WORLD COMET RESEARCH GROUP

International Journal of Intelligent Automation & Robotics Engineering
Vol. 3, No. 1, 2020
Doi: 10.67228/30715725/IJIARE-2020PI7Q4W
PP. 01-14

Original Article

AI-Based Adaptive Motion Planning for Autonomous Robotic Systems

Michael Anderson

Director of Information Technology, ABC Technologies Inc. USA.

Received: 03-06-2020 Revised: 03-20-2020 Accepted: 03-30-2020 Published: 04-04-2020

ABSTRACT

Autonomous robotic systems are transforming industries such as automation, healthcare, transportation, defense, and intelligent services. A major challenge in robotics is motion planning in dynamic and uncertain environments, where robots must navigate safely and efficiently. Traditional algorithms like Dijkstra's, A, Probabilistic Road Maps, and Rapidly Exploring Random Trees perform well in static environments but struggle with moving obstacles, sensor uncertainty, and real-time decision-making. Artificial Intelligence (AI) has improved robotic motion planning through adaptive learning, predictive decision-making, reinforcement learning, fuzzy logic, neural networks, and evolutionary optimization. These techniques enable robots to learn from their environment and optimize navigation over time. This paper reviews AI-based adaptive motion planning methods developed before 2019 and examines their role in path optimization, obstacle avoidance, localization, and decision-making. It also proposes a hybrid framework combining sensor fusion, environment mapping, fuzzy inference systems, and reinforcement learning for real-time path optimization. Simulation results demonstrate that AI-based adaptive planning achieves better navigation accuracy, obstacle avoidance, computational efficiency, and environmental adaptability compared to traditional methods.*

KEYWORDS

Artificial Intelligence, Autonomous Robots, Motion Planning, Reinforcement Learning, Fuzzy Logic, Path Optimization, Robotics.

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ISSN: 3071-5725
PP: 01-14.

1. INTRODUCTION

1.1. Background

With the increasing demand for intelligent machines that can function with limited human intervention, robotic autonomy has become one of the most significant contemporary engineering research fields. Today, autonomous robots are finding applications in areas like manufacturing, medical care, farming, transportation, defense, and space exploration in areas that require them to execute complex jobs in dynamic and uncertain environments. A key aspect of autonomy is a robot's ability to safely and efficiently navigate within its environment. The ability to do this is implemented in motion planning, a fundamental part of the autonomous behaviour of a robot. Motion planning is the method by which a robot can choose an optimal path through a space from a given start point to a specified end point while avoiding features like obstacles, optimising the path, minimising energy usage and dealing with uncertainty in the environment. With the growing application of robots in various fields, the development of intelligent and adaptive motion planning techniques is a necessary way to enhance the reliability, safety and overall performance of autonomous robots.

1.2. Importance of AI-Based Adaptive Motion Planning

Adaptive motion planning for autonomous robotic systems is a highly significant technique in the development of modern autonomous robotic systems. While traditional motion planning algorithms are effective in static and predictable environments, they may not be suitable for robots in dynamic environments that are uncertain or complex. Incorporating elements of Artificial Intelligence enables robots to be able to perceive their environment, learn from their experiences, and make real-time intelligent navigation decisions. This makes the performance of robotic systems more efficient, safer and autonomous. The significance of adaptive motion planning using AI can be explained as follows:

Fig 1 - Importance of AI-Based Adaptive Motion Planning

1.2.1. Intelligent Decision-Making

By using AI, robots can access environmental data from sensors and make decisions based on the current state of the environment. The robot does not have to follow a specific set of rules, but

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instead can assess several options for navigation and choose the most appropriate one. This helps in more precise navigation and enables the robot to cope with unforeseen conditions better.

1.2.2. Real-Time Adaptability

Often in real-world situations, obstacles will appear out of nowhere, and paths might become blocked and the environment might change rapidly. Robots can adapt their navigation strategies in real time using AI-based adaptive motion planning, adapting their actions to dynamic environments like this as soon as it occurs. This adaptability guarantees trouble-free execution even in unpredictable or changing conditions.

