.1 Geometric modeling	66
3.2 Rigid-body transformations	76
3.3 Transforming kinematic chains of bodies	83
3.4 Transforming kinematic trees	93
3.5 Nonrigid transformations	99
4 The Configuration Space	105
4.1 Basic topological concepts	105
4.2 Defining the configuration space	120
4.3 Configuration space obstacles	129
4.4 Closed kinematic chains	139
5 Sampling-Based Motion Planning	153
5.1 Distance and volume in C-space	154
5.2 Sampling theory	161
5.3 Collision detection	173
5.4 Incremental sampling and searching	180

5.5	Rapidly exploring dense trees	189
5.6	Roadmap methods for multiple queries	196
6	Combinatorial Motion Planning	206
6.1	Introduction	206
6.2	Polygonal obstacle regions	208
6.3	Cell decompositions	218
6.4	Computational algebraic geometry	232
6.5	Complexity of motion planning	247
7	Extensions of Basic Motion Planning	257
7.1	Time-varying problems	257
7.2	Multiple robots	263
7.3	Mixing discrete and continuous spaces	270
7.4	Planning for closed kinematic chains	279
7.5	Folding problems in robotics and biology	287
7.6	Coverage planning	292
7.7	Optimal motion planning	295
8	Feedback Motion Planning	304
8.1	Motivation	304
8.2	Discrete state spaces	306
8.3	Vector fields and integral curves	314
8.4	Complete methods for continuous spaces	328
8.5	Sampling-based methods for continuous spaces	340
III	Decision-Theoretic Planning	357
9	Basic Decision Theory	360
9.1	Preliminary concepts	361
9.2	A game against nature	368
9.3	Two-player zero-sum games	378
9.4	Nonzero-sum games	386
9.5	Decision theory under scrutiny	393
10	Sequential Decision Theory	408
10.1	Introducing sequential games against nature	408
10.2	Algorithms for computing feedback plans	419
10.3	Infinite-horizon problems	430
10.4	Reinforcement learning	435
10.5	Sequential game theory	442
10.6	Continuous state spaces	455
11	Sensors and Information Spaces	462
11.1	Discrete state spaces	463
11.2	Derived information spaces	472
11.3	Examples for discrete state spaces	480

11.4	Continuous state spaces	487
11.5	Examples for continuous state spaces	494
11.6	Computing probabilistic information states	507
11.7	Information spaces in game theory	512
12	Planning Under Sensing Uncertainty	522
12.1	General methods	523
12.2	Localization	528
12.3	Environment uncertainty and mapping	540
12.4	Visibility-based pursuit-evasion	564
12.5	Manipulation planning with sensing uncertainty	570
IV	Planning Under Differential Constraints	587
13	Differential Models	590
13.1	Velocity constraints on the configuration space	590
13.2	Phase space representation of dynamical systems	606
13.3	Basic Newton-Euler mechanics	615
13.4	Advanced mechanics concepts	630
13.5	Multiple decision makers	645
14	Sampling-Based Planning Under Differential Constraints	651
14.1	Introduction	652
14.2	Reachability and completeness	660
14.3	Sampling-based motion planning revisited	670
14.4	Incremental sampling and searching methods	678
14.5	Feedback planning under differential constraints	693
14.6	Decoupled planning approaches	696
14.7	Gradient-based trajectory optimization	707
15	System Theory and Analytical Techniques	712
15.1	Basic system properties	712
15.2	Continuous-time dynamic programming	720
15.3	Optimal paths for some wheeled vehicles	728
15.4	Nonholonomic system theory	736
15.5	Steering methods for nonholonomic systems	753
	Bibliography	767
	Index	811