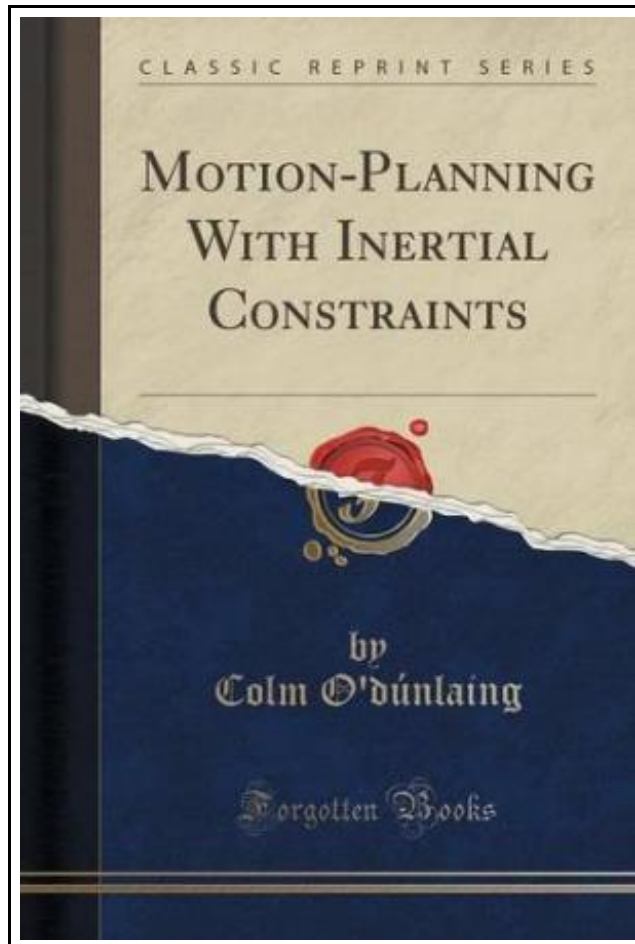


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Forgotten Books, United States, 2015. Paperback. Book Condition: New. 229 x 152 mm. Language: English . Brand New Book ***** Print on Demand *****.Excerpt from Motion-Planning With Inertial Constraints There has been much recent research into many motion-planning problems as computational problems, but there has been little work done on the problem of motion-planning in the presence of constraints on velocity or acceleration. The relevance of such studies is rendered plausible in the following scenario: an automated manufacturing system is in the process of design, and all the steps in the manufacture have been planned as a sequence of motions of various robots, feeder belts, and so forth, but the overall speed of assembly has yet to be planned. It is likely in certain instances that this overall speed be limited by the fragility of the parts under assembly; the speed of assembly, and consequently the throughput of the line, should be chosen to be as rapid as possible subject to limits on the inertial forces brought to bear on the parts being assembled. Therefore this paper addresses the motion-planning problem with inertial constraints, in the following simple case: To decide whether it is possible for the particle to follow a (space-time) path with boundary positions and velocities (X_a, V_a) and $(X_b, V_b,)$ at boundary times a and b , respectively, where the particle evades two pursuing particles, whose positions are given by functions $f(t)$ and $g(t)$ respectively, where f and g are parabolic splines, and the acceleration of the particle in question never exceeds a fixed bound M in absolute value. It is curious that, even for the simple case studied here, a satisfactory solution to the constrained problem remains nontrivial. This paper provides two alternative solutions to the above problem: one with a runtime of $O(n)$ and...



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