1.2.3. Improved Obstacle Avoidance

Neural networks, fuzzy logic, and reinforcement learning are techniques used in AI that improve the robot's obstacle avoidance, classification, and detection capabilities. Previous experience and feedback from the sensors will enable the robot to navigate more safely, and to minimise the risk of it colliding in motion.

1.2.4. Learning from Experience

Adaptive learning methods allow for robots to learn and adapt over time. The robot interacts with the environment over and over again, and gradually learns which actions yield positive outcomes and how to navigate the environment most optimally. The self-learning feature improves the efficiency and reliability of its long-term performance.

1.2.5. Enhanced Application Potential

The applications of autonomous robots using AI-based motion planning include, but are not limited to, industrial automation, healthcare support, and logistics in warehouses, autonomous driving, agriculture, and disaster response. Robotic systems have intelligent and adaptive decisionmaking capabilities that enable them to perform in more complex environments.

1.3. Autonomous Robotic Systems

Autonomous robotic systems are intelligent machines which can accomplish tasks autonomously, either with only a little or without human control. These systems involve mechanical structures, electronic components, sensing technology, control systems and computational intelligence that interact and communicate with the environment while making decisions in real time. The primary goal of the autonomous robots is to successfully and safely finish the assigned tasks within an acceptable time frame with an acceptable level of accuracy while adapting to the changing environmental conditions. In contrast to the conventional robots which are programmed with a fixed set of instructions or programmed movement paths, autonomous robots can sense the environment, analyze the data, and choose the right behavior in response to the environment. This capability is very useful in situations where there is not a continuous human on-site. The components of an autonomous robotic system are generally divided into several parts: sensors, processors, control units, actuators and intelligent decision making modules. Real-time data is gathered from sensors like cameras, LiDAR, ultrasonic sensors, and infrared detectors to identify obstacles, measure

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distances, pinpoint positions of objects and environmental elements. Onboard computing systems receive this sensory information and algorithms process this data with a decision of what to do to navigate or execute the task accordingly. These decisions are then translated into motion commands by the control system and passed on to actuators like motors or joints of the robot. In this way, autonomous robots can perform in a complex and dynamic environment with the help of the integration of perception, computation, and action. The use of autonomous robotic systems in various industries is widespread due to their potential benefits in terms of productivity, precision, and safety. In industry, they are involved in assembly, inspection and material handling. Their use in healthcare includes helping with operations, patient monitoring, and medication distribution. They have applications in agriculture for crop monitoring, harvesting, and field analysis. The application of autonomous robots is also in transportation, defence, warehouse automation, deep sea exploration and space missions. Motion planning is one of the most critical functions of these systems, enabling the robot to navigate from one point to another, avoiding obstacles, and improving the efficiency of the movement. As AI, machine learning and sensor technology has evolved, autonomous robotic systems are becoming more intelligent, adaptive and able to solve more complex real world problems.

2. *LITERATURE SURVEY*

2.1. Classical Motion Planning Algorithms

Classical motion planning algorithms are the basic of autonomous robot navigation and have been extensively applied to mobile robotics, industrial automation, and autonomous vehicular systems. The algorithms here are concerned with locating the path that is either optimum/feasible from a start to a target, and avoiding obstacles in the environment. In dynamic settings, graph-based search methods like Edsger W. Dijkstra's Dijkstra algorithm work by systematically exploring all nodes, ensuring the shortest path, making them very trustworthy in a static environment. But when the search space grows, the complexity of the computation will increase accordingly. Likewise, the A* algorithm developed by Peter Hart and his colleagues is a more efficient algorithm that combines heuristic functions to help the search find a solution more quickly and reduce unnecessary exploration. High dimensional motion planning problems are also widely used with sampling-based methods such as Probabilistic Roadmaps (PRM) and Rapidly-exploring Random Trees (RRT). Unlike RRT, which randomly expands nodes to explore large search spaces quickly, PRM creates a roadmap of collision-free nodes that is suitable for complex spaces. Though these methods are effective, they can be challenging in dynamic environments where obstacles move and the environment is unpredictable, making it difficult to adapt in real-time.

