

论文检索证明

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注: 本证明根据委托人提供的文献清单检索, 委托人已核对所述内容, 并确认无误。

1. Research on dynamic obstacle avoidance path planning strategy of AGV (Open Access)

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Authors: Miao, Zhenteng (1); Zhang, Xiaolei (1); Huang, Guojue (1)

Author affiliation: (1) Department of Robotics, Guangdong Country Garden Polytechnic, Guangdong, Qingyuan; 511510, China

Corresponding author: Miao, Zhenteng(miaozhenteng@bgypt.edu.cn)

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