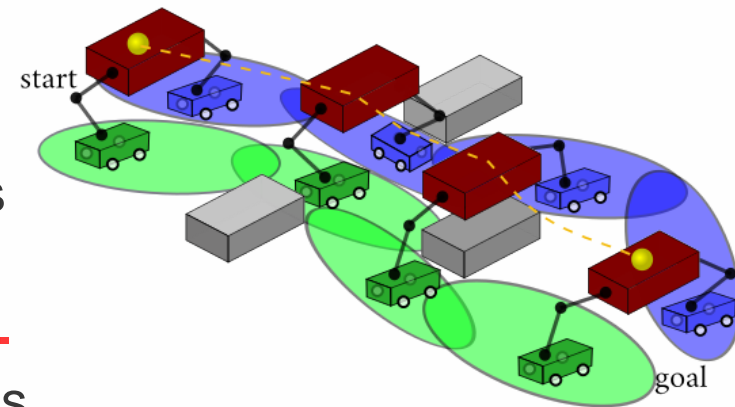


Task-Space Decomposed Motion Planning Framework for Multi-Robot Loco-Manipulation

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- Propose a **dual-resolution** motion planning framework for multi-robot simultaneous **locomotion and manipulation**.
- Compute and decompose **obstacle-free convex task spaces** for the different subsets of the configuration space.
- Introduce a global planner to explore the **low-dimensional** decomposed task-space regions.
- Introduce a local planner to compute a path in **high-dimensional** constrained configuration space.



A path for multi-robot loco-manipulation utilizing decomposed task-space