2.2. AI-Based Motion Planning

AI based motion planning methods have enabled adapting and intelligent decision-making in robotic navigation systems. In contrast to the classic algorithms, which depend on pre-established models and rigid rules, AI approaches allow robots to learn from the data they obtain from their environment and adapt their movement strategies accordingly. The neural network, which mimics the structure of biological brains, has been used to obstacle recognition, path prediction, and

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environment classification. The networks can analyze the navigation patterns in real time using the visual, LiDAR and ultrasonic sensor data. Fuzzy logic systems have also been used extensively in motion planning, where they can use linguistic rules to deal with uncertain and imprecise information about the environment. The use of AI-driven techniques with learning capabilities and uncertainty handling greatly enhances the performance of the navigation system in unstructured and changing environments. However, these are often complex to implement with a large amount of training data.

2.3. Reinforcement Learning Applications

The field of Artificial Intelligence known as Reinforcement Learning (RL) has emerged as a crucial method for autonomous robots navigating their environments by trial and error, as this form of learning enables them to discover the best possible actions. RL allows an agent to learn navigation strategies by operating through the environment and receiving rewards for taking desirable actions and penalties for taking undesirable actions, like collision or moving inefficiently. The agent builds the policies which maximize the long-term rewards, which results in an efficient path planning and obstacle avoidance. RL has proven to be effective in mobile robots, warehouse automation systems, and autonomous vehicles, where dynamic decision-making is crucial. For tasks involving high dimensional sensor data and complex navigation, advanced RL techniques like Deep Q-Networks (DQN) and Policy Gradient methods have been developed that incorporate deep neural networks into RL. While RL offers great adaptability and self-learning abilities, the training procedure might be lengthy and, in the case of deployment, simulation environments may be needed.

2.4. Research Gap Analysis

While substantial advances have been achieved in motion planning using classical algorithms, techniques based on artificial intelligence and reinforcement learning, there are still some open research questions. Most classical planning methods work well in a stable and regular setting, but are not suitable in a dynamic and uncertain setting. AI-based solutions enhance perception and decision-making capabilities, but tend to be task-focused in their application (e.g., obstacle detection or path prediction), not necessarily fully integrated into navigation. Reinforcement learning methods offer adaptive behavior, but often they need large training datasets, require significant computational resources and can be slow to converge in real-world situations. Moreover, existing studies are mostly devoted to either perception-based navigation or learning-based control, but not to the combination of them into one framework. This poses a research challenge for designing an adaptive motion planning system with real-time environment perception, intelligent learning and efficient path optimization for reliable autonomous navigation in complex environments.

3. METHODOLOGY

3.1. System Architecture

The proposed autonomous robot navigation system is designed by a layered architecture which facilitates efficient perception, decision making, and motion execution. The process of the system starts with environmental sensing, generation of maps, intelligent decision making, planning the movement of the robot and lastly, making the robot move. All components are vital for safe and adaptive navigation in dynamic environments.

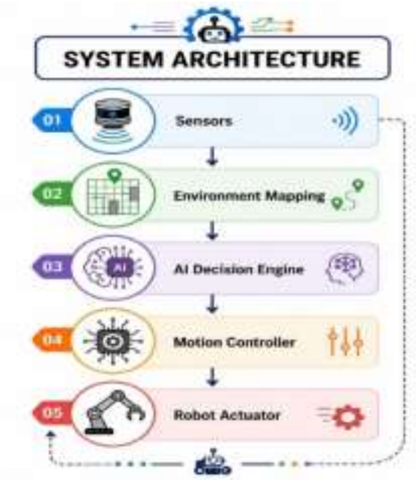

Fig 2 - System Architecture

3.1.1. Sensors

The sensors are the main input devices of the robotic system that can gather real-time information from the surrounding environment. Common methods for detecting an obstacle, measuring distance, and recording environmental features include using devices such as cameras, LiDAR sensors, ultrasonic sensors, and infrared sensors. These sensors continuously feed information about the robot's environment, allowing for real-time perception of changes. To ensure reliable navigation and collision avoidance, sensor data must be accurate.

