
TRAJECTORY CONTROL OF THE UNMANNED VEHICLE BY DANAMIC WINDOW METHOD

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Abstract

This paper describes a method for trajectory control of the unmanned vehicle motion by using a dynamic window. A special feature of this method is the determination of the realized trajectories group out of many possible trajectories by imposing certain restrictions, and the subsequent selection of the optimal trajectory. We carried out a test using the model of the car in environment "Stage" and analysed the results

Keywords

Unmanned vehicle, automatic control system, model, modeling, trajectory motion

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