Abstract

This paper denotes a survey on formation control of multi-mobile robot systems which drawn significant attention for the last years. It is concentrated on the stability of multi mobile robots when they obtained the required formation. Also this paper discusses the approaches of formation control and applications of them in changing and remote environments. Two classifications for the formation control methods are surveyed in this paper: the formation control strategies and the formation control stability. The differences among the surveyed approaches are discussed and the results are summarized.

References

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