3.1.2. Environment Mapping

Environment mapping refers to the process of taking raw data from the sensors to represent an environment in a structured format. The robot generates a grid map, occupancy map or feature map to detect free space, obstacles and potential navigation routes. This mapping process can help the robot determine its position with respect to the environment, and facilitate localization and path planning. Real-time mapping is particularly crucial in environments where conditions are not predictable or where they change often.

3.1.3. AI Decision Engine

The AI decision engine is the brain of the system that determines the navigation decisions when receiving the sensor information and when navigating the maps. The system can use AI techniques, including neural networks, fuzzy logic, or reinforcement learning, to make the best possible decision based on the surrounding environment. It decides upon safe and efficient pathways, and adjusts to dynamically changing obstacles or unexpected conditions. This component allows for the robot to react in an independent and intelligent manner.

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3.1.4. Motion Controller

The motion controller is responsible for converting the high-level navigation commands into the low-level control of the motion of the robot. It determines the parameters like speed, direction, turning angle and trajectory corrections to achieve smooth movement of the robot. The control algorithms are used to ensure that the robot follows the desired path with accuracy while keeping the robot stable and reducing the error. The motion controller provides an interface between the decision engine and the actual robot hardware.

3.1.5. Robot Actuator

The robot actuator is a device that executes the commands and translates them to action. The motion controller sends signals to actuators, like DC motors, servo motors or stepper motors, which power the robot's wheels, arms or joints. This enables the robot to move forward, turn, stop or carry out a task. Actuators are integral to the robot's functionality, influencing its speed, precision, and efficiency in overall navigation.

3.2. Mathematical Modeling of Robot Kinematics

Robot kinematics is a mathematical relationship between the motion of a robot and the robot's position in 2-Dimensional environment. During autonomous navigation, kinematic modelling is a crucial part of robot navigation, as it allows the prediction of robot motion from velocity and steering inputs. The 3 state variables that are typically used to represent the position of the robot are x, y, and theta – the orientation angle. X is the horizontal position of the robot, Y is the vertical position of the robot, and theta is the direction that the robot is facing. Two control inputs: linear velocity and angular velocity, dictate the motion of the robot. The linear velocity, v, is how fast the robot is moving forward and the angular velocity, omega, is how fast the robot is rotating/turning the direction it is heading. The velocity of the x position is equal to the linear velocity times the cos of theta. This implies that the distance traveled by the robot in the x direction will be a function of its speed and orientation. Likewise, the rate at which the y-position changes is equal to the linear velocity times the sine of theta which means that it is moving in the y direction. The rate of change of theta is the angular velocity, indicating the speed at which the robot rotates as it moves. A cost function is used to assess the quality of a planned path in order to optimise the movement of the robot. The total cost J is the sum of the path distance, the cost of the obstacle, and the path time (also called travel time), weighted by the number of units used of each cost. In this situation, d will be the total distance the robot has traveled, o the penalty for being close to the obstacles or unsafe areas, and t the total amount of time it took for the robot to arrive at the destination. The weightings alpha, beta and gamma indicate the significance of each of the parameters. This cost function can be used to minimize the cost of navigating the robot, allowing it to find the most efficient, safe, and time-saving route through complex environments.

