



## CONTENTS

<b>HALAMAN PENGESAHAN</b>	<b>ii</b>
<b>PREFACE</b>	<b>iii</b>
<b>CONTENTS</b>	<b>vii</b>
<b>LIST OF FIGURES</b>	<b>x</b>
<b>LIST OF TABLES</b>	<b>xii</b>
<b>Abstract</b>	<b>xiii</b>
<b><i>Intisari</i></b>	<b>xiv</b>
<b>I INTRODUCTION</b>	<b>1</b>
1.1 Research Motivation . . . . .	1
1.2 Problem Statement . . . . .	4
1.3 Thesis Organization . . . . .	5
<b>II ROBOT PATH PLANNING</b>	<b>6</b>
2.1 Classification of Path Planning . . . . .	6
2.2 The State of The Art in Robot Path Planning . . . . .	9
2.3 Formation Control State of Art . . . . .	10
<b>III ARRIVAL TIME FIELD</b>	<b>13</b>
3.1 Intuitive Introduction to Arrival Time Field . . . . .	13
3.2 Mathematical Formulation . . . . .	14
3.3 Fast Marching Method . . . . .	15



<b>IV PATH PLANNING STRATEGY</b>	<b>16</b>
4.1 Arrival Time Field for Robot Path Planning . . . . .	16
4.2 Gradient Descent Method for Backtracking Optimum Path . . . . .	17
4.3 Path Planning Algorithm . . . . .	18
4.3.1 Arrival Time Field with Uniform speed . . . . .	19
4.3.2 Arrival Time Field with speed Function . . . . .	19
4.3.3 Arrival Time Field with Safe-distance Thresholded Speed Func- tion . . . . .	20
4.4 Numerical Experiment . . . . .	22
4.4.1 Normal Terrain . . . . .	22
4.4.2 Narrow Passage . . . . .	28
4.4.3 Labyrinth . . . . .	31
4.4.4 Arbitrary Shape Obstacle . . . . .	36
4.4.5 Simulation on Quradrotor UAV . . . . .	39
<b>V FORMATION CONTROL STRATEGY</b>	<b>41</b>
5.1 Introduction to Formation Control . . . . .	41
5.2 Multi-agent System . . . . .	42
5.2.1 General Formation Control Strategy . . . . .	42
5.2.2 Formation Control via Potential Field . . . . .	44
5.3 Proposed Formation Control Strategy . . . . .	48
5.3.1 Hybrid Leader Follower and Behavioral Approach . . . . .	48
5.4 Numerical Experiment . . . . .	53
5.4.1 Simulation on Quradrotor UAV . . . . .	53
<b>VI CONCLUSIONS AND FUTURE WORKS</b>	<b>55</b>
6.1 Conclusions . . . . .	55



6.2 Future Works . . . . .	56
<b>REFERENCES</b>	<b>57</b>