



## **Advances in Mobile Robot Navigation in an Unstructured and Dynamically Cluttered Environment**

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### **Message from the Guest Editors**

In the last few decades, researchers in the robotics field have conducted many investigations on using robots within human–robot coexistent environments to perform complex works such as surveillance, rescue, transportation, and working in underground mines. Due to this fast growth in robots' utilization, the challenge of mobile robots' navigation in unstructured dynamic environments has become a field of interest to many researchers around the globe.

This Special Issue aims to discuss state-of-the-art algorithms and methodologies addressing the challenges facing researchers in the various fields and applications of modern mobile robots' navigation. Those field can be related but not limited to:

- Obstacle tracking and path prediction;
- Optimal path planning;
- Obstacle tracking and path prediction;
- Collision-free and safe motions;
- Manoeuvrability in a high-density dynamic environment.





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## Message from the Editor-in-Chief

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Our aim is to encourage scientists to publish their experimental and theoretical results in as much detail as possible. There is no restriction on the length of the papers. Full experimental and/or methodical details must be provided.

There are, in addition, unique features of this journal: Manuscripts regarding research proposals and research ideas will be particularly welcomed; Electronic files or software regarding the full details of the calculation and experimental procedure - if unable to be published in a normal way can be deposited as supplementary material.

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