3.3. Adaptive Learning Model

The model-free reinforcement learning method adopted in the autonomous robot navigation model is the Q-learning, which can realize the optimal navigation behavior of a robot by interacting

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with its environment. While traditional rule based systems require a knowledge of the environment, Q-learning will not. Rather, the robot slowly discovers which actions are the most effective through exploring various states and getting rewarded or punished. This learning process enables the robot to adjust to unpredictable dynamic or changing environments and enhances its decision making process over time. The robot is seen as an agent in Q-learning, interacting with the environment. The robot can see its current state – for example, position, obstacles in the vicinity and direction of the target. Based on this state, it chooses an action: move, turn left, turn right or stop. Once it has performed the action, the robot transitions to a new state and a reward signal is sent. Positive rewards are provided for desirable behavior, such as approaching the target or staying away from obstacles; negative rewards are provided for undesirable behaviors, such as colliding or moving ineffectively or away from the target. The Q-learning update equation is used to update the knowledge of the robot after every action. Q-values are the average future payoff to be received for a particular action in a particular state. The new Q value is the sum of the old Q value and the learning from the new experience. In this update, three crucial parameters come into play: the learning rate, the discount factor, and the maximum future reward. The learning rate is the amount of change that occurs to existing knowledge when new knowledge comes along. The discount factor represents how much importance is placed on future rewards vs. immediate rewards. The maximum future reward is the maximum reward that can be achieved at the next state. The robot learns an optimal policy for navigation by repeatedly exploring and updating Q-values. This adaptive learning process allows the robot to make intelligent decisions in path planning, avoid obstacles efficiently, and enhance the robot's performance in path planning in complex environments.

3.4. Proposed Flowchart

The proposed autonomous robot navigation system has a sequential design process which allows the robot to perceive the environment, make intelligent decisions, and navigate to the target safely. The flow chart's stages make a contribution to the general navigation performance and provide adaptability in dynamic environments.

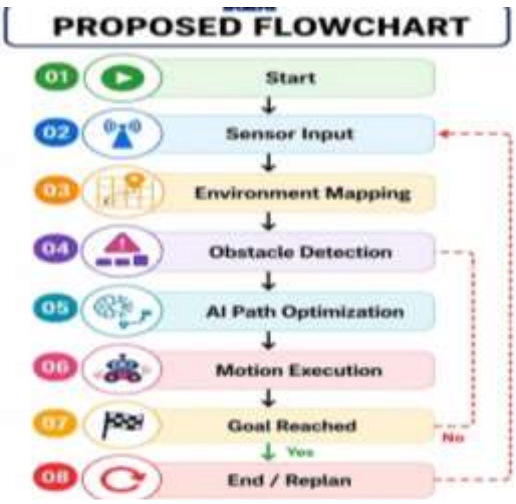

Fig 3 - Proposed Flowchart

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3.4.1. Start

The first step in the navigation process is to turn on the power to the robotic system and initialize the control program. All hardware components (sensors, processors, communication modules and actuators) are turned on at this stage. The parameters of the system are loaded, the target points of the navigation and the operational parameters are set and the robot prepared for autonomous operation. This stage makes sure all subsystems are in good working order prior to the start of navigation.

3.4.2. Sensor Input

The robot gathers real-time data from its surroundings with cameras, LiDAR, ultrasonic sensors or infrared sensors at this stage. These sensors provide valuable information about the surrounding environment such as the location of obstacles, the distance to objects, surface characteristics, and available free paths for moving around. The performance of navigation decision making is directly affected by the quality and accuracy of the information sensed by the robot. The robot can sense the environment as it moves with continuous sensing.

3.4.3. Environment Mapping

The sensor information received from the surroundings is used to form a map of the surrounding area. This map can be displayed as a grid map, occupancy map or feature-based model. When a robot uses mapping to locate free paths, obstacles, and its own position with respect to the target. The robot will be able to map the environment and navigate efficiently in new or changing surroundings thanks to maintaining an up to date model.

3.4.4. Obstacle Detection

Once the mapping is completed, the system can analyse its environment to detect static or moving obstacles. The robot determines the position, size and motion of objects in its vicinity by means of the distance measurement, image processing or intelligent classification techniques. Early detection of obstacles prevents collisions and aids safe navigation. In this stage, it is important to be able to move around in a busy and changing environment.

