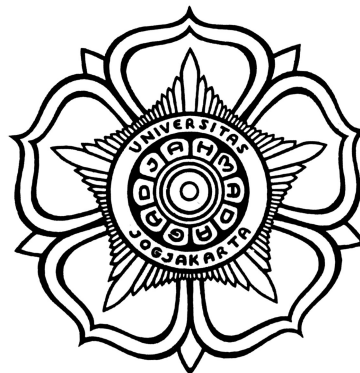


NON-HOLONOMIC ROBOT PATH PLANNING BASED ON ARTIFICIAL POTENTIAL FIELD

Dissertation



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