

# PUBLICATIONS

The chapters of this thesis are based on the following papers:

## Chapter 2

R. Geraerts and M.H. Overmars. A comparative study of probabilistic roadmap planners. In *Workshop on the Algorithmic Foundations of Robotics*, pages 43–57, 2002.

R. Geraerts and M.H. Overmars. Sampling techniques for probabilistic roadmap planners. In *Conference on Intelligent Autonomous Systems*, pages 600–609, 2004.

R. Geraerts and M.H. Overmars. Sampling and node adding in probabilistic roadmap planners. *Journal of Robotics and Autonomous Systems*, 54:165–173, 2006.

## Chapter 3

R. Geraerts and M.H. Overmars. Reachability analysis of sampling based planners. In *IEEE International Conference on Robotics and Automation*, pages 406–412, 2005.

R. Geraerts and M.H. Overmars. On the analysis and success of sampling based motion planning. In *Conference of the Advanced School for Computing and Imaging*, pages 313–319, 2005.

## Chapter 4

R. Geraerts and M.H. Overmars. Clearance based path optimization for motion planning. In *IEEE International Conference on Robotics and Automation*, pages 2386–2392, 2004.

R. Geraerts and M.H. Overmars. On improving the path quality for motion planning. In *Conference of the Advanced School for Computing and Imaging*, pages 211–217, 2004.

R. Geraerts and M.H. Overmars. On improving the clearance for robots in high-dimensional configuration spaces. In *IEEE/RSJ International Conference on Intelligent Robots and Systems*, pages 4074–4079, 2005.

## **Chapter 5**

R. Geraerts and M.H. Overmars. Clearance based path optimization for motion planning. In *IEEE International Conference on Robotics and Automation*, pages 2386–2392, 2004.

R. Geraerts and M.H. Overmars. On improving the path quality for motion planning. In *Conference of the Advanced School for Computing and Imaging*, pages 211–217, 2004.

## **Chapter 6**

R. Geraerts and M.H. Overmars. Creating small roadmaps for solving motion planning problems. In *IEEE International Conference on Methods and Models in Automation and Robotics*, pages 531–536, 2005.

## **Chapter 7**

R. Geraerts and M.H. Overmars. Creating high-quality roadmaps for motion planning in virtual environments. Submitted to *IEEE/RSJ International Conference on Intelligent Robots and Systems*, 2006.