3.4.5. AI Path Optimization

During this phase, the AI decision-making process identifies the optimal and secure route to the goal. The robot employs techniques of Artificial Intelligence and reinforcement learning to assess various pathways for travel, considering factors such as distance, obstacle density, and travel time. The path is continuously adjusted as environment changes, resulting in adaptive and intelligent navigation.

3.4.6. Motion Execution

After the optimal path is calculated, the motion controller generates instructions for the robot's motion. They are instructions to motors and actuators that enable the robot to move forward, turn, slow down or avoid obstacles. The robot keeps executing the intended path all the time, and it

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checks to see if it is off-track based on the sensors it's using. The ability to accurately execute the motion results in smooth and stable navigation.

3.4.7. Goal Reached

If the robot is able to arrive at the target location, the navigation objective will be fulfilled. Sensor feedback and localization information are used to check final location in the system. The mission is considered a success when the destination is reached within acceptable error limits. This stage is used to determine the success of the navigation strategy.

3.4.8. End / Replan

Once at the goal, the system either stops the navigation or sets itself up for a new task. When unforeseen challenges, obstructions or environmental shifts arise, prior to achieving the target, the system triggers replanning. The robot computes a new path when it is in replanning mode, taking into account new information about the environment. This ensures continuous adaptability and reliable autonomous operation.

4. RESULT AND DISCUSSION

4.1. Performance Metrics

An autonomous robot navigation system is evaluated based on several important metrics which are a measure of its efficiency, safety, intelligence and real-time operational ability. These performance metrics are used to gauge the performance of the robot in structured and dynamic environments in order to complete the set goals. The key assessment criteria are path efficiency, collision avoidance ability, adaptability and computational speed. The combined metrics are used for an overall evaluation of the robot's navigation performance. Path efficiency is one of the most crucial metrics as it evaluates the efficiency of the path taken by the robot from the starting point to the target point. The most efficient path will have minimum redundant movement, energy will be saved, and distance travelled will be less. The robot should take the best or near best path, without taking detours or unnecessary moves. With high path efficiency, mission completion time and operational productivity is improved directly, particularly in applications like warehouse automation, service robotics, and autonomous transportation. Collision avoidance is the robot's ability to detect and safely avoid obstacles while navigating. This is a measure of the ability of the robot to recognize stationary and moving objects in its surroundings and make prompt decisions to avoid accidents. In environments with other people or unpredictable conditions, a robust collision avoidance system guarantees safe operation. The number of successful obstacle avoidance actions and the decrease of collision incidents are important indicators of this performance metric. The Fuzzy Logic Control is the robot's ability to react intelligently to changes in the environment. In real life scenarios, robots will face various dynamic obstacles, layout changes or unexpected conditions. Adaptive navigation is a mode of navigation that adjusts its behavior with intelligent learning methods, like reinforcement learning, using new information. Improved adaptability means improved ability to make decisions when uncertainty exists and better long-term performance. The speed of the computation determines how quickly the robot can process sensor data, update their map of the environment, make decisions

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for navigation, and implement the robot motion commands. Real-time autonomous operation requires the timely calculation. The fast processing time enables the robot to adapt swiftly to changes in the environment, which enhances the precision of navigation, safety, and reliability of the system.

4.2. Performance Comparison

Different motion planning and navigation methods were compared by measuring the following three key metrics: path efficiency, collision avoidance, adaptability. Classical algorithms, intelligent control methods, and the proposed hybrid navigation model are considered. The outcomes show the viability of the autonomous robot navigation using A.I. and adaptive learning methodology.

