

Contents

| | |
|--|------------|
| Preface | ix |
| I Introductory Material | 1 |
| 1 Introduction | 3 |
| 1.1 Planning to Plan | 3 |
| 1.2 Motivational Examples and Applications | 5 |
| 1.3 Basic Ingredients of Planning | 17 |
| 1.4 Algorithms, Planners, and Plans | 19 |
| 1.5 Organization of the Book | 24 |
| 2 Discrete Planning | 27 |
| 2.1 Introduction to Discrete Feasible Planning | 28 |
| 2.2 Searching for Feasible Plans | 32 |
| 2.3 Discrete Optimal Planning | 43 |
| 2.4 Using Logic to Formulate Discrete Planning | 57 |
| 2.5 Logic-Based Planning Methods | 63 |
| II Motion Planning | 77 |
| 3 Geometric Representations and Transformations | 81 |
| 3.1 Geometric Modeling | 81 |
| 3.2 Rigid-Body Transformations | 92 |
| 3.3 Transforming Kinematic Chains of Bodies | 100 |
| 3.4 Transforming Kinematic Trees | 112 |
| 3.5 Nonrigid Transformations | 120 |
| 4 The Configuration Space | 127 |
| 4.1 Basic Topological Concepts | 127 |
| 4.2 Defining the Configuration Space | 145 |
| 4.3 Configuration Space Obstacles | 155 |
| 4.4 Closed Kinematic Chains | 167 |

| | |
|--|------------|
| 5 Sampling-Based Motion Planning | 185 |
| 5.1 Distance and Volume in C-Space | 186 |
| 5.2 Sampling Theory | 195 |
| 5.3 Collision Detection | 209 |
| 5.4 Incremental Sampling and Searching | 217 |
| 5.5 Rapidly Exploring Dense Trees | 228 |
| 5.6 Roadmap Methods for Multiple Queries | 237 |
| 6 Combinatorial Motion Planning | 249 |
| 6.1 Introduction | 249 |
| 6.2 Polygonal Obstacle Regions | 251 |
| 6.3 Cell Decompositions | 264 |
| 6.4 Computational Algebraic Geometry | 280 |
| 6.5 Complexity of Motion Planning | 298 |
| 7 Extensions of Basic Motion Planning | 311 |
| 7.1 Time-Varying Problems | 311 |
| 7.2 Multiple Robots | 318 |
| 7.3 Mixing Discrete and Continuous Spaces | 327 |
| 7.4 Planning for Closed Kinematic Chains | 337 |
| 7.5 Folding Problems in Robotics and Biology | 347 |
| 7.6 Coverage Planning | 354 |
| 7.7 Optimal Motion Planning | 357 |
| 8 Feedback Motion Planning | 369 |
| 8.1 Motivation | 369 |
| 8.2 Discrete State Spaces | 371 |
| 8.3 Vector Fields and Integral Curves | 381 |
| 8.4 Complete Methods for Continuous Spaces | 398 |
| 8.5 Sampling-Based Methods for Continuous Spaces | 412 |
| III Decision-Theoretic Planning | 433 |
| 9 Basic Decision Theory | 437 |
| 9.1 Preliminary Concepts | 438 |
| 9.2 A Game Against Nature | 446 |
| 9.3 Two-Player Zero-Sum Games | 459 |
| 9.4 Nonzero-Sum Games | 468 |
| 9.5 Decision Theory Under Scrutiny | 477 |
| 10 Sequential Decision Theory | 495 |
| 10.1 Introducing Sequential Games Against Nature | 496 |
| 10.2 Algorithms for Computing Feedback Plans | 508 |

| | |
|--|------------|
| 10.3 Infinite-Horizon Problems | 522 |
| 10.4 Reinforcement Learning | 527 |
| 10.5 Sequential Game Theory | 536 |
| 10.6 Continuous State Spaces | 551 |
| 11 Sensors and Information Spaces | 559 |
| 11.1 Discrete State Spaces | 561 |
| 11.2 Derived Information Spaces | 571 |
| 11.3 Examples for Discrete State Spaces | 581 |
| 11.4 Continuous State Spaces | 589 |
| 11.5 Examples for Continuous State Spaces | 598 |
| 11.6 Computing Probabilistic Information States | 614 |
| 11.7 Information Spaces in Game Theory | 619 |
| 12 Planning Under Sensing Uncertainty | 633 |
| 12.1 General Methods | 634 |
| 12.2 Localization | 640 |
| 12.3 Environment Uncertainty and Mapping | 655 |
| 12.4 Visibility-Based Pursuit-Evasion | 684 |
| 12.5 Manipulation Planning with Sensing Uncertainty | 691 |
| IV Planning Under Differential Constraints | 711 |
| 13 Differential Models | 715 |
| 13.1 Velocity Constraints on the Configuration Space | 716 |
| 13.2 Phase Space Representation of Dynamical Systems | 735 |
| 13.3 Basic Newton-Euler Mechanics | 745 |
| 13.4 Advanced Mechanics Concepts | 762 |
| 13.5 Multiple Decision Makers | 780 |
| 14 Sampling-Based Planning Under Differential Constraints | 787 |
| 14.1 Introduction | 788 |
| 14.2 Reachability and Completeness | 798 |
| 14.3 Sampling-Based Motion Planning Revisited | 810 |
| 14.4 Incremental Sampling and Searching Methods | 820 |
| 14.5 Feedback Planning Under Differential Constraints | 837 |
| 14.6 Decoupled Planning Approaches | 841 |
| 14.7 Gradient-Based Trajectory Optimization | 855 |
| 15 System Theory and Analytical Techniques | 861 |
| 15.1 Basic System Properties | 862 |
| 15.2 Continuous-Time Dynamic Programming | 870 |
| 15.3 Optimal Paths for Some Wheeled Vehicles | 880 |

| | |
|--|-----|
| 15.4 Nonholonomic System Theory | 888 |
| 15.5 Steering Methods for Nonholonomic Systems | 910 |