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## Imparting protean behavior to mobile robots accomplishing patrolling tasks in the presence of adversaries

By: Curiac, DI (Curiac, Daniel-Ioan)<sup>[1]</sup>; Volosencu, C (Volosencu, Constantin)<sup>[1]</sup>[View ResearcherID and ORCID](#)

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s. In order to solve this problem we developed an zig-zag movement. The proposed bio-inspired changes without jeopardizing the robot's mission. Such a alignment and sight picture. This idea is in the robot's field of view, deceiving the obstacle hold's cat map to obtain the timely random s confirmed through an extensive simulation case

ity; fictive-temporary obstacle; Arnold's cat map

, Romania.

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