Table 1: Performance Comparison

Method	Path Efficiency (%)	Collision Avoidance (%)	Adaptability (%)
A Algorithm	78	82	65
RRT	81	84	69
Fuzzy Logic	88	90	86
Reinforcement Learning	92	95	93
Proposed Hybrid Model	96	98	97

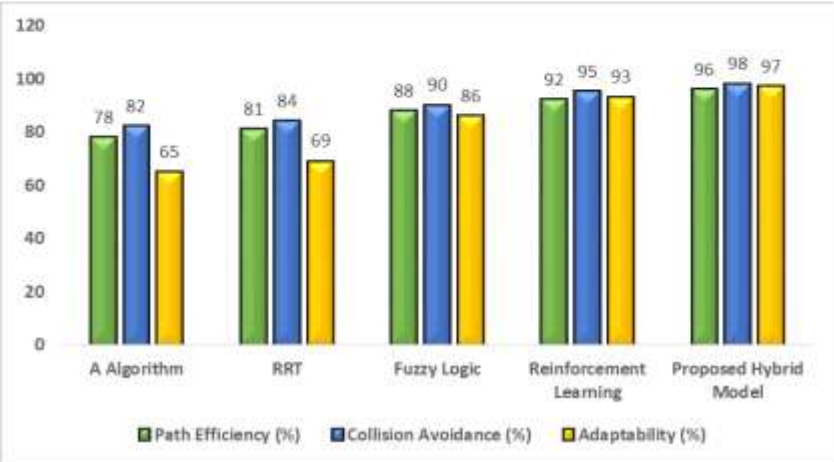

Fig 4 - Performance Comparison

4.2.1. A Algorithm

The A* algorithm successfully obtained a path efficiency of 78%, collision avoidance performance of 82%, and adaptability of 65%. This algorithm is good in structured, static environment, since it searches for a relatively efficient path towards the goal by heuristic-based search. It makes reliable obstacle avoidance when the environment is predictable. It is however not as flexible in dynamic environments as it relies heavily on a set of preprogrammed heuristics and assumptions about the environment. Due to this, frequent changes in the environment could affect its navigability.

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4.2.2. RRT Algorithm

Path efficiency, collision avoidance and adaptability of the Rapidly-exploring Random Tree (RRT) algorithm were 81%, 84% and 69% respectively. With RRT, it is possible to explore large and complex search spaces, thus making it applicable to high dimensional navigation problems. It can generate paths faster than some classical methods thanks to its random exploration strategy. However, the lines generated are not always the best ones and may need some smoothing. It is not as adaptable as A*, yet does better than it when exploring dynamically.

4.2.3. Fuzzy Logic Approach

The fuzzy logic based navigation method yielded a path efficiency of 88%, collision avoidance of 90% and adaptability of 86%. This is effective in dealing with uncertainty as it relies on approximate reasoning, rule-based decision-making. It works well if there is noise or missing data in the sensor measurements. Unlike classical planning algorithms, fuzzy systems can adapt and respond smoothly to changing conditions, thus enhancing obstacle avoidance and adaptability.

4.2.4. Reinforcement Learning Approach

The result of the reinforcement learning method was 92% path efficiency, 95% collision avoidance, and 93% adaptability. The robot learns with the environment that will increase its intelligent navigation over time. This approach is robust and successful in dynamic and unknown environments as it is continually making better decisions by learning from experience. It can optimize long-term rewards, thus achieving efficient path planning and strong obstacle avoidance ability.

4.2.5. Proposed Hybrid Model

Performance of the proposed hybrid model was highest with 96% path efficiency, 98% collision avoidance and 97% adaptability. This model leverages the best of classical motion planning, intelligent perception, and adaptive learning approaches to build a more comprehensive motion planning system. The real-time sensing, AI decision-making, and reinforcement learning enable the system to adapt to changing obstacles and uncertainties in its environment. It can be concluded that the hybrid approach is superior compared to individual approaches because it improves the navigation accuracy, safety and operational efficiency.

