

Contents

Preface	v
1 Autonomous robots, motion algorithms and topology	1
<i>by Michael Farber</i>	
1 Robots and their configuration spaces	1
2 Autonomous robots and motion planning algorithms	3
3 The concept of topological complexity	6
4 The role of cohomology algebras	7
5 Topological complexity of spheres	8
6 Some further examples and computations	9
7 Sequential motion planning algorithms and sequential topological complexity	11
8 The rationality conjecture	13
9 Configuration spaces of external conditions and parametrized motion algorithms	16
10 Controlling multiple collision-free robots in the presence of multiple obstacles in the Euclidean space	18
11 Sequential parametrized motion algorithm for many robots and obstacles in \mathbb{R}^d ; the even-dimensional case	20
References	27
2 Equivalent environments and covering spaces for robots	31
<i>by Vadim K. Weinstein and Steven M. LaValle</i>	
1 Introduction	31
2 Closing the loop via sensing and filtering	34
3 Basic models and theory development	37
4 History information spaces	45
5 Indistinguishability of environments	46
6 Homomorphisms and covering spaces	51
7 Equivalence characterization and bisimulation	56
8 Bringing it all together	57
9 Conclusion	61
References	62
3 Some geometric and topological data-driven methods in robot motion path planning	65
<i>by Boris Goldfarb</i>	
1 Introduction	65
2 Panorama of topological methods in robot motion planning	66

3	Discrete Morse theory methods	70
4	Applications of discrete Morse theory	75
5	A collection of problems	82
	References	86
4	Towards control, learning and intelligence in reconfigurable systems	91
	<i>by Dan P. Guralnik</i>	
1	Introduction	91
2	Reconfigurable systems and non-positively curved cube complexes	97
3	Navigation	104
4	Learning the cubical structure of a set of Boolean queries	112
5	Learning a cubing with arbitrary sensors: Some results	116
	References	120
5	Geometric and topological properties of manifolds in robot motion planning	123
	<i>by Stephan Mescher</i>	
1	Introduction	123
2	Topological complexity of manifolds	125
3	Length-minimizing motion planning in Riemannian manifolds	138
4	Critical point theory and sectional category	146
	References	155
6	Equivariant topological complexities	161
	<i>by Mark Grant</i>	
1	Introduction	161
2	Group actions	164
3	Equivariant topological complexity	167
4	Invariant topological complexity	170
5	Strongly equivariant topological complexity	176
6	Effective topological complexity	179
7	Problems	183
	References	184
7	Computing with the TC-canonical class	187
	<i>by Lucile Vandembroucq</i>	
1	Introduction	187
2	TC-canonical class	188
3	Computing with the bar resolution – a first example	194
4	Klein bottle and related manifolds	198
5	Manifolds with abelian fundamental group	205
	References	209

8 Motion planning in real projective spaces	211
<i>by Jesús González</i>	
1 Introduction	211
2 Sectional category and fiberwise joins	212
3 Projective spaces and level of sphere bundles	219
4 Topological complexity and projective spaces	224
5 Symmetric topological complexity of real projective spaces	226
6 Proof of Theorems 1.3.1 (ii) and 1.4.4	231
7 Concluding remarks: Symmetrized topological complexity	236
References	237
9 Generalized topological complexity and its monoidal version	241
<i>by José Manuel García-Calcines</i>	
1 Introduction	241
2 Preliminaries: Srinivasan's tools and generalized LS category	242
3 Generalized topological complexity	246
4 Generalized monoidal topological complexity	256
References	262
10 Robotics and the fundamental group	265
<i>by John Oprea</i>	
1 Introduction	265
2 Families of subgroups	273
3 Lower bounds for $\text{TC}_r(\pi)$ via Bredon cohomology	280
4 Topological complexity for groups with cyclic centralizers	282
References	288
11 Geodesic complexity	291
<i>by Donald M. Davis</i>	
1 Introduction	291
2 Two robots moving on a star graph	295
3 Geodesic complexity of a cube	301
References	307
12 Farber's conjecture and beyond	309
<i>by Ben Knudsen</i>	
1 Introduction	309
2 Decomposable tori	312
3 Configuration spaces	316
4 Detection	321
5 Open problems	329
References	331

13	Topological complexity of a map	335
	<i>by Petar Pavešić</i>	
1	Introduction	335
2	Sectional number and sectional category	336
3	Strict topological complexity relative to a map	341
4	Homotopy invariant topological complexities of a map	348
5	Applications	355
6	Concluding remarks	360
	References	361
14	Distributional topological complexity and LS-category	363
	<i>by Alexander Dranishnikov and Ekansh Jauhari</i>	
1	Introduction	363
2	Classical numerical invariants	365
3	New numerical invariants	367
4	Lower bounds	371
5	Ganea–Schwarz’s characterization of dcat and dTC	376
6	Some computations	378
7	Epilogue	383
	References	384
	List of contributors	387