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A quick intelligent control system for a mobile robot to avoid collision with moving obstacles

Published online: 25 October 2005
© Springer-Verlag 2005

Microsyst Technol (2005) 11:569–576

Due to an unfortunate error, Eq. 9 was published incorrectly. The corrected version is shown below:

$$|\mathbf{P}_{o2}\mathbf{P}| = \frac{|\mathbf{P}_r\mathbf{P}_o(0)| \cdot \sin \theta_{ro2}}{\sin \beta} + \frac{\varepsilon_1}{\sin \beta} + L_o - \frac{\varepsilon_2}{\tan \beta} \quad (9)$$

In the unnumbered equation between Eqs. 12 and 13
> should be <, see below:

$$\sin(\beta - \theta_{ro2}) < \frac{|\mathbf{V}_r(0)|}{|\mathbf{V}_o(0)|} \sin \theta_{ro2},$$

The online version of the original article can be found <http://dx.doi.org/10.1007/s00542-005-0556-y>

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