

**VISUAL NAVIGATION: FROM BIOLOGICAL SYSTEMS
TO UNMANNED GROUND VEHICLES (COMPUTER VISION
SERIES)**

Leigh Divens

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Keywords: Motion and Path Planning Abstract: The paper proposes a path planning algorithm for cluttered environment and maze. The effectiveness of the approach has been proven in a manipulation task, where the adaptive task structure is able to generalize to unseen object locations.

The position involves designing and implementing Computer Vision and Machine Learning. In particular, for the first time a cooperative manipulation task between a ground industrial manipulator and an aerial manipulator has been robustly demonstrated.

Our experiments demonstrate that the proposed method is efficient in location enable a car to travel without any driver embedded within the vehicle, some companies use a remote driver.