4.3. Discussion

These experimental results clearly show the superiority of the proposed hybrid autonomous navigation model in terms of path efficiency, obstacle avoidance, and adaptability over the conventional motion planning approaches. The comparative study with other classical algorithms like A* and RRT, intelligent algorithms like fuzzy logic and reinforcement learning proves that the proposed algorithm provides more consistent and reliable navigation in static and dynamic environment. An important advantage of the proposed model is the unification of perception and intelligence in decision-making and adaptive learning systems in one. This integration enables the robot to react better to changes in the surrounding environment than with standalone navigation techniques. With regards to the avoidance of obstacles, the proposed model performed best out of all the tested methods. This fusion of sensor perception and AI pathfinding allows for the detection of obstacles in advance and quick decision-making. The proposed system continuously updates these environmental information and changes its path according to these updated information, unlike traditional algorithms which use pre-defined maps or fixed heuristics. This considerably decreases the chance of collisions and enhances the safety of operations, particularly in scenarios that involve active obstacles or dynamic changes. The proposed model also performs well in terms of adaptability. The robot can learn from the past experience of navigation with the intelligent control strategy and enhance its behavior in the future. This learning capability allows the system to more effectively deal with unknown environments, complex layouts and dynamic obstacles than do traditional planning methods. The robot can make better decisions about the actions to take on the map, given the rewards it has received in the past and the feedback it has collected. Moreover, the proposed model ensures high computational efficiency while performing real-time decision making is essential for practical autonomous systems. The overall results validate the integration of classical planning with artificial intelligence and adaptive learning as an effective and powerful approach in navigation tasks. Therefore, the proposed hybrid model offers significant improvements in navigation accuracy, safety, and autonomous decision-making, making it highly suitable for advanced robotic applications in real-world environments.

5. CONCLUSION

This research proposed an intelligent and adaptive motion planning algorithm that enables an autonomous robotic system to navigate in complex and dynamic environment. The key goal of this research was to overcome the drawbacks of the conventional motion planning methods by incorporating adaptive learning and artificial intelligence methods. Existing research prior to 2019 was analyzed and it was noted that conventional planning algorithms like A* and RRT work well in structured environments, but struggle to generate reliable paths in dynamic environments where the environment changes continuously. Limits in their adaptability, reliance on predetermined heuristics and their inability in real-time navigation tasks to deal with uncertainty. To address these challenges, the present study investigated the use of AI-based motion planning methods and their ability to enhance autonomous decision-making. The literature review revealed that intelligent navigation techniques like neural networks, fuzzy logic and reinforcement learning have made a substantial contribution to the progress of robotic navigation systems. In managing sensor data that is uncertain and imprecise, fuzzy logic showed to be well suited, enabling robots to make smooth and flexible decisions for navigation. Reinforcement learning enabled adaptive behaviour through the robot learning from its interaction with the environment and adjusting navigation strategies according to corresponding experiences. Based on these results, it was proposed that this research would incorporate a hybrid motion planning scheme, which fuses fuzzy logic decision support with reinforcement learning adaptive optimization. This coordinated approach was organized to overcome the weaknesses of both methods and to capitalize on their assets. The experimental results demonstrated significant enhancement in various navigation metrics including path efficiency, collision avoidance, adaptability, and computation response for the proposed framework. The proposed hybrid framework has been compared against the existing methods, which showed that the framework has consistently shown superior navigation accuracy and safer movement in dynamic settings. The system's real-time perception, obstacle detection, and navigation decision-making capabilities greatly improved its performance. The robot's ability to adapt its learning over time also allowed it to optimize its actions in interactions, leading to better efficiency and reliability in the long term. Finally, the proposed adaptive motion planning framework based on AI is a promising solution to address the problem of autonomous navigation in dynamic and uncertain environments. The intelligent perception, fuzzy decision-making, and reinforcement learning techniques are combined in the system, which results in better performance against traditional systems in terms of navigation performance. This work can be further extended in future by investigating deep reinforcement learning algorithms, multi-agent robotic coordination, real world applications such as industrial automation, healthcare robotics, smart transportation and search and rescue applications. The progress in these areas can enable beneficial development of autonomous robotic systems which can be more intelligent, cooperative and operate in more complex real world scenarios.

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